

## **Drives and Motion Accelerator Toolkit**





## **Important User Information**

Read this document and the documents listed in the additional resources section about installation, configuration, and operation of this equipment before you install, configure, operate, or maintain this product. Users are required to familiarize themselves with installation and wiring instructions in addition to requirements of all applicable codes, laws, and standards.

Activities including installation, adjustments, putting into service, use, assembly, disassembly, and maintenance are required to be carried out by suitably trained personnel in accordance with applicable code of practice.

If this equipment is used in a manner not specified by the manufacturer, the protection provided by the equipment may be impaired.

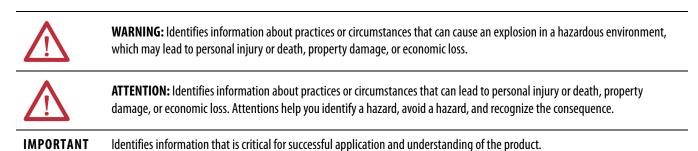
In no event will Rockwell Automation, Inc. be responsible or liable for indirect or consequential damages resulting from the use or application of this equipment.

The examples and diagrams in this manual are included solely for illustrative purposes. Because of the many variables and requirements associated with any particular installation, Rockwell Automation, Inc. cannot assume responsibility or liability for actual use based on the examples and diagrams.

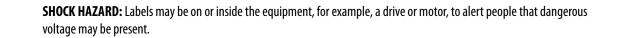
No patent liability is assumed by Rockwell Automation, Inc. with respect to use of information, circuits, equipment, or software described in this manual.

Reproduction of the contents of this manual, in whole or in part, without written permission of Rockwell Automation, Inc., is prohibited.

Throughout this manual, when necessary, we use notes to make you aware of safety considerations.



Labels may also be on or inside the equipment to provide specific precautions.



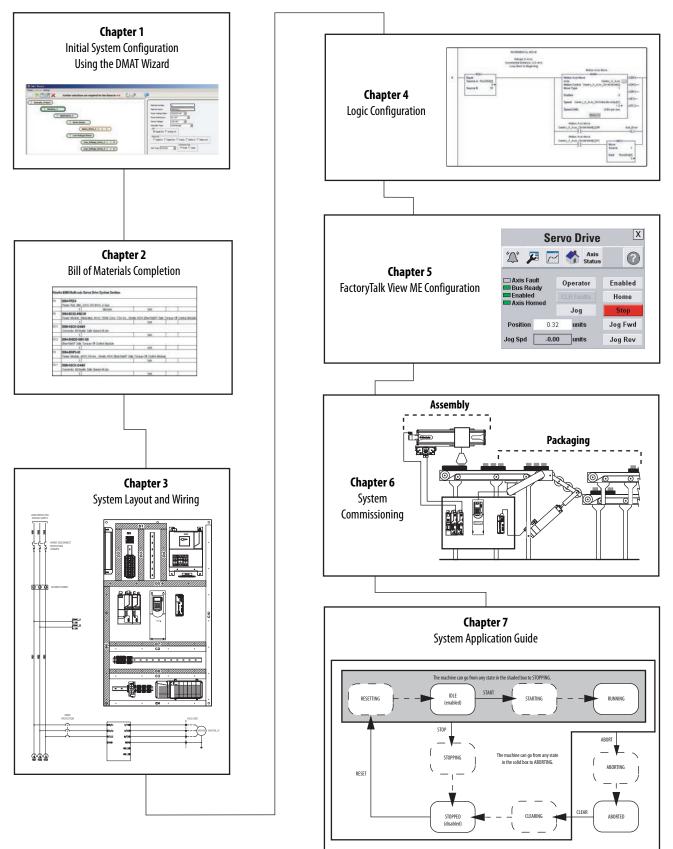


**BURN HAZARD:** Labels may be on or inside the equipment, for example, a drive or motor, to alert people that surfaces may reach dangerous temperatures.



**ARC FLASH HAZARD:** Labels may be on or inside the equipment, for example, a motor control center, to alert people to potential Arc Flash. Arc Flash will cause severe injury or death. Wear proper Personal Protective Equipment (PPE). Follow ALL Regulatory requirements for safe work practices and for Personal Protective Equipment (PPE).

Allen-Bradley, ArmorStart, CenterONE, CompactLogix, ControlFLASH, ControlLogix, CrossWorks, DPI, DriveExplorer, DriveTools, E3, E3 Plus, E300, Explorer, FactoryTalk, GuardLogix, HPK-Series, Integrated Architecture, Kinetix, LDC-Series, LDL-Series, Logix5000, MCS, MP-Series, PanelView, PowerFlex, ProposalWorks, RailBuilder, RDD-Series, Rockwell Automation, Rockwell Software, RSLogix, RSLinx, SCANport, SMC, Stratix, Studio 5000 Logix Designer, Studio 5000, TL-Series, and Ultra are trademarks of Rockwell Automation, Inc. Follow this path to complete your Drives and Motion application.



### Notes:

This manual contains new and updated information.

## New and Updated Information

This table contains the changes made to this revision.

Topic	Page
Added user manual references for E300 <sup>™</sup> overload relays and ArmorStart <sup>®</sup> distributed motor controllers	15
Updated Motion Analyzer Software with online dialog boxes	23
Added PowerFlex 527 drives, E300 relays, and ArmorStart motor controllers to Faceplate Displays table	109, 117
Added Kinetix 5500 and PowerFlex 527 to Commissioning CIP Motion Drives	157
Added Commissioning E300 Electronic Overload Relays	170
Added Commissioning ArmorStart LT Distributed Motor Controllers	174
Added Commissioning ArmorStart Distributed Motor Controllers	176
Added E300 Overload Relay Faceplates	208
Added ArmorStart Distributed Motor Controller Faceplates	216
Added E300 overload relays and ArmorStart distributed motor controllers to Module Routine Overview	227
Added PowerFlex 527 to Configure CIP Motion Drive Modules	315
Added E300 Overload Relay Configuration	345
Added ArmorStart Distributed Motor Controller Configuration	352
Added Import and Configure E300 Device Modules	380
Added Import and Configure ArmorStart Distributed Motor Controller Device Modules	387

## Notes:

### Preface

About This Publication	13
Conventions	14
Required Software	14
Additional Resources	15

### **Chapter 1**

Before You Begin 18
What You Need         18
Follow These Steps 18
Review the DMAT Wizard 19
Simple System and Drive Configuration Entries
Bill of Material Output 19
System Drawing Set Output 20
Project File Output 21
FactoryTalk View Me Project File Output
Review Other System Selection and Configuration Tools 23
Motion Analyzer Software 23
Engineering Assistant Software 24
Product Selection Toolbox 25
Install Other System Selection and Configuration Tools 26
Motion Analyzer Software 26
Install Engineering Assistant Software
Install Product Selection Toolbox 27
Run the DMAT Wizard 28
Launch the DMAT Wizard 28
Edit the DMAT Wizard Configuration 31

### Chapter 2

Before You Begin	37
What You Need	37
Follow These Steps	38
Import the Initial Project BOM File	38
Edit Your Project BOM File	40

#### Chapter 3

Before You Begin48What You Need48Follow These Steps49Create a New Project50Edit Power Drawings51Edit Drive, Controller, and Safety I/O Drawings56Edit System Communication Drawings61Edit System Layout Drawings62

# Initial System Configuration Using the DMAT Wizard

### **Bill of Materials Completion**

**System Layout and Wiring** 

Logic Configuration

# FactoryTalk View ME Configuration

## Chapter 4

## Chapter 5

Before You Begin 103
What You Need 103
Follow These Steps 104
Design From a Preconfigured HMI Application File 104
Open Factory Talk View ME Configuration Guide 105
Restore and Open a Preconfigured HMI Application 106
Delete Unused Displays 108
Delete Unused Parameter Files
Configure Parameter Files 111
Delete Unused Alarm Triggers and Tags 115
Design From an Existing HMI Application File 117
Open Your Existing HMI Application File and Add Displays 117
Add Parameter Files 121
Configure Parameter Files 123
Import Alarm Setup File 127
Delete Unused Alarm Triggers 129
Import and Edit Alarm Tags 130
Configure Goto Display Buttons on Startup Display 133
Configure Equipment Status Faceplate Display
Add the Equipment Status Faceplate Display
Add the ME_Equipment_Parameter File 140
Configure Goto Buttons on the Equipment Status Faceplate 142
Configure Additional Device Value Columns
Configure Equipment Status Faceplate for Energy Monitoring 145

## Chapter 6

Before You Begin	149
What You Need	149
Follow These Steps	150
Download Applications	150
Download Logix Designer Project	150
Configure and Download FactoryTalk Project to	
PanelView Plus Terminal	152
Commissioning Devices	157
Commissioning CIP Motion Drives	157
Commissioning Sercos Drives	162
Commissioning PowerFlex 7-class Drives	163
Commissioning PowerFlex 5-class Drives	165
Commissioning PowerFlex 4-class Drives	166
Commissioning Kinetix 300 Drives	167
Commissioning E3 Plus Overload Relays	168
Commissioning E300 Electronic Overload Relays	170
Commissioning SMC-50 Soft Starter Modules	173
Commissioning ArmorStart LT Distributed Motor Controllers.	174
Commissioning ArmorStart Distributed Motor Controllers	176
Commissioning Drives and Motion Systems	179
Verify Network Communication	179
Clearing Faults	180
Operator (manual) Control	181
Program (automatic) Control	181

## Chapter 7

Before You Begin 183
What You Need 183
Follow These Steps 184
Machine Startup Faceplate
Machine Status
Machine Control 187
Program/Operator Mode 187
State Diagram Faceplate Display 188
Motion Drives Faceplates
Home View
Axis Status Views 190
Axis Control Views
Fault Indication View.193
Fault Diagnostic Views 194
Configuration View 195
Trend Views 195
PowerFlex Drives Faceplates 197
Home View
Control View

System Application Guide

System Commissioning

Fault Indication View	198
Fault Diagnostic Views	
Configuration Views	199
Trend Views	201
Energy Status Views	203
Online Help Views	204
E3 Plus Overload Relay Faceplates	204
Home/Control View	204
Fault Indication View	205
Fault Diagnostic Views	206
Configuration View	207
Online Help Views	207
Energy Status Views	208
E300 Overload Relay Faceplates	208
Home/Control View	
Fault Indication View	210
Fault Diagnostic Views	
Configuration View	211
Online Help Views	211
Trend View	
Energy Status View	
SMC-50 Soft Starter Faceplates.	
Home/Control View	213
Fault Indication View	
Fault Diagnostic Views	
Configuration View	215
Online Help Views	215
Energy Status Views	
ArmorStart Distributed Motor Controller Faceplates	
Home View	
Control View	
Fault Indication View	
Fault Diagnostic Views	
Configuration Views	
Trend Views	
Online Help Views	
Equipment Status Display Overview	
Equipment Status Display for Energy Overview	
Alarm History Display Overview	223

## Appendix A

Machine/Application/Device Module Relationship	226
Module Routine Overview	227
Machine Module	230
Machine States	230
Machine Control Module Tags	232
Device and Application Status Rung Tags and Logic	233

## Logic Program Overview

	Application Modules236Device Modules237Device Module Tags237Device Module Control Logic Example239
Logic Module Customization	Machine State Customization241Tag and Logic Modification Recommendations244State Display Tag Modifications245Bypass Idle State Modifications246Module Fault Customization247Alarm History Faceplate Logic Modification249
	Coordinated Reset Customization 250
Add Other Devices to the Equipment Status Faceplate	Appendix CAdd Devices to the Equipment Status FaceplateAdd Optional Faceplate Views254
	Appendix D
Logix Designer Communication and Controller Configuration	Configure Personal Computer Communication Properties257Configure the EtherNet/IP Driver259Configure the Logix5000 Controller260
	Appendix E
Create and Add BOM Device Modules Without the DMAT Wizard	Before You Begin267What You Need267Follow These Steps268Select Initial BOM Files268Add BOM Device Modules270
	Appendix F
Assemble Project Drawing Set Without the DMAT Wizard	Before You Begin277What You Need277Follow These Steps278

Select Drive Power Drawings.279Select Controller Power Drawings.281Select External Safety Relay Option Drawings.282Select Drive I/O Drawings.283Select Controller I/O Drawings.284Select System Communication Drawings.286Select System Layout Drawings.287Select Power and Control Component Layout Footprint Drawings.289

Controller, Network, and Device Configuration Without the DMAT Wizard

## Appendix G

Before You Begin	291
What You Need.	291
Follow These Steps	292
Controller and Network Configuration	293
Create a New Project File	293
Configure the Ethernet Module	295
Configure the Sercos Module	
Save the Project File	298
Device Configuration	299
PowerFlex Drive Configuration	299
Update PowerFlex Add-On Profiles	300
PowerFlex 525 Add-On Profiles	302
Add and Configure PowerFlex Drives	303
Set PowerFlex Drive Parameters	
Download Drive Parameters	312
CIP Motion Drive Configuration	315
Configure CIP Motion Drive Modules	
Configure the Motion Group	
Configure Axis Properties	
Sercos Motion Drive Configuration	
Configure Sercos Drive Modules	
Configure the Motion Group	
Configure Axis Properties	
Kinetix 300 Drive Configuration	
Update Kinetix 300 Add-On Profiles	
Add Kinetix 300 Drives to Your Logix Designer Project	
Configure Kinetix 300 Drives.	
E3 Plus Overload Relay with Communication Auxiliary	
Configuration	343
Update E3 Plus Add-On Profiles	343
Add E3 Plus Devices to Your Logix Designer Project	
E300 Overload Relay Configuration	
Update E300 Add-On Profiles	345
Add E300 Devices to Your Logix Designer Project	
SMC-50 Soft Starter Configuration.	
Update SMC-50 Add-On Profiles	347
Add SMC-50 Devices to Your Logix Designer Project	348
Download Soft Starter Parameters	
ArmorStart Distributed Motor Controller Configuration	352
Update ArmorStart Add-On Profiles	352
Add ArmorStart Devices to Your Logix Designer Project	352
Import and Configure Logic Modules	
Import and Configure the Machine Logic Module	
Import and Configure Application Logic Modules	
Import and Configure Device Logic Modules	

## **About This Publication**

This quick start provides step by step instructions for using the Drives and Motion Accelerator Toolkit to help you design, install, operate, and maintain a drive system. Included are selection tools, layout and wiring drawings, and pre-configured logic and HMI files to assist you in creating an Integrated Architecture<sup>™</sup> solution for your application requirements.

The instructions also show how the Drives and Motion Accelerator Toolkit (DMAT) Wizard can automate the tasks needed to build the files used in the Integrated Architecture solution.

All of the supporting files are included on the Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>, including the DMAT Wizard. The DVD provides drive selection tools; CAD drawings for panel layout and wiring; basic status, control, and diagnostic logic files; FactoryTalk<sup>®</sup> View ME and SE faceplates, and more. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative. With these tools and the built-in best-practices design, the system designer is free to focus on the design of their machine control and not on design overhead tasks.

You can also download these same supporting files from the Rockwell Automation<sup>®</sup> Integrated Architecture Tools website, <u>http://www.ab.com/go/iatools</u> on the Beyond Getting Started tab.

**IMPORTANT** Before using this quick start and the contents of the Drives and Motion Accelerator Toolkit DVD, read the Terms and Conditions READ ME.pdf on the DVD.

The beginning of each chapter contains the following information. Read these sections carefully before beginning work in each chapter.

- **Before You Begin** This section lists the steps that must be completed and decisions that must be made before starting that chapter. The chapters in this quick start do not have to be completed in the order in which they appear, but this section defines the minimum amount of preparation required before completing the current chapter.
- What You Need This section lists the tools that are required to complete the steps in the current chapter. This includes, but is not limited to, hardware and software.
- Follow These Steps This illustrates the steps in the current chapter and identifies which steps are required to complete the examples using specific networks.

## Conventions

Convention	Meaning	Example
CIP Motion	Used as an abbreviation for Integrated Motion on the EtherNet/IP network. This term describes Rockwell Automation servo drives and high-power AC drives that use CIP Motion and CIP Sync technology from ODVA, all built on the Common Industrial Protocol (CIP) communicating over the EtherNet/IP network. Two drive platforms that apply are Kinetix® 6500 servo drives and PowerFlex® 755 AC drives when used on the EtherNet/IP network.	CIP Motion Drive Configuration
Click	Click left mouse button once (assumes cursor is positioned on object or selection). Click button to initiate action.	Click Browse.
Double-click	Click left mouse button twice in quick succession (assumes cursor is positioned on object or selection).	Double-click the H1 icon.
Right-click	Click right mouse button once (assumes cursor is positioned on object or selection).	Right-click the Fieldbus Networks icon.
Drag and drop	Click and hold the left mouse button on an object, move the cursor to where you want to move the object, and release the mouse button.	Drag and drop the desired block into the Strategy dialog box.
Select	Click to highlight a menu item or list choice.	From the pull-down menu, choose H1-1.
Check/uncheck	Click to select a checkbox option.	Check Consider Case if you want to conduct a case-sensitive search.
>	Shows nested menu selections as menu name followed by menu selection.	Click File>Page Setup>Options.
Expand	Click the + to the left of a given item /folder to show its contents.	In the H1-1 dialog box, expand FFLD.
Enter	Used when you can type from the keyboard or choose from a list.	Enter the catalog number of the product.
Туре	Used when the only option is to type from the keyboard.	Type the catalog number of the product.
Press	Press a specific button on the PanelView <sup>™</sup> terminal or other component with touch-screen technology.	Press Axis Control.

## **Required Software**

Rockwell Automation Software	Cat. No.	Version	Required For
Studio 5000 Logix Designer® application		21.00 or later <sup>(1)</sup>	
RSLogix™ 5000 • ControlFLASH™ • BOOTP/DHCP utility (EtherNet/IP) • RSLinx® Classic	9324-RLD300 <i>xx</i> E	19.00 or later <sup>(2)</sup>	All Kinetix and PowerFlex drive applications
FactoryTalk View Studio for Machine Edition <ul> <li>FactoryTalk Services</li> <li>RSLinx Enterprise</li> <li>RSLinx Classic</li> </ul>	9701-VWSTMENE	5.1 or later	PanelView Plus terminals
Motion Analyzer	Rockwell Automation Configuration and Selection Tools	5.2 or later	Drive/motor sizing
ProposalWorks™	website <a href="http://www.rockwellautomation.com/en/e-tools">http://www.rockwellautomation.com/en/e-tools</a> or ask your Rockwell Automation sales representative for the Product Selection Toolbox DVD	7.5 or later	Bill of materials development
Drives and Motion Accelerator Toolkit DVD	IASIMP-SP017	N/A	CAD files, wiring diagrams, application files, and other support information

(1) When PowerFlex 527 drives are used, version 24.00 or later is required.

(2) When Kinetix 350 servo drives are used, version 20.00 or later is required.

## **Additional Resources**

These documents contain additional information concerning related products from Rockwell Automation.

Resource	Description		
PowerFlex 4 Adjustable Frequency Drive User Manual, publication 22A-UM001			
PowerFlex 40 Adjustable Frequency Drive User Manual, publication 22B-UM001			
PowerFlex 40P Adjustable Frequency Drive User Manual, publication 22D-UM001	Provides mounting and wiring instructions for PowerFlex 4-class AC drives. Also provides information on how to set drive parameters and troubleshoot the drive.		
PowerFlex 70 and 70EC Adjustable Frequency Drive User Manual, publication 20A-UM001			
PowerFlex 400 Adjustable Frequency Drive User Manual, publication 22C-UM001			
PowerFlex 525 Adjustable Frequency AC Drive User Manual, publication 520-UM001	Provides mounting and wiring instructions for PowerFlex 525 AC drives.		
PowerFlex 527 Adjustable Frequency AC Drive User Manual, publication 520-UM002	Provides mounting and wiring instructions for PowerFlex 527 AC drives.		
PowerFlex 700 Adjustable Frequency Drive User Manual, publication 20B-UM001			
PowerFlex 700H Adjustable Frequency Drive User Manual, publication 20C-PM001			
PowerFlex 700S High Performance Drive, Phase II User Manual, publication 20D-UM006	Provides mounting and wiring instructions for PowerFlex 7-class AC drives. Also pro		
PowerFlex 700S High Performance Drive, Phase I User Manual, publication 20D-UM001	information on how to set drive parameters and troubleshoot the drive.		
PowerFlex 700 Vector Controlled AC Drives User Manual, publication 20B-UM002			
PowerFlex 750-Series AC Drives Installation Instructions, publication 750-IN001			
PowerFlex Family Selection Guide, publication <u>PFLEX-SG002</u>	Provides drive specifications for the PowerFlex 4-class, 5-class, and 7-class AC drive products.		
PowerFlex 70 EtherNet/IP Adapter User Manual, publication 20C0MM-UM010			
PowerFlex 70 DeviceNet Adapter User Manual, publication 20C0MM-UM002	Provides details on how to install, configure, and use the adapter.		
PowerFlex 525 Embedded EtherNet/IP Adapter User Manual, publication <u>520COM-UM001</u>			
Kinetix 300 EtherNet/IP Indexing Drives User Manual, publication 2097-UM001			
Kinetix 350 Single-axis EtherNet/IP Drives User Manual, publication 2097-UM002			
Kinetix 6200 and Kinetix 6500 Modular Multi-axis Servo Drives User Manual, publication 2094-UM002	Provides mounting, wiring, configuring, and troubleshooting instructions for the Kinetix		
Kinetix 6000 Multi-axis Servo Drives User Manual, publication 2094-UM001	Motion Control servo drives.		
Kinetix 6000M Integrated Drive-Motor System User Manual, publication 2094-UM003			
Kinetix 2000 Multi-axis Servo Drives User Manual, publication 2093-UM001			
Kinetix 7000 Multi-axis Servo Drives User Manual, publication 2099-UM001			
Ultra™3000 Digital Servo Drives Installation Manual, publication <u>2098-IN003</u>	Provides mounting and wiring instructions for Ultra3000 digital servo drives.		
Ultra3000 Digital Servo Drives Integration Manual, publication 2098-IN005	Provides configuring and troubleshooting instructions for the Ultra3000 digital servo drives.		
Kinetix Motion Control Selection Guide, publication <u>GMC-SG001</u>	Overview of Kinetix servo drives, motors, actuators, and motion accessories designed to help make initial decisions for the motion control products best suited for your system requirements.		
Kinetix Rotary Motion Specifications, publication GMC-TD001	Product specifications for MP-Series™ (Bulletin MPL, MPM, MPF, MPS), Kinetix 6000M (Bulletin MDF), TL-Series™, RDD-Series™, and HPK-Series™ rotary motors.		
Kinetix Linear Motion Specifications, publication <u>GMC-TD002</u>	Product specifications for Bulletin MPAS and MPMA linear stages, Bulletin MPAR, MPAI, and TLAR electric cylinders, and LDC-Series <sup>™</sup> and LDL-Series <sup>™</sup> linear motors.		
Kinetix Servo Drives Specifications, publication <u>GMC-TD003</u>	Product specifications for Kinetix Integrated Motion over the EtherNet/IP network, Integrated Motion over sercos interface, EtherNet/IP networking, and component servo drive families.		
Kinetix Motion Accessories Specifications, publication <u>GMC-TD004</u>	Product specifications for Bulletin 2090 motor and interface cables, low-profile connector kits, drive power components, and other servo drive accessory items.		

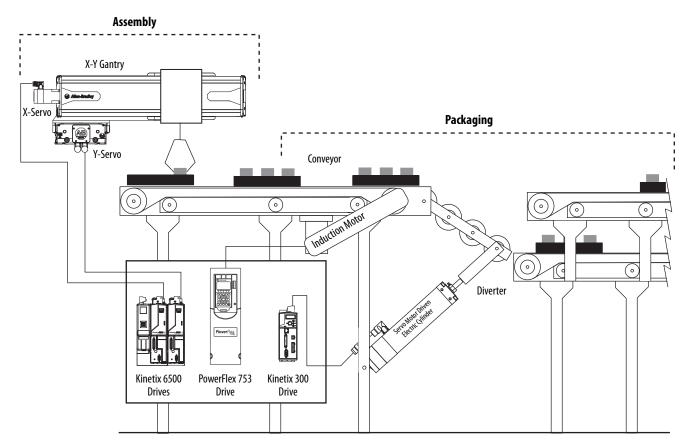
Resource	Description
Kinetix 6000 and Kinetix 6200/6500 Drive Systems Design Guide, publication GMC-RM003	
Kinetix 300 and Kinetix 350 Drive Systems Design Guide, publication GMC-RM004	System design guide to determine and select the required (drive specific) drive module, power accessory, connector kit, motor cable, and interface cable catalog numbers for
Kinetix 2000 Drive Systems Design Guide, publication GMC-RM006	your drive and motor/actuator motion control system. Included are system performance
Kinetix 7000 Drive Systems Design Guide, publication <u>GMC-RM007</u>	specifications and torque/speed curves (rotary motion) and force/velocity curves (linear motion) for your motion application.
Ultra3000 Drive Systems Design Guide, publication GMC-RM008	
E3 <sup>™</sup> and E3 Plus <sup>™</sup> Solid-state Overload Relay User Manual, publication <u>193-UM002</u> .	Provides mounting and installation instructions for E3 and E3 Plus overload relays and
EtherNet/IP Communications Auxiliary User Manual, <u>193-UM014</u>	Bulletin 193 EtherNet/IP communication auxiliary modules.
E300 Electronic Overload Relay User Manual, publication <u>193-UM015</u>	Provides mounting, wiring, configuring, and troubleshooting instructions for E300 (Bulletin 193/592) electronic overload relays.
SMC <sup>™</sup> -50 Solid-state Smart Motor Controller User Manual, publication <u>150-UM011</u> .	Provides mounting and installation instructions for SMC-50 soft-starter modules.
ArmorStart LT Distributed Motor Controller User Manual, publication 290E-UM001	Provider installation and wiring instructions for the ArmorStart motor controllors. Also
ArmorStart Distributed Motor Controller with EtherNet/IP User Manual, publication 280E-UM001	Provides installation and wiring instructions for the ArmorStart motor controllers. Also provides information on how to set parameters and troubleshoot the device.
Sercos and Analog Motion Configuration and Startup User Manual, publication <u>MOTION-UM001</u>	Information on configuring and troubleshooting your ControlLogix <sup>®</sup> and CompactLogix <sup>™</sup> sercos interface modules.
Motion Coordinate System User Manual, publication MOTION-UM002	Information to create a motion coordinate system with sercos or analog motion modules.
Integrated Motion on the Ethernet/IP Network Configuration and Startup User Manual, publication MOTION-UM003	Information on configuring and troubleshooting your ControlLogix and CompactLogix EtherNet/IP network modules.
Integrated Motion on the Ethernet/IP Network Reference Manual, publication MOTION-RM003	Provides descriptions of the AXIS_CIP_DRIVE attributes and Logix Designer application Control Modes and Methods.

You can view or download publications at <u>http://www.rockwellautomation.com/literature</u>. To order paper copies of technical documentation, contact your local Allen-Bradley distributor or Rockwell Automation sales representative.

## Initial System Configuration Using the DMAT Wizard

In this chapter you use the Drives and Motion Accelerator Toolkit (DMAT) Wizard to create an initial bill of materials, assemble a system drawing set, and create a Studio 5000 Logix Designer project file with a preconfigured controller, network, drives and initial system program logic. In addition, you are introduced to several Rockwell Automation system configuration tools that provide assistance in sizing your motor/drive combinations for a variety of load, transmission, and application types.

To assist you in architecture and hardware selection, the Widg-O-matic machine application is referenced in the selection steps. Hardware selection includes all power and control equipment to support two servo drives for the X-Y gantry, one PowerFlex drive for the conveyor, and one Kinetix 300 drive for the packaging diverter.



#### Widg-O-matic Machine Application Example

## **Before You Begin**

Collect specific application data, for example:

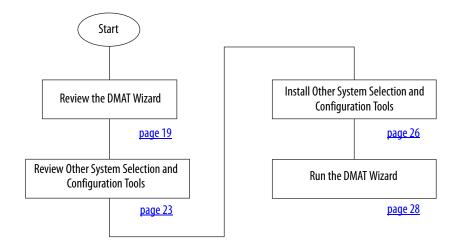
- System Input Voltage
- Ambient temperature and Altitude Specifications
- Transmission Type
- Motor data
- Load Data Inertia and Cycle Profiles
- Other System Sizing Info

## What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication<u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative.
- PowerFlex Family Selection Guide, publication <u>PFLEX-SG002</u>.
- Kinetix Motion Control Selection Guide, publication <u>GMC-SG001</u>.

## **Follow These Steps**

Complete the following steps to create a bill of materials and size your drives and motion system components.



## **Review the DMAT Wizard**

Once you have a general idea of the overall control architecture, relative size, and type of the drives in your system, you can use the DMAT Wizard to create a bill of material, assemble a system drawing set, and create a Logix Designer application project file with a preconfigured controller, network, drives, and initial system program logic. This can be accomplished in minutes by inserting simple system and drive configuration entries and running other system selection tools as needed.

#### RA DMAT Wizard File Edit Tools Help RA DMAT Wizard ) 🛷 🖹 🗹 🌾 C Generate X 24 <u>Eile Edit Tools Help</u> Example\_Project 🗋 🝠 💾 🛃 🏈 X C) Generate 🔺 🌼 Machine\_1 Example\_Project X Application\_1 Drive Name Low\_Voltage 🔺 🏶 Machine\_1 Motor Control Drive Type: PF4 Application\_1 Low Voltage Drives Output Current: 1.5 Motor Control SERCOS Servo Drives Comms: Ethernet Low Voltage Drives ٠ CIP Motion Drives Low\_Voltage\_Drive\_1 EtherNet/IP Indexing Servo Drives SERCOS Servo Drives ÷ On Machine SERCOS\_Servo\_Drive\_1 Soft Starters RA DMAT Wizard Starters with Electronic <u>File Edit Tools Help</u> 🗋 🛷 🖹 🗹 🌾 h X 24 C) Generate Example\_Project Drive Name SERCOS\_Servo\_Drive\_1 ▲ 🏶 Machine\_1 Drive Type: K6000 X Application\_1 IAM or AM: IAM Motor Control Axis Configuration Velocity Loo Low Voltage Drives ٠ IAM Selection Low\_Voltage\_Drive\_1 Spare Slot Count Inverter Current Rating: 5 A SERCOS Servo Drives ٠ Converter Power Rating: 3 kW SERCOS\_Servo\_Drive\_1 Shunt Module: CIP Motion Drives ٠ Slot Count

## **Simple System and Drive Configuration Entries**

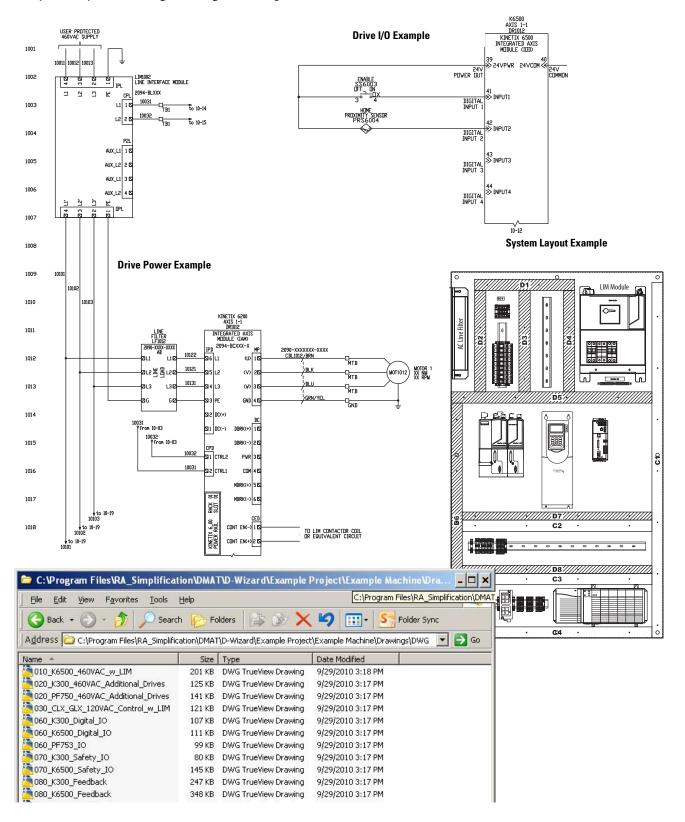
## **Bill of Material Output**

The initial BOM files include power and control distribution equipment, control circuit protection, operator devices, and system drives and accessories.

1155 Sprint Column, Deff. Sprint Hall, Strate TAM, Sprint Hall, Strate Hall, Sprin Hall, Strate Hall, Sprint Hall, Strate Hall, Sprin	Bern 7	DeviD Oty Typical Delivery Wit don DS POC Net Only List Ea		
Visit Sparse Construct, Radi, Darpet Hall, Richeler, Radi, Sarpet Hall, Richeler, Richer, Radi, Sarpet Hall,	ervo Drive	- Garity_X	Tall CMAT P Export List ME bs • yopy Agreement Platests Vew Sed • Parted Decort Cetal	
2         Interview         No.         (3)         (4)	0		tem / DeviD Oth Typical Delivery Mt dbs) DS POC Net Only List Ea Set Each Ext The DMAT F Export List mt to	Spply Agreemen Patresh View Sell
New Mask. Negrad. Mov. dl. 2007. MAN.         120         1784-A1         1394-A2         1392-A1         <	_		Controller and Hill Parts	et Only List Ea Set Each End Net (USD
Distriction         Distriction <thdistriction< th=""> <thdistriction< th=""></thdistriction<></thdistriction<>		Power Module, Integrated, 460V, 6kW Conv. 3A Inv.,		
Image: Dist Dist Dist Dist Dist Dist Dist Dist				
Image: New Gene Gardina Status         1         Printerest         Name         500         \$ 4,000.10         100000         \$ 1,000.00         \$ 1,0		Power Rail, Sim, 220V OR 460V, 2 Avis	24 1756-ENDTR 1555 ETHE CAMP, 3 Conductors, R.MS, Shadort Ma	
N 2000 FPA Displant hybrined/AD Product Network File Dismost, Net	2	MPL-8540D-SJ72AA	1 Preferred N/A [05 530 \$4,050.10 1,0000 \$4,050.10 1 40 23548C01480148	\$51.51 1.0000 \$51.51 \$103.0
29HoCPVH070-f44481         55/26 V/AC Prem Early 12 Pres 0 PO/ To 1 Prefered         1         No.		in.), 2000 RPM, Single-turn High-resolution Encoder. Keyed Shaft Extension, Speed	16 Avis SERCOS Servo Module 11 Preferred N/A H1 738	\$1,807.90 1.0000 \$1,807.90 \$1,807.9
INSE Press Ore, Source: Diverse: D				
I         Perform         NA         ICI 241         \$11372         ICI 244         \$11372           299-CENDRO* CEAAB         500 CENDRO* CEABB				\$ 297.95 1 0000 \$ 297.95 \$ 297.9
Matr Freddo Orb, Sovertiz, DN Jonnetz, Drivensen, Drivensen, Strevensen, Streve	_	1 Preferred N/A H2 744 \$113.12	27 1756-42 Ib.deth MPL - Low-Inertia Brushess Servo Matters Prod	
1         Preferred         NA         [42]         244         4 100         235           2039 AGCK-01041         Directive Mark Feedback, D-thet/Tem Block, 15-Inv         1         NA         981         722         \$ 2,510,000         10000         \$ 2,210         00000 <td></td> <td></td> <td></td> <td>Hybel bhat Extension, speed FEC DIN Connector, Hight Angle, 110° Hotatable Hotes (Type FF)</td>				Hybel bhat Extension, speed FEC DIN Connector, Hight Angle, 110° Hotatable Hotes (Type FF)
Connector Mater Feedback, D-State/Feen Book, 15 Prv. 11 Preferred N/A 05 530 \$11,100,00 10000 \$11,100,00 \$ Mater Feedback, D-State/Feen Book, 15 Prv.	_	1 Preferred N.M. H2 244 \$ 104.03		\$2,510.00 1,0000 \$2,510.00 \$2,510.0
			1 Preferred N/A D5 530 \$11,100.00 \$11,100.00 \$ Mater Power Only, Speedfec DIN Connector, Drive en	
1 Prierred N/A H2 731 \$59.59 29 \$2440.0000 + 10 10 10 10 10 10 10 10 10 10 10 10 10			29 \$324-FLD306ENE 1 Preferred N/A H2 744	\$113.12 1.0000 \$113.12 \$113.1

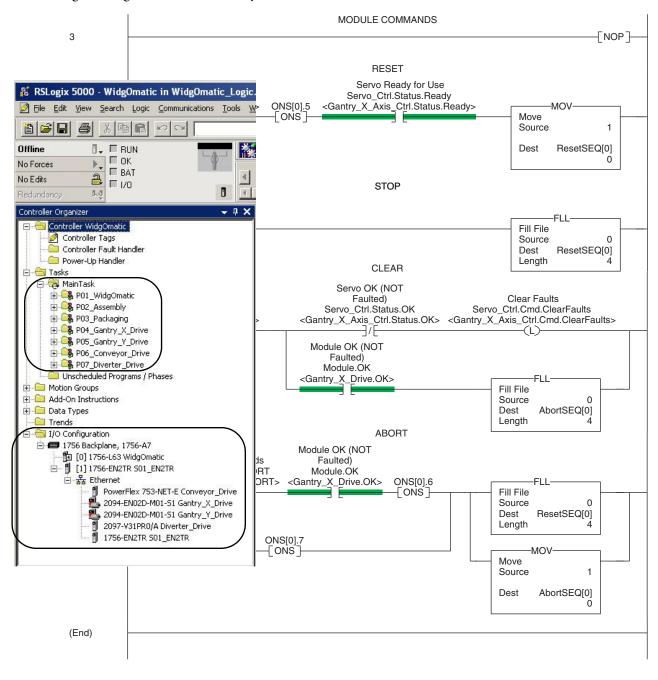
### System Drawing Set Output

The assembled system drawing set includes power distribution, drive power and control wiring, communication, and system layout drawings in .dwg, .dxf, or .pdf formats.



### **Project File Output**

The project file includes preconfigured controller, drives, network, and machine/application/ device program logic providing an integrated logic architecture to add your specific application logic to. The preconfigured file saves hours in logic configuration and assembly.



### FactoryTalk View Me Project File Output

The FactoryTalk View Me ConfigurationGuide folder contains two files. The FactoryTalk View Me (.apa) file contains the basic screens and parameters needed for a DMAT Wizard application. The folder also includes a Microsoft Word document with custom instructions on how to adapt the example file to your application drive set and prepare it to add any additional screens.

#### Factory Talk View ME Configuration Guide

This guide was created based on your DMAT Wizard selections and is meant to assist you in designing your Factory Talk View ME application using the DMAT Pre-configured HMI application files. Use this document as a supplement to the *Design From a Preconfigured HMI Application File* section in Chapter 5 of the *Drives and Motor Accelerator Toolkit Quick Start* guide, *IASIMP-QS019*,

This document will define specific steps to help you:

- Restore and Open a Preconfigured HMI Application
- Delete Unused Displays
- Delete Unused Parameter Files
- Configure Parameter Files
- Delete Unused Alarm Triggers and Tags
- Configure Goto Display Buttons on Startup Display
- Configure Equipment Status Faceplate Display

### **Design From a Preconfigured HMI Application File**

#### **Restore and Open a Preconfigured HMI Application**

- 1. Navigate to the Panelview Plus 1000 folder
- 2. Double-click the PVP1000\_Application.apa archive file

#### **Delete Unused Displays**

#### List of Required Faceplates

[ALARM] [DIAGNOSTICS] [INFORMATION] CIPMotion Faceplate K300\_Faceplate PowerFlex\_753\_755\_Faceplate PVP1000\_Startup\_Faceplate PVP1000\_StateDiagram\_Faceplate PVP1000\_AlarmHistory\_Faceplate PVP1000\_EquipmentStatus\_Faceplate

#### **Delete Unused Parameter Files**

#### List of Required Parameter Files

CIPMotion\_Parameter K300\_Parameter PF\_Parameter Startup\_Parameter StateDiagram\_Parameter EquipmentStatus\_Parameter

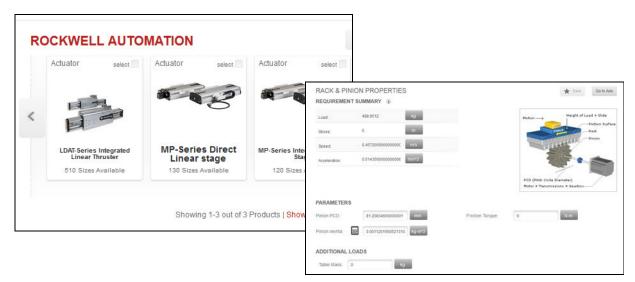
## **Review Other System Selection and Configuration Tools**

Rockwell Automation provides a variety of other system selection and configuration tools.

### **Motion Analyzer Software**

Motion Analyzer software is a comprehensive standard-drives and motion-control application sizing tool used for analysis, optimization, selection, and validation. Motion Analyzer software includes configuration of load types, profiles, and mechanisms for a variety of applications.

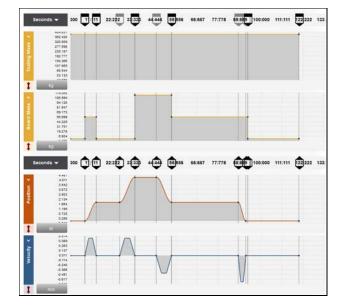
#### Load Type and Data



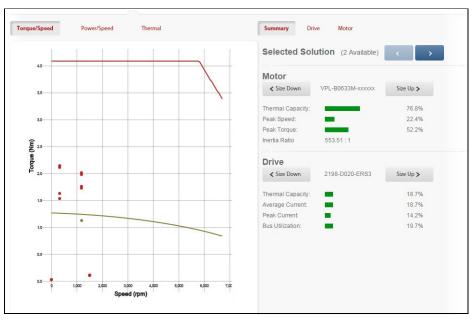
#### **Mechanism Type and Data**

Actuator	select	Actuator select	Actuator	select					
Lei	31			PMBS Ball So	crews				
E		<u> </u>				SEI	ECTION SUMM	Save Ax	Ga to
		MP-Series Direct		all the second second	-		Selected.	PMBS 32x32R-4x	w1/T7/2000
LDAT-Serie Linear	es Integrated Thruster	Linear stage	MP-Series Interest				Iguration.	Not Selected	
510 Size	s Available	130 Sizes Available	120 Sizes			Proc	uct Catalog No.	PMBS 32x32R-4x	W1/T7/2000
								Show	v Compatible Prod
									Learn N
		Showing 1-3 out of	3 Products   Sho						
		Showing 1-3 out of	3 Products   Sho	Clear Filters Selection Filters (8)	Base Product Info	Ch	oose Size 🎯	Set Config	uration 🎯
		Showing 1-3 out of	3 Products   Shot		3		<b>1</b> 2 3 4 5 6		uration 🥥
		Showing 1-3 out of	3 Products   Sho		1847 total items (				uration 🥥 SELECT
		Showing 1-3 out of	3 Products   Sho		3	fibered from 1847)	<u>1</u> 23456	462 🔊	
		Showing 1-3 out of	3 Products   Sho		> 1847 total items () SELECTA SIZE	fibered from 1847)	<u>1</u> 23456	462 🔊	SELECT PW05 12-2R
		Showing 1-3 out of	3 Products   Sho		1847 total items ()     SELECT A SIZE     FEATURES     Catalog Number     Max Acceleration	SELECT PH/IB 12/2R- 3////0/10/150	1 2 3 4 5 6 SELECT PMBS 12/2R- 24/00/110/200	462 SELECT PHILIS 12/2R- 3FWIOT10/200	SELECT PMDS 12/2R 3/W/0/T10/40
		Showing 1-3 out of	3 Products   Sho		> 1847 total items () SELECT A SIZE FEATURES Catalog Number	filtered from 1847) < SELECT PuIDS 12x2R-	1 2 3 4 5 6 SELECT PMD5 12078-	962 ≯ SELECT PMBS 12/2R-	
		Showing 1-3 out of	3 Products   Sho		SELECT A SIZE     FEATURES     Catalog Number     Max Acceleration     (msr2)	SELECT PH/US 12/2/R- 3//W0/T10/150 9.8	1 2 3 4 5 6 SELECT PMIS 1209- 200401100200 9.8	462 SELECT PMIDS 12x2R- 3FWIDT 10/2000 9.8	BELECT PMDS 12:2P 3wW0T1040 9.8

#### **Profile Data**



#### **Solution Options**



### **Engineering Assistant Software**

Engineering Assistant software provides inertia, power/ torque, braking, and other application specific calculators and formulas to assist you in sizing the motor, drive, and transmission for your application. Use this software as a supplement to Motion Analyzer.

Engineeri	ng Assistant - Aug 18, 2008–10:07	7:46 AM Ver. 3.0.4
Help Info	Tools Quit	
D	F2 - Inertia Calculations	
KOC.	F3 - Power/Torque Calculations	$\mathcal{D}n$
	F4 - Dynamic Braking Calculations	Drives Business
	F5 - Derating Worksheet	Drives Business
	Cable Voltage Drop	s
	Center Winder Calculator	
	Centrifuge Calculator	
	Conveyor Calculator	
	Drive Thermal Overload - PF700	
	Energy Savings Program - old version	
	Energy Savings	<b>F</b>
	Harmonic Calculator	
	Impact Analog Scaling	
	Lift w/No Counter Weight	
	Line Reactor Sizing	
	PF700S Electronic Gear Ratio Calculator	
	Power Formulas	

### **Product Selection Toolbox**



The Rockwell Automation Product Selection Toolbox (PST) offers a complete suite of user tools for product selection and configuration across product lines from project conception through final design. From push buttons to drives to motor control centers and fully networked control systems, you'll find the product information and configuration assistance you need to help you and your customers succeed with Rockwell Automation.



C Properties and Configuration of the second configuration	ByProduct [ dor Law ] F angement C at F angement C at F angement C at F angement C at F angement C at a second Q F angement C at a second R F angement C at a secon	-		
tex. Start 0.0 See 94 sector 10 First 64 402.CH009 403.CH009 403.CH009 403.CH009 403.CH009 403.CH009 404.CH009 40		Tonare Telefort		
a [ aponti []]gen fan	Tar GA K KING PACING PACING	T. B. R. R.	-	

#### Motion Analyzer

- Design Motion Control Systems
- Assists the user in selecting correct motor for application, proper drive, and gearbox (if required)
- Effective optimization capabilities allow user to get the most out of the selected motor and drive combination



- Allows users to have the most up-to-date applications, product, price, and supplementary information
- All programs are scheduled for update every three weeks

#### MCS Star Design MCS Bus Systems

- Helps you configure Motor Control System starters for rated motor voltages from 230...690V
- Program provides the correct catalog number, wiring diagram, and layout drawing for starters
  of your choice
- Provides assistance in selecting and dimensioning all of required busbar rack components

#### CrossWorks Competitive Cross Reference Program

- Assists in crossing competitive part numbers to Rockwell Automation equivalents
- Gives users the ability to submit crosses directly to PST and they will provide a cross or users
  can go to: <u>ab.com/e-tools</u> and look up existing cross references in the database

#### **Product Selection & System Design Tools**



#### ProposalWorks\*\*

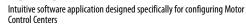
- Provides access to information on a broad range of Allen-Bradley<sup>®</sup> products and services
- Easy product selection interface to make it a snap to determine the exact catalog numbers for the item you need
- Access to current list pricing, and a comprehensive supplemental product information list
- Contains features, such as product selection wizards, agreement pricing, a spare parts generator, and the ability to separate part numbers to see what Rockwell Automation components comprise them
- All of these features and more can help you select the correct product based on your requirements and give your customers the information they need fast



#### Integrated Architecture Builder

- Lets you quickly develop Logix/NetLinx control system configurations with BOM and reports
- Integration with configurator allows configuration of PowerFlex drives and ArmorStart motor controllers
- Motion control drive/motor combinations and accessories can be added through links to Motion Analyzer software
- New Ethernet capabilities include Stratix<sup>™</sup> switches and physical media with enhanced graphical views
- IAB output can be easily exported to ProposalWorks to take advantage of extended proposal generation features, and supplementary data

## Design Low Voltage MCCs



User friendly interface helps reduce error and enables customers to get their MCCs quickly



- Simplifies the design of custom terminal block rails
- Allows you to select and place terminal blocks on mounting rail along with specifying labeling of terminal blocks, locating jumper bars between blocks, automatically selecting end barriers, and partition plates



- Allows you select product 3D CAD drawings in AutoCAD software
- Provides you with access to thousands of drawings for a wide range of Allen-Bradley
  products as well as assistance configuring catalog numbers

## Install Other System Selection and Configuration Tools

You can install the system selection and configuration software tools from the Drives and Motion Accelerator Toolkit DVD or download/access them from the Web.

## **Motion Analyzer Software**

To access Motion Analyzer software, go to <u>https://motionanalyzer.rockwellautomation.com</u>. Login or create an account to use the Motion Analyzer system sizing and selection tool.

Motion Analyzer					UNT   ¶LC	GIN Rog	kwell ation
PRODUCTS	LIBRARY	TOOLS	SUPPORT	Enter keyword or	product #	Products 🗸	P
			Learn. Select.	Size.			
Find	the solution	for your a	oplication from Rockwel	l Automation and our F	PartnerN	letwork.	
START BUI	IDING			2	QUICK T	OOLS	
	building, sizing an	nd selecting?	(Internet in the second s		Compatib	ility Browser	
Click here to st application.	tart a new project	to size your			Inertia Ca	lculator	
			2 . Leo		LINKS		
Start A New Proj	ect		@		Allen Brad	lley	

## **Install Engineering Assistant Software**

Follow these steps to install the Engineering Assistant Software tool from the Drives and Motion Accelerator Toolkit DVD.

1. Navigate to and select the Engineering Assistant Installation application on the toolkit DVD.

- DISCRETE DEVELOPMENT TOOLS -	Architecture and Hardware Selection	Suggested Selection Tools     System Selection and     Configuration Tools
	CAD Drawing Libraries Controller Logic HAI Application Miscellaneous Example Software Project Examples	BOM Development Installation the HMI screen templates can help costs. red panel diagrams and CAD drawi g starting point for your machine design. Is for both EtherNet/IP and sercos motion control.

The initial Engineering Assistant Setup dialog box opens.

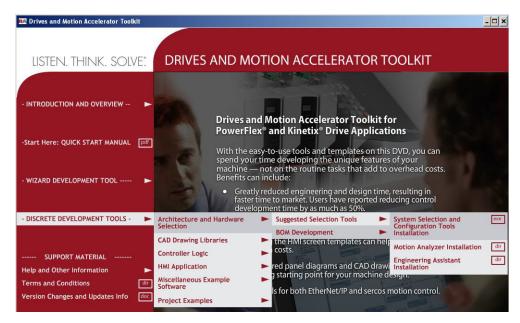
2. Click OK and follow installation instructions.

Welcome to the Eng	ineeringAssistant ver 4.1.0 insta	lation
program.		
Before proceeding, we recomme	or update shared files if they ar and that you close any applicatio	
e running.		

### **Install Product Selection Toolbox**

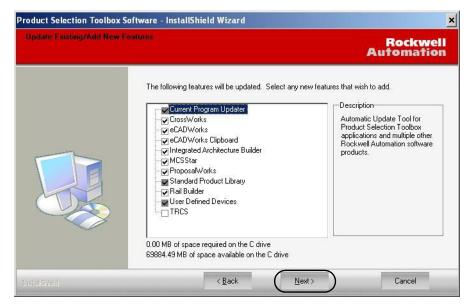
Follow these steps to install desired tools from the Product Selection Toolbox. ProposalWorks software installation is the minimum requirement for completing your system bill of materials in the next chapter.

1. Navigate to and select the System Selection and Configuration Tools Installation application on the Drives and Motion Accelerator Toolkit DVD.



The Product Selection Toolbox Software InstallShield Wizard opens.

2. Check all features that you wish to have installed.



3. Click Next and follow all install wizard instructions to complete the software installation.

ProposalWorks software installation is the minimum requirement for completing your system bill of materials in the next chapter.

## **Run the DMAT Wizard**

The DMAT Wizard creates an initial bill of materials, assembles a system drawing set, and creates a Logix Designer project file with preconfigured controller, network, drives, and initial system program logic. All of this is created in just minutes by executing the following steps.

If you prefer to build these initial files by using the traditional application tools, skip over this section and go directly to <u>Chapter 2</u>.

### Launch the DMAT Wizard

Follow these steps to launch the DMAT Wizard and set up your wizard configuration.

1. Navigate to and select the DMAT Wizard .exe file on the Drives and Motion Accelerator Toolkit DVD image.

💀 Drives and Motion Accelerator Toolkit		- 🗆 ×
LISTEN, THINK, SOLVE: DRIVE	ES AND MOTION ACCELERATOR TOOLKIT	
LISTEIN, THINK, SOLVE, DRIVE		
- INTRODUCTION AND OVERVIEW		
	Drives and Motion Accelerator Toolkit for	
	PowerFlex <sup>®</sup> and Kinetix <sup>®</sup> Drive Applications	
-Start Here: QUICK START MANUAL pdf		
	With the easy-to-use tools and templates on this DVD, you can spend your time developing the unique features of your	
	machine — not on the routine tasks that add to overhead costs.	
- WIZARD DEVELOPMENT TOOL Design with	the DMAT Wizard even lude:	
	<ul> <li>Greatly reduced engineering and design time, resulting in faster time to market. Users have reported reducing control</li> </ul>	
	development time by as much as 50%.	
- DISCRETE DEVELOPMENT TOOLS -		
	<ul> <li>Basic pre-configured logic can get you up and running quickly.</li> </ul>	

The Open or Create a Project dialog box opens.

2. Click Create New to initiate a new project.

Another configuration information dialog appears explaining machine, application, and drive configuration.

- **3.** Read configuration information dialog box and click OK to continue.
- 4. The New Project Wizard dialog box opens.
  - a. Enter Project Name.
  - b. Enter Project Description (optional).
  - c. Click Next.



Project Name:	WidgOmatic
Description:	Quick Start Example

**5.** From the Number of Machines pull-down menu, choose the number of machines in your project.

A machine, as defined by the wizard, is a control system using a single controller and housed in a single enclosure.

- 6. Click Next.
- 7. Click the Machine Name edit field and enter the desired machine name.

For the Widg-O-matic example, the machine name entered is WidgOmatic.

8. Click the Power Voltage Class edit field and from the pull-down menu choose the power voltage for your system.

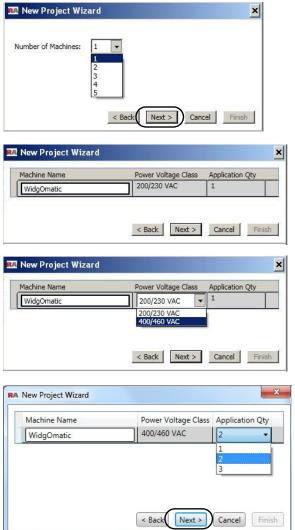
For the Widg-O-matic example, the voltage level is 400/460V AC.

**9.** Click the Application Qty edit field and from the pulldown menu choose the number of applications you are configuring.

For the Widg-O-matic example, the quantity is set to 2.

10. Click Next.

The WidgoMatic machine displays with the number of applications specified in <u>step 9</u>.



11. Click the Application\_*x* edit fields and rename the application names.

	Low-Voltage Drives	SERCOS Servo Drives	CIP Motion Drives	Ethernet/IP Indexing Servo Drives	Starters w/ Electronic Overload Relays	Soft Starters	On Machine
• WidgOmatic							
Assembly	0 -	0 -	0 🔹	0 🕶	0 👻	0 -	0 -
Packaging	0 -	0 🕶	(Q)) •	0 -	0 -	0 🕶	0 -

For the Widg-O-matic example, the two applications were renamed Assembly and Packaging.

**12.** From the Low-Voltage drives pull-down menus, choose the number of low-voltage drives to assign to each application.

w Project Wizard							
	Low-Voltage Drives	SERCOS Servo Drives	CIP Motion Drives	Ethernet/IP Indexing Servo Drives	Starters w/ Electronic Overload Relays	Soft Starters	On Machine
WidgOmatic							
Assembly	0 -	0 -	0 -	0 -	0 -	0 -	0 -
Packaging		0 -	0 -	0 -	0 -	0 -	0 -
Tuckuging							(° .)
	1 I						
	2						
	3				< Back	c Next > Ca	ancel Finish
	4						

For the Widg-O-matic example, the quantity was set to 0 for the Assembly application and 1 for the Packaging application.

**13.** From each of the Servo Drives pull-down menus, choose the number of servo drives to assign to each application.

	Low-Voltage Drives	SERCOS Servo Drives	CIP Motion Drives	Ethernet/IP Indexing Servo Drives	Starters w/ Electronic Overload Relays	Soft Starters	On Machine
<ul> <li>WidgOmatic</li> <li>Assembly</li> <li>Packaging</li> </ul>		0 • 0 •	2 <b>•</b> 0 <b>•</b>			0 •	
					< <u>B</u> ack	<u>N</u> ext >	ancel <u>Einis</u> ł

There are three types of servo drives. For the Widg-O-matic example, the CIP Motion Servo Drives quantity was set to 2 for the Assembly application and the EtherNet/IP Indexing Servo Drives quantity was set to 1 for the Packaging application. Also, you can set the number of electronic overload relays and soft-starter modules for your application.

14. Click Finish.

The DMAT Wizard configuration dialog box opens.

RA DMAT Wizard				x
<u>Eile Edit Tools H</u> elp				
📄 🛷 🛅 🜌 🌮   💼 🗙   🐼   🖏 Generate				
▲ cfdsfs	<u></u>			ר
🖌 🌣 WidgOmatic		Drive Name:	Low_Voltage_Drive_1	
<ul> <li>X Assembly</li> </ul>		Drive Type:	PF4 •	
Motor Control		Output Current: Comms:	Ethernet	
Soft Starters	+			
Starters with Electronic Overload Relays	+			
Low Voltage Drives	+			
SERCOS Servo Drives	+			
CIP Motion Drives	+			
CIP_Motion_Drive_1	=			
CIP_Motion_Drive_2				
EtherNet/IP Indexing Servo Drives	+			
🗂 On Machine	+			
🖌 🎇 Packaging				
<ul> <li>Motor Control</li> </ul>				
Soft Starters	+			
Starters with Electronic Overload Relays	+			
Low Voltage Drives	+			
Low_Voltage_Drive_1				
SERCOS Servo Drives	+			

### **Edit the DMAT Wizard Configuration**

Follow these steps to continue editing the DMAT Wizard configuration.

1. Edit your Machine Configuration.

e <u>E</u> dit <u>T</u> ools <u>H</u> elp	
📄 🛷 🛅 🛃 🌮   📑 🗙   🐼   🖏 Generate	
cfdsfs	*
A 🔅 WidgOmatic	Machine Number: 1
Assembly	Machine Name: WidgOmatic
Motor Control	Power Voltage Class: 400/460 VAC
	Power Distribution: UL LIM
Soft Starters	Control Voltage: 120 VAC
Starters with Electronic Overload Relays	Controller Type:
Low Voltage Drives	+ HMI Type: PVP1000 •
SERCOS Servo Drives	Programming Software:   RSLogix 5000   Studio 5000
CIP Motion Drives	Enclosure Size:      Small     Large
CIP_Motion_Drive_1	
CIP_Motion_Drive_2	E Digital I/O Analog I/O Point I/O
EtherNet/IP Indexing Servo Drives	Digital In Digital Out Analog Safety In Safety Out
C On Machine	•

a. Click the machine in your project configuration tree.

In this example, the machine name is WidgOmatic. The Machine editing window appears to the right of the project tree.

- b. Click the Machine Name edit field to change the machine name.
- c. Click each of the other machine configuration pull-down menus or check boxes and choose the appropriate power and control options.
- d. Select the Programming Software you intend to use for your application.
- e. Repeat step 1 for each of your machines in your project.
- 2. Edit the Application Names.

RA DMAT Wizard	
<u>Eile Edit Iools Help</u>	
📄 🛷 🛅 🕅 🌮 📄 🗙 🐼 🚱 Generate	
▲ cfdsfs	
WidgOmatic	Application Name: Assembly
Assembly	
Motor Control	
🗂 Soft Starters 🔶	
🗂 Starters with Electronic Overload Relays 🔸	
🗂 Low Voltage Drives 🔸	
🗖 SERCOS Servo Drives 🔸	
CIP Motion Drives	
CIP_Motion_Drive_1	

a. Click an application in the project configuration tree.

For the WidgOmatic example, Assembly was selected. The Application editing window appears to the right of the project configuration tree.

- b. Click the Application Name edit field to change the application name.
- c. Repeat <u>step 2</u> for each of the applications in your project.

3. Edit the SERCOS, CIP Motion, and Ethernet/IP Indexing Servo Drive Configurations.

RA DMAT Wizard	
<u>File Edit Iools H</u> elp	
📄 🛷 🛅 🜠 🌮 📄 🗙 🔣 🐼 Generate	
▲ cfdsfs	
🔺 🏶 WidgOmatic	Drive Name: CIP_Motion_Drive_1
Assembly	Drive Type:
Motor Control	Motor Type:
🗂 Soft Starters 🔶	Motor Series:
🗂 Starters with Electronic Overload Relays 🔶	
🖿 Low Voltage Drives 🔸	
🗂 SERCOS Servo Drives 🔶	
CIP Motion Drives	
CIP_Motion_Drive_1 🛕	
CIP_Motion_Drive_2 1	
🖿 EtherNet/IP Indexing Servo Drives 🔸	
🗂 On Machine 🔸	
A X Packaging	

a. Select a servo drive in the project configuration tree.

For the WidgOmatic example, CIP\_Motion\_Servo\_Drive\_1 was selected. The drive editing window appears to the right of the project configuration tree.

b. Click the Drive Name edit field and enter the desired drive name.

For the WidgOmatic example, Gantry\_X was entered as the initial drive name.

c. Click the Drive Type pull-down menu to choose the drive family.

RA DMAT Wizard	
File Edit Tools Help	
📄 🛷 🛅 🛃 🌮   🖶 🗙   🔀   🖏 Generate	
▲ cfdsfs	
🖌 🌣 WidgOmatic	Drive Name: Gantry_X
<ul> <li>Assembly</li> </ul>	Drive Type: IAM or AM: PF755
<ul> <li>Motor Control</li> </ul>	K350 Motor Type: K6500
Soft Starters	Motor Series:
Starters with Electronic Overload Relays	+
Low Voltage Drives	+
SERCOS Servo Drives	+
CIP Motion Drives	+
Gantry_X 🔨	E
CIP_Motion_Drive_3	
EtherNet/IP Indexing Servo Drives	+
🗋 On Machine	+
🔺 💥 Packaging	
Motor Control	
Soft Starters	+
Starters with Electronic Overload Relays	+
Low Voltage Drives	+
Low_Voltage_Drive_1	
SERCOS Servo Drives	+
CIP Motion Drives	+ Rockwe

For the WidgOmatic example, the Kinetix 6500 drive was chosen.

d. For assistance in sizing complex motor/drive combinations, click Motion Analyzer or Kinetix Motion Control Selection Guide, then return to this wizard section to complete your drive/motor configuration. 4. For multi-axis servo drive types, select an integrated axis module (IAM) for the first drive of its type. For the WidgOmatic example, the Gantry\_X drive is configured as an IAM module.

RA DMAT Wizard	
<u>Eile Edit Tools H</u> elp	
📄 🛷 🛅 🜌 🌮   💼 🗙   🐼   🖏 Generate	
▲ cfdsfs	
WidgOmatic	Drive Name: Gantry_X
Assembly	Drive Type: K6500 •
<ul> <li>Motor Control</li> </ul>	IAM or AM: IAM
Soft Starters	Spare Slot Count:
Starters with Electronic Overload Relays	Inverter Current Rating: 9 A
Low Voltage Drives	Converter Power Rating: 6 kW
SERCOS Servo Drives	Shunt Module:
CIP Motion Drives	Slot Count: 3
Gantry_X	E Motor Type:
CIP_Motion_Drive_3 🔥	Motor Series:
🛅 EtherNet/IP Indexing Servo Drives	+
Cn Machine	+
🖌 💥 Packaging	
Motor Control	
Soft Starters	+
Starters with Electronic Overload Relays	+

- a. From the Spare Slot Count pull-down menu, choose the number of spare slots available on the Bulletin 2094 power rail.
- b. From the Inverter Current Rating pull-down menu, choose the inverter current rating for your drive.
- c. From the Converter Power Rating pull-down menu, choose the converter power rating for your drive.
- d. Check Shunt Module if the Bulletin 2094 (rail-mounted) shunt module is included on your power rail.
- e. Note the Slot Count value.

This is the total number of slots used on the 2094 power rail. You are prompted if the slot count exceeds the power rail capacity.

f. Check Velocity and Torque Mode Only if you would like the servo drive axis to be configured for Velocity mode.

To select Torque mode, use the Axis Properties configuration in the Logix Designer application. If this box is clear, the axis configuration defaults to Position mode.

g. From the pull-down menus, choose the Motor Type and Motor Series being paired with the drive. For the WidgOmatic example, the Gantry\_X drive is configured for the Rotary Motor Type and the MPL Motor Series. 5. For single-axis drive types or secondary multi-axis servo drives, select the appropriate axis module (AM) configuration option.

For the WidgOmatic example, the Gantry\_Y drive is a Kinetix 6500 (K6500) AM module.

RA DMAT Wizard	
Eile Edit Tools Help	
📗 🛷 🛅 🖾 🌮 🛛 👘 🗙 🛛 🚱 Generate	e e e e e e e e e e e e e e e e e e e
▲ cfdsfs	
WidgOmatic	Drive Name: Gantry_Y
<ul> <li>X Assembly</li> </ul>	Drive Type: K6500   IAM or AM: AM
Motor Control	AM Selection
🗋 Soft Starters 🔹 🔸	Inverter Current Rating: 4 A
🗂 Starters with Electronic Overload Relays 🔹	Parent IAM Drive: Gantry_X
🗋 Low Voltage Drives 🔹	Motor Type: Rotary
🗋 SERCOS Servo Drives 🔸	Motor Series: MPL
CIP Motion Drives	
Gantry_X	
Gantry_Y	
EtherNet/IP Indexing Servo Drives	
🗂 On Machine 🔸	

- a. From the Inverter Current Rating pull-down menu, choose the inverter current rating for your drive.
- b. From the Parent IAM Drive pull-down menu, select the parent IAM module this AM module is assigned to (applies to multi-axis systems only).

AM modules must be assigned to a parent IAM module of the same drive family.

- c. From the pull-down menus, choose the Motor Type and Motor Series being paired with the drive. For the WidgOmatic example, the Gantry\_Y drive is configured for the Rotary Motor Type and the MPL Motor Series.
- d. Repeat step 3 through step 5 for all of the remaining servo drives in your project.

RA DMAT Wizard	
<u>Eile Edit T</u> ools <u>H</u> elp	
📄 💞 🖺 🖉 🧭 📑 🗙 🐼 Generate	8
▲ cfdsfs	
WidgOmatic	Drive Name: Gantry_Y
Assembly	Drive Type: K6500   IAM or AM: AM
Motor Control	AM Selection
🗋 Soft Starters 🔶	Inverter Current Rating: 4A
🗋 Starters with Electronic Overload Relays 🔶	Parent IAM Drive: Gantry_X
🗋 Low Voltage Drives 🔸	Motor Type: Rotary •
🗋 SERCOS Servo Drives 🔸	Motor Series: MPL
CIP Motion Drives	
Gantry_X	
Gantry_Y	
EtherNet/IP Indexing Servo Drives	
🗋 On Machine 🔸	
🔺 💥 Packaging	
Motor Control	
🗂 Soft Starters 🔶	
🗂 Starters with Electronic Overload Relays 🔹 🔸	
▲ 🗋 Low Voltage Drives +	
Low_Voltage_Drive_1	
🗖 SERCOS Servo Drives 🔸	
CIP Motion Drives	Rockwell
LetharNot/ID. Indaving. Coper. Drives	Automation

6. Edit the Low-Voltage Drive configurations.

RA DMAT Wizard	
Eile Edit Iools Help	
▲ cfdsfs	
WidgOmatic	Drive Name: Low_Voltage_Drive_2
Assembly	Drive Type:
Motor Control	Output Current:
🗂 Soft Starters 🔹 🔸	
🗂 Starters with Electronic Overload Relays 🔹	
🔺 🛅 Low Voltage Drives 🔶	
Low_Voltage_Drive_2 🔨	
🗂 SERCOS Servo Drives 🔸	
CIP Motion Drives	

a. Select Low\_Voltage\_Drive\_*x* in the project configuration tree.

For the WidgOmatic example, Low\_Voltage\_Drive\_1 was selected. The drive editing window appears to the right of the project configuration tree.

RA DMAT Wizard		
Eile Edit Tools Help		
📄 🛷 🛅 🖉 🌾 💼 🗙 🐼 🖏 Generate		
▲ cfdsfs		
WidgOmatic		ror_Drive
<ul> <li>X Assembly</li> </ul>	Drive Type: PF753 Output Current: 5	
<ul> <li>Motor Control</li> </ul>	Comms: Ethernet	
Soft Starters	+ Energy:	
Starters with Electronic Overload Relays	+	
🔺 🛅 Low Voltage Drives	+	
Conveyor_Drive		
SERCOS Servo Drives	+	
CIP Motion Drives	+ ■	
Gantry_X		
Gantry_Y		
🛅 EtherNet/IP Indexing Servo Drives	+	
🛄 On Machine	+	
🖌 💥 Packaging		
Motor Control		
Soft Starters	+	
Starters with Electronic Overload Relays	+	
🔺 🛅 Low Voltage Drives	+	
Low_Voltage_Drive_1		
E SERCOS Servo Drives	+	Rockwell
CID Motion Drives		Automation

- b. Click the Drive Name edit field and enter the desired drive name.
   For the WidgOmatic example, Conveyor\_Drive was entered as the initial drive name.
- c. From the Drive Type pull-down menu, choose the drive family. For the WidgOmatic example, the PowerFlex 753 (PF753) drive is selected.
- d. Select the appropriate output current for the drive.
- e. Repeat step 6 for all of the remaining low-voltage drives in your project.
- 7. Edit all electronic overload relays and soft starter modules in your application.

Current and other selection pull-down menus are similar to the drive menus.

8. Generate the Output Files.

Before you can generate a DMAT file, all red highlighted items must be cleared in your configuration.

a. Click Generate on the DMAT Wizard toolbar.

RA DMAT Wizard	
Eile Edit Tools Help	
📄 🛷 🛅 🛃 🌮   📑 🗙   🔀 (😍 Generate )	
▲ cfdsfs	
🖌 🏶 WidgOmatic	
Assembly	

The Generate Outputs dialog box opens.

b. Check the Drawing Types you wish to have generated as part of the output files.



c. Click Generate.

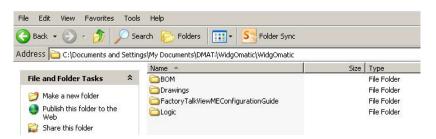
The DMAT Wizard generates a folder containing the output files. If the Drives and Motion Accelerator Toolkit was installed in the default directory, you will find the folder located in: C:\Documents and Settings\My Documents\DMAT\<projectname>.

For the WidgOmatic example, the path is:

C:\Documents and Settings\My Documents\DMAT\WidgOmatic.

e Edit View Favorites	Tools	Help		
🕤 Back 🔹 🕥 🔹 🏂 🗍	Se.	arch 🜔 Folders 🛛 🎹 🕶 🛃 Folder S	ync	
ddress 🗀 C:\Documents an	nd Settini	gs\My Documents\DMAT\WidgOmatic		40
	200	Name 🔺	Size	Туре
File and Folder Tasks	*	🛅 WidgOmatic		File Folder

d. Double-click the machine folders to view the different output folders and files created.



# **Bill of Materials Completion**

In this chapter you use Rockwell Automation ProposalWorks software to complete the drives and motion system bill of materials that the DMAT Wizard created.

If you chose not to use the DMAT Wizard, follow the procedures in <u>Appendix E</u> to assemble the initial BOM ProposalWorks file before executing the following steps in this chapter. If you do not have ProposalWorks software, you may use the Microsoft Excel file that the DMAT Wizard provides as a starting point in creating a bill of materials with the help of your local Allen-Bradley distributor.

# **Before You Begin**

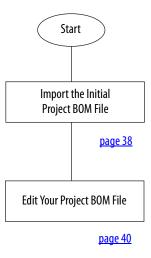
- Complete the initial system configuration using the DMAT Wizard (refer to <u>Chapter 1</u>) or
- Assemble the initial BOM using ProposalWorks software (refer to <u>Appendix E</u>)

## What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative
- ProposalWorks software, version 7.5 or later, or Microsoft Office Excel 2010 Download ProposalWorks software from <a href="http://www.rockwellautomation.com/en/e-tools/">http://www.rockwellautomation.com/en/e-tools/</a> or ask your local Allen-Bradley distributor for the Product Selection Toolbox DVD.
- The user manual for your Drives and Motion hardware. Refer to <u>Additional Resources</u> on <u>page 15</u> for publication numbers.

# **Follow These Steps**

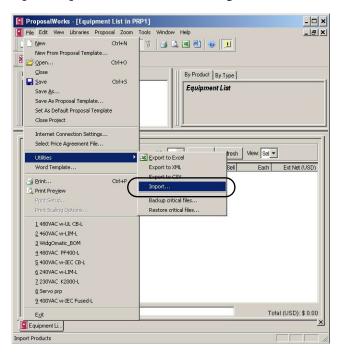
Complete these steps to complete the commissioning process for your drives and motion application.



# **Import the Initial Project BOM File**

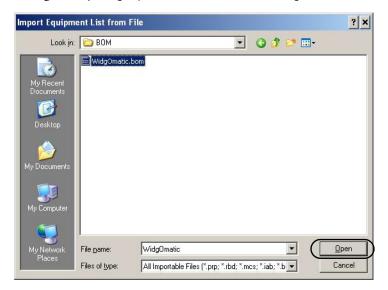
Follow these steps to import the initial project BOM file.

1. Open ProposalWorks software, navigate to File Menu>Utilities, and select Import.



If you chose to assemble the initial BOM file using ProposalWorks software, open the ProposalWorks (.prp) file you created in <u>Appendix E</u> and skip to <u>step 2</u>.

2. Navigate to your projects .bom file and click Open.



If the default DMAT Wizard directory was used, your project's .bom import file is in C:\Documents and Settings\*PC Name*\My Documents\DMAT\*ProjectName\MachineName*\BOM directory.

The Widg-O-matic example file may be found in: C:\Program Files\RA\_Simplification\DMAT\B-Files\ 6-Project Examples\Widg-O-matic.

The ProposalWorks file opens.

<u>Eile E</u> dit <u>V</u> ie				
	w <u>L</u> ibraries Proposal <u>Z</u>	oom <u>T</u> ools <u>W</u> indow	Help	
	🍠 🗔   🤣 🚳 🚇 💐			
	Proposal Outline Editor		By Product By Type	
Equipmer	t List		Equipment List	
E DMAT			DMAT	
			-2094-BL50S	
			- 140LI-H-RMX	cations 🔍
Printed Repo	rt Detail			_
Title: DMAT	I♥ Expo	rt List Wit: Ib	s 💌 iply Agraema (Refresh) View: Se	
Item / Dev		Wit (lbs) DS PGC Net C		5 (N) ( (100)
nem / Dev	D Qty Typical Delivery	INT (IDS) US PGC NET U	only List Ea Sell Each	Ext Net (USD)
The following	j catalog numbers provid	le a starting point to ma	ake it easy to adjust and finalize the comp	onents needed. Thi—
M	1.0. "			
Machine - W	dgOmatic			
Machine - W	dgOmatic			
	dgOmatic			
Machine - W System	dgOmatic			
	dgOmatic			
System	dgOmatic			
System	dgOmatic			
System	dgOmatic			
System Input Power				
Input Power	2094-BL50S	50V, 50A N/A H1 818	\$2,939.10 1.0000 \$2,939.10	\$ 2,939.10
System Input Power	2094-BL50S Line Interface Module, 46 1 Preferred 140U-H-RMX	N/A H1 818	\$2,939.10 1.0000 \$2,939.10	\$ 2,939.10
System Input Power 1	2094-BL50S Line Interface Module, 46	N/A H1 818		\$ 2,939.10
System Input Power 1	2094-BL50S Line Interface Module, 46 1 Preferred 140U-H-RMX	N/A H1 818	\$2,939.10 1.0000 \$2,939.10	\$2,939.10
System Input Power 1	2094-BL50S Line Interface Module, 46 1 Preferred 140U-H-RMX	N/A H1 818	I . I + mont .	\$ 2,939.10 
System Input Power 1 2 Add:	2094-BL50S Line Interface Module, 46 1 Preferred 140U-H-RMX	N/A H1 818	I . I + mont .	

3. Click Refresh to update prices in local currency.

# **Edit Your Project BOM File**

The DMAT Wizard you used in <u>Chapter 1</u> or the steps you followed in <u>Appendix E</u> created an initial bill of materials (BOM), however, individual preconfigured product listings should be reviewed and possibly edited to fit your specific application needs.

ProposalWorks software includes a variety of specific product configuration tools to make further BOM adjustments easy. These steps provide examples of using ProposalWorks Product Configuration Assistants to edit your initial project BOM file to meet your specific application needs.

Follow these steps to edit the BOM file you imported or assembled for your specific application.

- 1. Edit a product for your specific application.
  - a. Double-click a product catalog number to activate the Product Configuration Assistant.

4	1492-SP1C010				
	1492 Supplementary Pro	tectors, 1 pole, Magnetic Trip Ra	inge 510 x Rated Current	(Inductive Load	ds), 1.0 A
	1	Stocked	N/A	B6	\$32
;	1489-A2D250				
	UL489/CSA 22.2 No 5.1	Circuit Breaker, 2 Pole, Trip Cu	rve D, 25 Amp, 480Y/277 \	/AC	
	1	Stocked	N/A	B5	182
-					
Su	rge / Filter - note double :	click surge product to select (	other current, voltage or	pole configu	rations.
Su	rge / Filter - note double	click surge product to select	other current, voltage or	pole configu	rations.
02.02	4983-DS120-401	<b>lick surge product to select</b>	•		rations.

In this example, catalog number 1489-A2D250 was selected.

The Product Configuration Assistant dialog box opens. You can browse and select from a variety of product options.

b. Click the Current Rating attribute.

nter the order code for the i	desired 1489 Miniature Circuit Breakers	• 22
489-A2D250		
<b>R</b> , make the selections for	the product that you need using the interactive selection chart.	
Accept Validate	Cancel Reset Undo Redo	Representative Photo Only
IRCUIT BREAKER D	ATA	Current Rating
Configuration	Standard Configuration	C 0.5 A
Pole Configuration	2 Poles	C 1A
Trip Curve	Type D trip Curve (Highly Inductive)	C 1.5 A
Current Rating	25 A )	0 2 A
PTIONS		C 3A -
Options	- NO SELECTION	© 4 A
CCESSORY ITEMS		0 5 A
Accessories	- NO SELECTION	C 6 A
		C 7 A
		C 8 A
		C 10 A
		O 13 A
		O 15 A
		0 <u>16 A</u>
		O 20 A
		© 25 A)
		C 30 A
		C 32 A
		C 35 A

In this example, the Current Rating option is 25 A. For more in-depth product selection information, refer to product selection guides or Motion Analyzer software.

c. For this example, select 15 A under the Current Rating field. The catalog number field is replaced with 1489-A2D150.

Product Configurator Powere	ed by RAISE				
<b>1489 Miniature Circ</b> <b>Product Configuration</b> Enter the order code for the d 1489-A2D150 <u>OR</u> , make the selections for t	Assistant esired 1489 M he product tha	iniature Circuit	ing the interact		Representative Photo Only
Accept Validate	Cancel	Reset	Undo	Redo	
CIRCUIT BREAKER DA	10000				🚔 Current Rating 🚔
Configuration	Conception and the second	d Configuratior	1		C 0.5 A
Pole Configuration	2 Poles				C 1 A
Trip Curve	and the second sec	trip Curve (Higl	hly Inductive)		C 1.5 A
Current Rating	15 A				C 2 A
OPTIONS					O 3 A -
Options	- NO SEL	ECTION			O 4 A
ACCESSORY ITEMS Accessories	- NO SEL	ECTION			O 5 A
Accessories	- NU 3EL	ECHOM			O 6 A
					07A
					C 8A
					O 10 A
					C 13 A
					(© 15 A)
					0 <u>16 A</u> 0 20 A
					0 25 A
					0 25 A
					O 32 A
					C 35 A
					0 35 A
A					
C MESSAGES					

d. Click Accept to make the product change within the Product Configuration Assistant. The Product Configuration Assistant closes and your BOM file reflects the change.

4	1492-SP1C010						
	1492 Supplementary Pro	otectors, 1 pole, Magnetic Trip Ra	nge 510 x Rated Current	(Inductive Load	is), 1.0 A		
	1	Stocked	N/A	B5	\$32		
5	1489-A2D150						
			D 45 A 4000/0771	1.1.1			
	UL489/CSA 22.2 No 5.1	Circuit Breaker, 2 Pole, Trip Cur	Ve D, 15 Amp, 480 Y/2/ / V	/AC			

6	4983-DS120-401					
	4983 Surge and	Filter Protection, Din Rail Mount, UL 1449, 1	r Protection, Din Rail Mount, UL 1449, 120V, 40kA, 1 Pole Configuration			
	1	Stocked	N/A	B5	914	

2. Edit a product group for your specific application.

Product group refers to an item (catalog number) that includes one or more sub items.

a. Double-click a product group catalog number to activate the Product Configuration Assistant.

In this example, item 13 (catalog number 2094-BMP5-M) with sub items 13.1 and 13.2 was selected.

The Product Configuration Assistant dialog box opens. You can browse and select from a variety of product options.

11	2094-PR2				
*Verify Price in SAP	Power Rail, 230V OR	460V, 2 Axis.			
	1	Non-Stocked	N/A		
12	2094-BC02-M02-M				
	Power Module, Integra	ted, 460V, 15kW Conv. 15A Inv., Kine	tix 6500 Ether Net/IP Safe		
	1		N/A		
12.1	2090-K6CK-D44M				
	Connector Kit Kinetix S	afe Speed 44 pin			
	1		N/A		
12.2	2094-EN02D-M01-S0				
	EtherNet/IP Safe Torqu	ie-Off Control Module	70		
$\sim$	1		N/A		
13	2094-BMP5-M				
	Power Module, 460V,	5A Inv., Kinetix 6500 Ether Net/IP Safe	Torque-Off Control Module		
	1		N/A		
13.1	2090-K6CK-D44M				
	Connector Kit Kinetix S	afe Speed 44 pin			
	1		N/A		
13.2	2094-EN02D-M01-S0				
	EtherNet/IP Safe Torqu	e-Off Control Module			
	1		N/A		
14	1585J-M8CBJM-0M3				
*Verify Price in SAP	1585 Ether Net Cables,	8 Conductors, RJ45, Straight Male, R.	J45, Teal PVC, Shielded, F		
12.0	1	- ++1, 548 (424) (25)	N/A		
15	1585J-M8CBJM-5				
*Verify Price in SAP	1585 Ether Net Cables,	& Conductors, RJ45, Straight Male, R.	J45, Teal PVC, Shielded, F		
	2		N/A		

b. Click the Inverter Current Rating attribute.

Product Configuration A	6500 Modular Multi-axis Servo Drive Assistant ired 2094, Kinetix 6200 / 6500 Modular Multi-axis Servo Drive	
OR, make the selections for the Accept Validate	product that you need using the interactive selection chart. Cancel Reset Undo Redo	Representative Photo Only
PRODUCT SELECTION		Inverter Current Rating
Bulletin Number	Bulletin 2094	○ 4A (460∨ Input Voltage)
Input Voltage	460V AC, 50/60Hz	C 9A (460V Input Voltage)
Power Module	Axis Module	C 15A (460V Input Voltage)
Converter Power Rating	None	C 30A (460∨ Input Voltage)
Inverter Current Rating	4A (460V Input Voltage)	C 45A (460V Input Voltage)
Control Module		35 d 882.
Control Module	Kinetix 6500 EtherNet/IP Safe Torque-Off Control Module 2094-EN02D-M01-S0	
Accessories		
Accessories	<ul> <li>(1) <u>Connector Kit Kinetix</u> Safe Speed 44 pin 2090-K6CK-D44M</li> </ul>	
		-

In this example, the Inverter Current Rating product option is 4 A. The sub items (13.1 and 13.2) include the control module and connector kit accessory. For more in-depth product selection information, refer to product selection guides or Motion Analyzer software.

c. For this example, select 15 A under the Inverter Current Rating field.

The catalog number field was replaced with 2094-BM02-M. In addition, the 2094-EN02D-M01-S1 control module was chosen to replace the 2094-EN02D-M01-S0.

Enter the order code for the des	ired 2094, Kinetix 6200 / 6500 Modular Multi-axis Servo Drive	
	e product that you need using the interactive selection chart. Cancel Reset Undo Redo	Representative Photo Only
RODUCT SELECTION		Inverter Current Rating
Bulletin Number	Bulletin 2094	C 4A (460∨ Input Voltage)
Input Voltage	ge 460V AC, 50/60Hz	
Power Module	Axis Module	€ 15A (460∨ Input Voltage)
Converter Power Rating	None	C 30A (460V Input Voltage)
Inverter Current Rating	15A (460∀ Input Voltage)	C 45A (460V Input Voltage)
Control Module		
Control Module	Kinetix 6500 EtherNet/IP Safe Speed Control Module 2094-EN02D-M01-S1	
Accessories		
Accessories	<ul> <li>(1) Connector Kit Kinetix Safe Speed 44 pin 2090-K6CK-D44M</li> </ul>	

d. Click Accept to make the product change within the Product Configuration Assistant.

11	2094-PR2				
*Verify Price in SAP	Power Rail, 230V OR 46	50V, 2 Axis.			
	1	Non-Stocked	N/A	H1	
12	2094-BC02-M02-M				
	Power Module, Integrate	ed, 460V, 15kW Conv. 15A Inv., k	(inetix 6500 EtherNet/IP Sa	fe Torque-C	
	1		N/A	H1	
12.1	2090-K6CK-D44M		46	16	
	Connector Kit Kinetix Sa	fe Speed 44 pin			
	1		N/A	H1	
12.2	2094-EN02D-M01-S0				
200,000	EtherNet/IP Safe Torque	e-Off Control Module			
	1		N/A	H1	
13	2094-BM02-M				
	Power Module, Axis, 46	0V, 15A Inv., Kinetix 6500 EtherN	let/IP Safe Speed Control N	lodule	
	1		N/A	H1	
13.1	2090-K6CK-D44M		195	100	
	Connector Kit Kinetix Sa	fe Speed 44 pin	50 <sup>-</sup>	200	
	1		N/A	H1	
	2094-EN02D-M01-S1				
13.2					
13.2	Ether Net/IP Safe Speed	Control Module			
13.2	EtherNet/IP Safe Speed	Control Module	N/A	H1	
	EtherNet/IP Safe Speed 1 1 1585J-M8CBJM-0M3	Control Module	N/A	H1	
14	1 1585J-M8CBJM-0M3	Control Module			
14	1 1585J-M8CBJM-0M3				
13.2 ( 14 *Verify Price in SAP 15	1 1585J-M8CBJM-0M3		, RJ45, Teal PVC, Shielder		
14 *Verify Price in SAP 15	1 1585J-M8CBJM-0M3 1585 Ether Net Cables, 8 1 1 1585J-M8CBJM-5		, RJ45, Teal PVC, Shielder	d, PVC Gen	

Sub item (13.2) also reflects the updated catalog number and description.

- 3. Delete products not required for your specific application.
  - a. Select the product or product group not required for your application.

Motors	Section
--------	---------

	CM201-NV00118AXZCC				
*Verify Price in SAP	CM201 - Vector Duty Enclosed Small AC M	Motors, 1 HP, 1800 RPM, C-Face Foot Mou	inted, Frame S	Size is 143 TC	
	1	59.000	D3	486	
37	CM227-BK00318AXZCA				
	CM227 - AC NEMA Frame Inverter Brake	Motor, 3 HP, 1800 RPM, C-Face Foot Mo	unted, Frame :	Size is 182TC	
	1	120.000	D3	502	
8	CM203-NV7F517AXZCC				
*Verify Price in SAP	CM203 - Vector Duty Laminated Steel Fran	me AC Motors, 7.5 HP, 1750 RPM, C-Face	Foot Mounted	I, Frame Size is F	L1852
	1	210.000	D3	486	1963W0409

In this example, items 37 and 38 were selected.

b. From your keyboard, press delete.

#### Motors Section

36		CM201-NV001	18AXZCC				
isaos:	*Verify Price in SAP	CM201 - Vector	Duty Enclosed Small AC Motors, 1 HP, 1800	RPM, C-Face Foot Mount	ed, Frame	Size is 143 TC	
		1		59.000	D3	486	

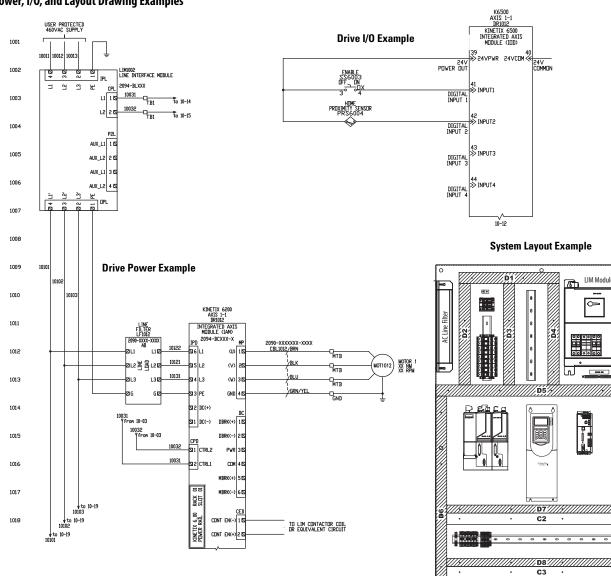
The product or products are deleted from the BOM project file.

- 4. Save your edited BOM project file.
- 5. Send the BOM project file to your Rockwell Automation distributor for a quote.

## Notes:

# **System Layout and Wiring**

In this chapter you edit the set of layout and wiring drawings from the DMAT drawing library that the DMAT Wizard created. If you chose not to use the DMAT Wizard, follow the procedures in <u>Appendix F</u> to assemble the initial project drawing set before executing the steps in this chapter.



#### Power, I/O, and Layout Drawing Examples

¢4

5

To assist you in understanding how to best use the drawing libraries, the Widg-O-matic machine application example is used in the drawing editing steps provided. The Widg-O-matic machine includes the following drive, power, and control devices:

- Two Kinetix 6500 (400V-class) servo drives and motors (home and enable inputs)
- One PowerFlex 753 (400V-class) drive and induction motor
- One Kinetix 300 (400V-class) servo drive and electric cylinder
- One Bulletin 2094 line interface module (LIM)
- One ControlLogix controller and EtherNet/IP network module

# **Before You Begin**

- Complete the initial system configuration using the DMAT Wizard (refer to <u>Chapter 1</u>) or
- Assemble the initial project drawing set without the DMAT Wizard (refer to Appendix F)

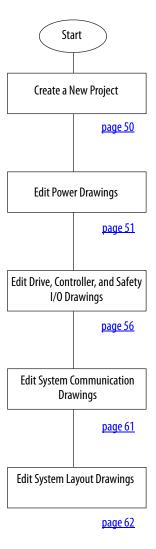
## What You Need

- Drives and Motion Accelerator Toolkit DVD, publication IASIMP-SP017
- AutoCAD Electrical or AutoCAD software to open the DWG or DXF files
- Adobe Reader software to open PDF files
- Line Interface Module Installation Instructions, publication 2094-IN005
- System Design for Control of Electrical Noise Reference Manual, publication GMC-RM001
- System Design for Control of Electrical Noise Video, publication GMC-SP004
- The user manual for your Drives and Motion hardware. Refer to <u>Additional Resources</u> on <u>page 15</u> for publication numbers.

## **Follow These Steps**

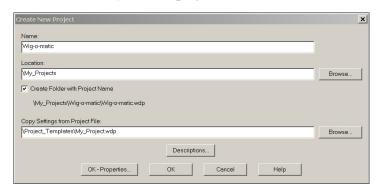
Complete the following steps to create your system layout and wiring drawings. These steps provide general instructions for how to maximize the use of the toolkit's drawing library in creating a complete drives-and-motion system layout and wiring drawing set. AutoCAD or AutoCAD Electrical software is recommended to take full advantage of the drawing editing steps included in this chapter and the library's device wiring references and attributes that move with the devices as you edit your project drawing set. Some of the initial project creation steps are illustrated using AutoCAD Electrical software, but most are generic and can be used with a variety of software drawing packages.

If you chose not to use the DMAT Wizard, follow the instructions in <u>Appendix F</u> before executing the following steps in this chapter.



### **Create a New Project**

- 1. Open your drawing software.
- 2. Create and name your new project.



3. Add and select the toolkit library drawings assembled by the DMAT Wizard.

Look in:	Wig-o-matic			- 🗧 🗹		🗃 🗹 🧕 🚿 🚨 🛒 🥹 - 👔	
	Name 🔺		Туре	Date Modified	Ē	B WIG-O-MATIC	
	010_K6500_460VAC_w_LIM.dwg		AutoCAD Drawing	8/6/2010 5:08 PM		Projects	
History	020_K300_460VAC_Additional_Drives.dwg		AutoCAD Drawing	8/6/2010 5:08 PM			
	020_PF750_Series_460VAC_Additional_Drives.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Close	
1 k	030_CLX_GLX_120VAC_Control_Power.dwg	29 KB		8/6/2010 5:08 PM			
_	660_K300_Digital_IO.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Descriptions	
ocuments	060_K6500_Digital_IO.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Title Block Update	
<u></u>	1060_PF753_IO.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Drawing List Report	
$\sim$	070_K300_Safety_IO.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Drawing List Keport	
avorites	070_K6500_Safety_IO.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		New Drawing	
avonies	B080 K300 Feedback.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Add Drawings	
	080 K6500 Feedback.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM			
	9090_CLX_Digital_Inputs.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Add Active Drawing	
esktop	100 CLX Digital Outputs.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM		Reorder Drawings	
	110_CLX_Analog_IO.dwg	29 KB		8/6/2010 5:08 PM		Remove Drawings	
	120_Ethernet_Communication.dwg	29 KB	AutoCAD Drawing	8/6/2010 5:08 PM			
	140 Sm Enclosure Layout.dwg	29 KB		8/6/2010 5:07 PM		Task List	
	150_CLX_w_LIM_Sm_Panel_Layout.dwg	29 KB		8/6/2010 5:07 PM		Publish +	
	320 PF750 Series Footprints.dwg	29 KB		8/6/2010 5:07 PM		Publish	
	400_Kinetix_300_Footprints.dwg		AutoCAD Drawing	8/6/2010 5:07 PM		Settings	
	430_Kinetix_6200_6500_Footprints.dwg		AutoCAD Drawing	8/6/2010 5:07 PM			
	500 LIM Footprints.dwg		AutoCAD Drawing	8/6/2010 5:07 PM		Exception List	_
	600_PanelView_Plus_Footprints.dwg		AutoCAD Drawing	8/6/2010 5:07 PM		Properties	
	- cooj alemenj boj copiliolang	100110	nacocho braning	0)0)2010 0.07111			
	•				jer 1		
					l 🎽		
					ar ar		
					Project Manager		
	File name:				ec		
					0		

4. Navigate to the appropriate DWG or DXF Drawing directory that was created by the DMAT Wizard.

If the default DMAT Wizard directory was used, your project's drawing set is in C:\Documents and Settings\*PC Name*\My Documents\DMAT\*ProjectName*\MachineName\Drawings\*filetype* directory.

The Widg-O-matic example drawing files may be found in: C:\Program Files\RA\_Simplification\DMAT\B-Files\6-Project Examples\Widg-O-matic\WidgOmatic\_CAD\*filetype* directory.

If you chose to assemble the Project Drawing Set without using the DMAT Wizard, navigate to the drawing directory you created in <u>Appendix F</u>.

### **Edit Power Drawings**

1. Open your initial drive power drawing that includes the main power distribution components.

For the Widg-O-matic machine application example, the 010\_K6500\_460VAC\_w\_LIM.dwg file is opened. Refer to the figure on page 52.

2. Delete drives not used in your project.

For the Widg-O-matic machine application example, only two Kinetix 6500 drives are required, so the third drive is deleted. Refer to the shaded area in the figure on <u>page 52</u>.

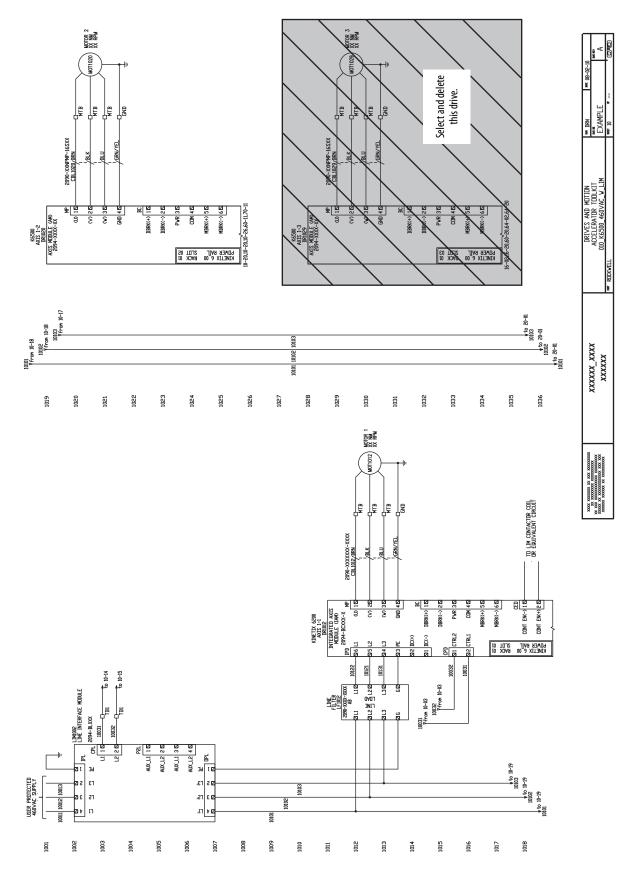
3. Open all additional drive drawings and delete drives not used in your project.

For the Widg-O-matic machine application example, both the 020\_K300\_460VAC\_Additional\_Drives.dwg file and the 020\_PF750\_Series\_460VAC\_Additional\_Drives.dwg file are opened and unused drives are deleted. Refer to the figures on page 53 and page 54.

4. Open all controller control power drawings and edit power connections and devices as necessary.

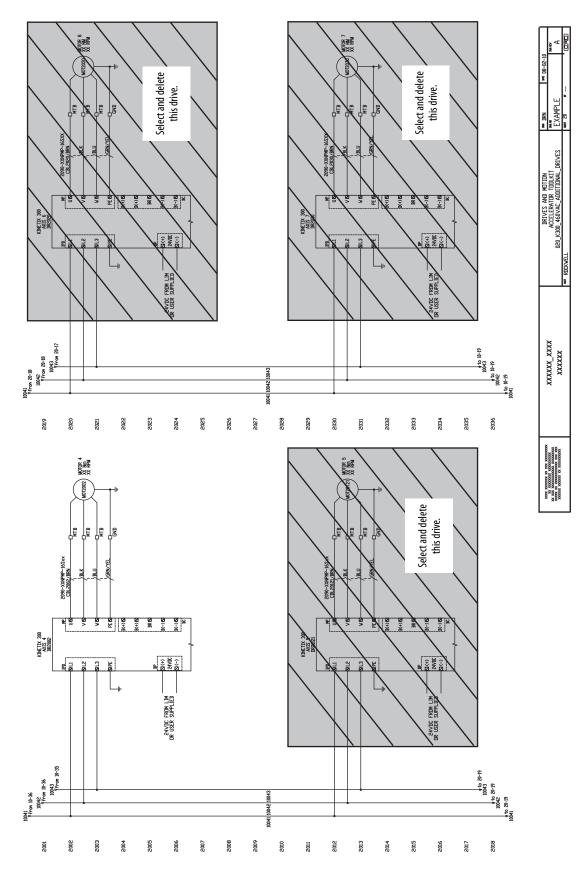
For the Widg-O-matic machine application example, no changes to the 030\_CLX\_GLX\_120VAC\_Control\_Power.dwg files were required. Refer to the figure on page 55.

#### Kinetix 6500 (460V) Drive with LIM Module

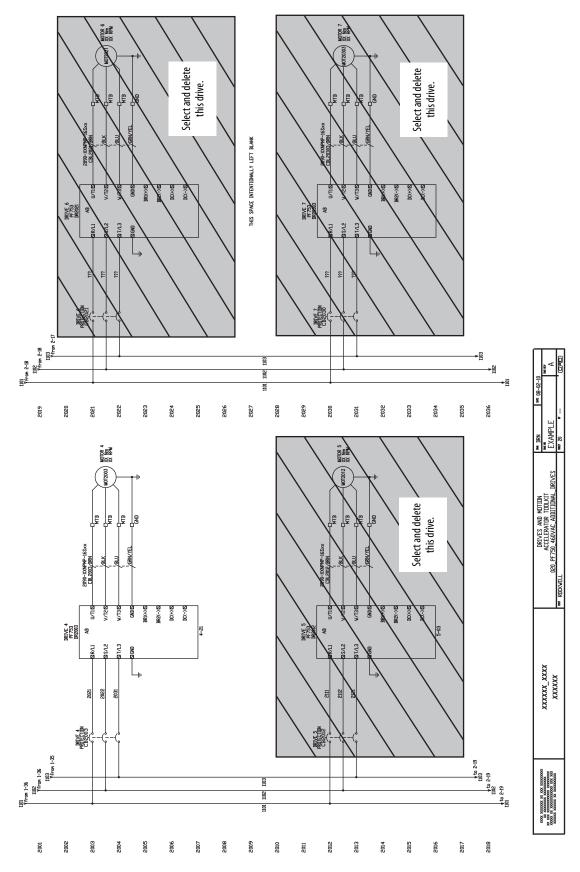


Rockwell Automation Publication IASIMP-QS019F-EN-P - September 2015

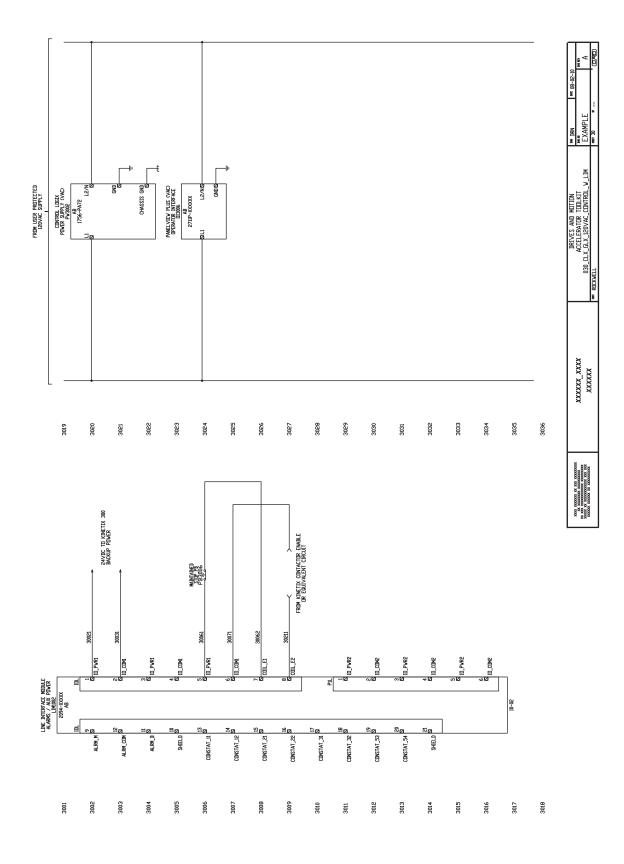
#### Kinetix 300 (460V) Additional Drives



#### PowerFlex 750 (460V) Additional Drives



#### ControlLogix/GuardLogix® (120V) Control Power with LIM Module



## Edit Drive, Controller, and Safety I/O Drawings

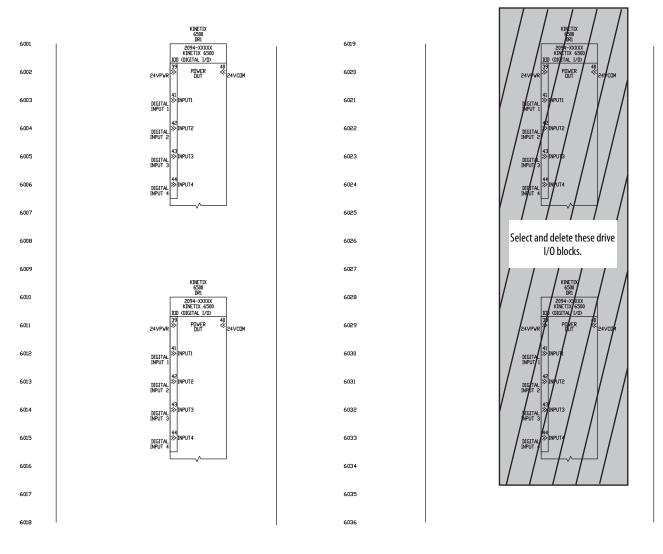
1. Open all drive, controller, and safety I/O drawings as required for your application.

For the Widg-O-matic machine application example, the 060\_K6500\_Digital\_IO.dwg file is opened.

2. Delete devices not used in your project.

For the Widg-O-matic machine application example, only two Kinetix 6500 drives are required, so the third and fourth I/O blocks are deleted.

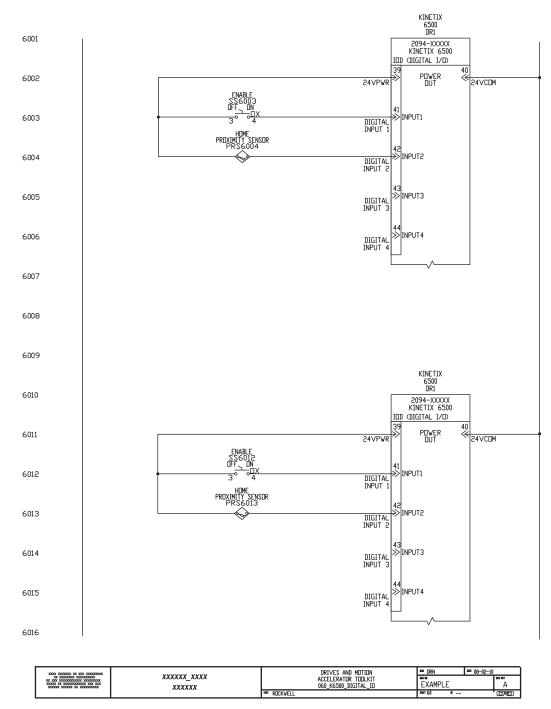
#### Kinetix 6500 Digital I/O Example



X00X X00000X XX X0X X0000000X		DRIVES AND MOTION	M DRN	ME 08-02-10	
XX X000000X X0000000X X00X X000000000X X000000X X00XX X00000000	xxxxxx_xxx xxxxxx	ACCELERATDR TDDLKIT 060_K6500_DIGITAL_ID	EXAMPLE		A
		as RDCKWELL	ыш 60 ø		

3. Add standard or unique I/O devices and connections required for your application.

For the Widg-O-matic machine application example, the Enable on-off switches and Home proximity switches are added to both Kinetix 6500 drives (input 1 and 2 respectively).



Kinetix 6500 Drives (add digital I/O devices)

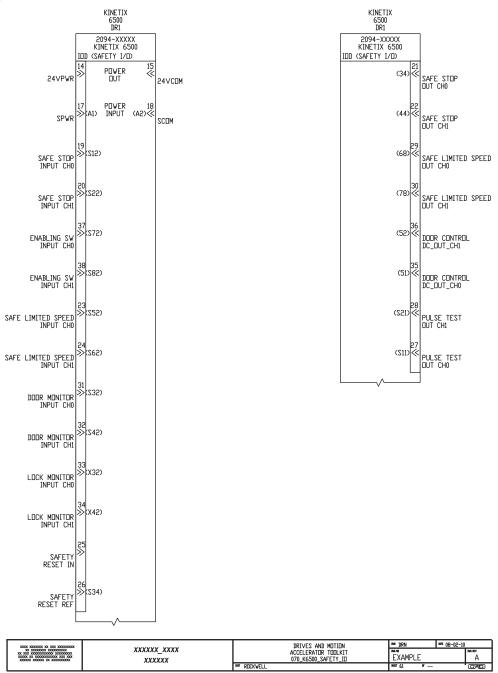
4. Repeat step 1 through step 3 for all I/O drawings within your project.

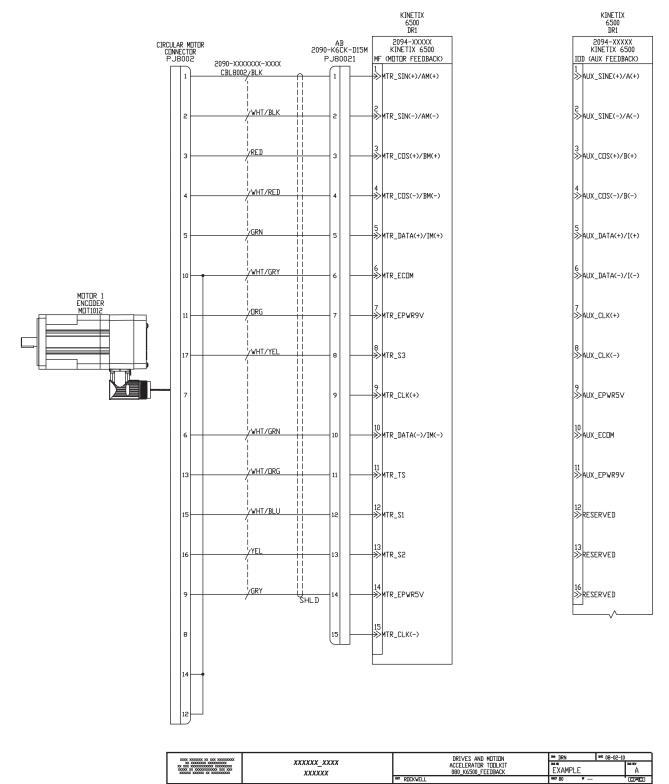
Additional I/O library drawings, used for the Widg-O-matic machine example, are available from the Drives and Motion Accelerator toolkit DVD. These drawings represent a sample of drive and controller I/O drawings.

#### Additional I/O Library Drawing Examples

I/O Library Drawings	File Name	Page	
Kinetix 6500 Drive Safety I/O	070_K6500_Safety_I0.dwg	<u>58</u>	
Kinetix 6500 Drive Feedback	080_K6500_Feedback.dwg	<u>59</u>	
ControlLogix Controller Digital Inputs	090_CLX_Digital_Inputs.dwg	<u>60</u>	

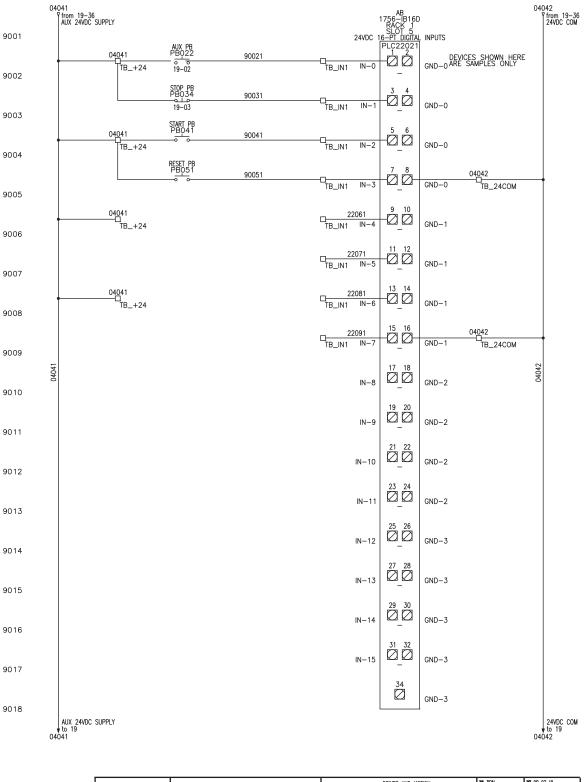
#### Kinetix 6500 Safety I/O





#### **Kinetix 6500 Feedback**

#### **ControlLogix Digital Inputs**



X00X X00000X XX X0X X0000000X		DRIVES AND MOTION	M DRN	WE 08-02-10	
XXX X0000000X XXX X0000000X XXX X00000000	xxxxxx_xxx xxxxxx	ACCELERATOR TOOLKIT 090_CLX_DIGITAL_INPUTS	EXAMPLE		A
		ONET ROCKWELL	seer 90 sr		

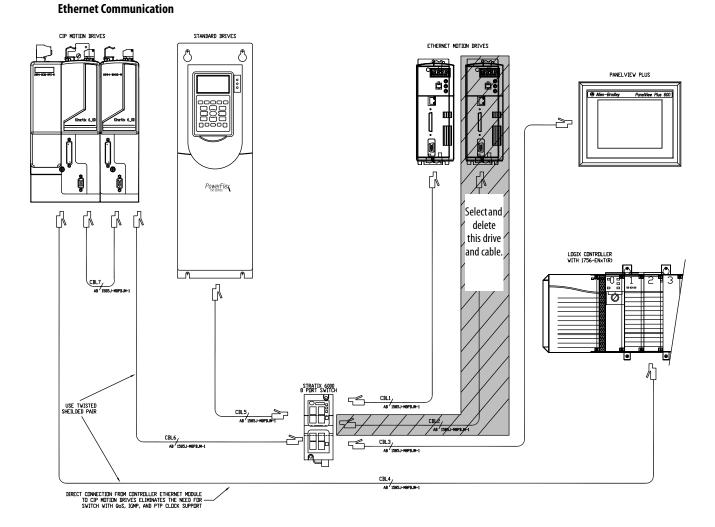
# **Edit System Communication Drawings**

1. Open the communication drawing for your application.

For the Widg-O-matic machine application example, the 060\_120\_Ethernet\_Communication.dwg file is opened.

2. Delete network devices not used in the project.

For the Widg-O-matic machine application example, one of the Kinetix 300 drives and associated cable is deleted.

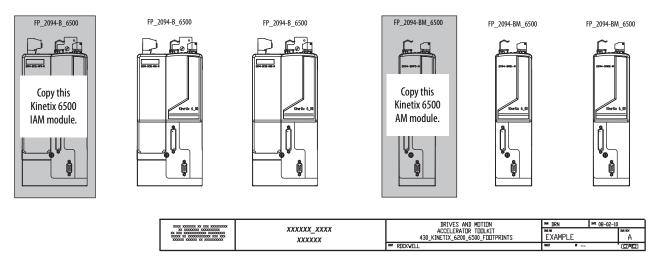


X00X X00000X XX X0X X0000000X		DRIVES HIND HUTIUN	M DRN	WE 08-02-10	
XX X000000X X0000000X X0000000X XX XXX X	xxxxxx_xxx xxxxxx	ACCELERATOR TOOLKIT 120_ETHERNET_COMMUNICATION	EXAMPLE		A
		our RDCKWELL	atti 0		CAD

- 3. Add any network device footprints required for your application.
  - a. Navigate to and open the required footprint drawings that were added to your Project Drawings folder from the toolkit library.
  - b. Copy device footprints from the footprint drawings.

In this example, Kinetix 6500 IAM and AM module footprints are copied.

#### Kinetix 6200/6500 Footprint Drawings



- c. Paste the device footprints onto your communication drawing.
- d. Re-route or copy cables on the communication drawings to the added devices.

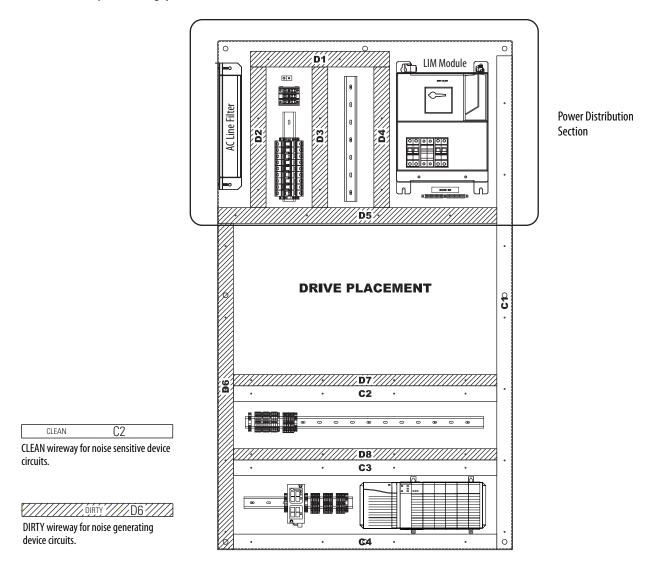
## **Edit System Layout Drawings**

1. Open the panel layout drawing for your application.

For the Widg-O-matic machine application example, the 150\_CLX\_w\_LIM\_Sm\_Panel\_Layout.dwg file is opened.

The panel layout includes a power distribution, drives, and control section. The panel is designed to accommodate best-practice techniques used to minimize electrical noise. Refer to the System Design for Control of Electrical Noise Reference Manual, publication <u>GMC-RM001</u>.

#### Small Panel Layout Drawing (power distribution)

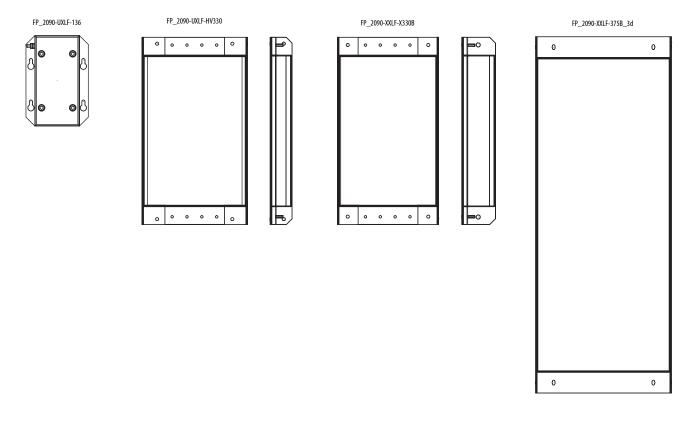


XXXX XXXXXXX XXX XXX XXXXXXXXXXXXXXXXX		DRIVES AND MOTION	IM DRN	₩E 08-02-10	
X000000X XX X000000X XXX X000000X X0000000X XXX X0000000X XXX X000 X0000000X XXX X0000000X XXX X0000000X	xxxxxx_xxx xxxxxx	ACCELERATOR TOOLKIT 150_CLX_W_LIM_SM_PANEL_LAYOUT	EXAMPLE		A
		ONT RECKWELL	sex 20 #	' (	

- 2. Replace or add power components to your panel layout drawing.
  - a. Inspect power section on layout drawing for proper component footprints for the project.
  - b. Open the associated power footprint drawings that were added to your project drawings from the toolkit library.

In this example, the 510\_Line\_Filter\_Footprints.dwg file is opened.

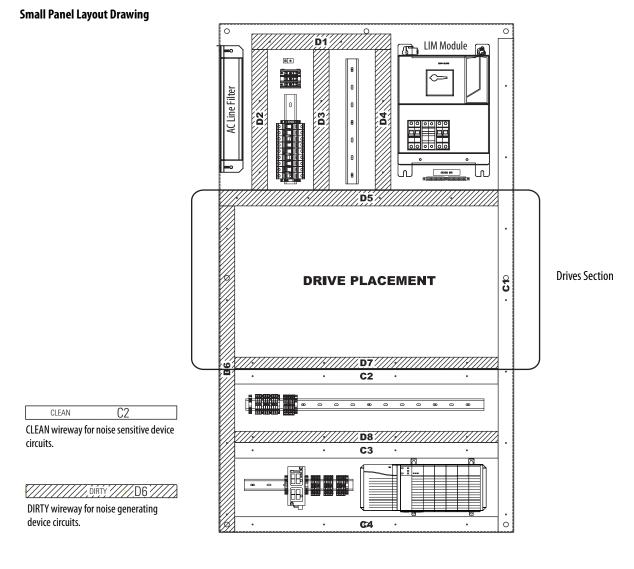




XXXXXX X ACCELERATOR TOOLKIT MIT XXXXXXX XXXXX S10_LINE_FILTER_FOOTPRINTS EXAMPLE	A
off RDCKVELL bit #	

- c. If the desired component is not represented in the current panel layout drawing, copy the proper component footprint from the footprint drawings.
- d. Delete the current component in the panel layout drawing and paste the desired component footprint into its place.
- e. Add any other required power components for your system.

- 3. Insert drives into the Drives Placement section.
  - a. Open the panel layout drawing for your application.



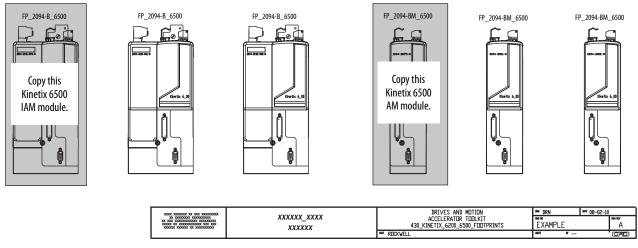
X00X X00000X XX X0X X0000000X		DRIVES AND MOTION	M DRN	ME 08-02-10	
XX X000000X XX X0000000X XX XXX X00000000	xxxxxx_xxx xxxxxx	ACCELERATOR TOOLKIT 150_CLX_W_LIM_SM_PANEL_LAYOUT	EXAMPLE		A
		ONET ROCKWELL	нет 20 и		

b. Open the associated drives footprint drawings that were added to your project drawings from the toolkit library.

For the Widg-O-matic machine application example, the 430\_Kinetix\_6200\_6500\_Footprints.dwg file is opened.

c. Copy the desired drive components from the footprint drawings for your panel layout drawing.

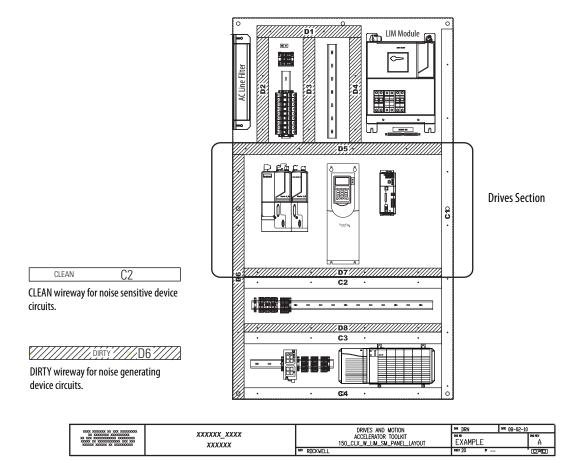
#### Kinetix 6200/6500 Drive Footprint Drawings



d. Paste the drive footprints onto the panel layout drawing.

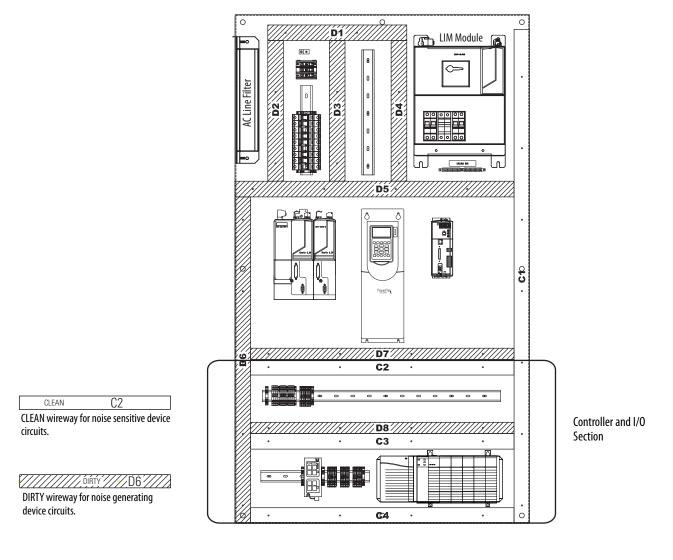
For the Widg-O-matic machine application example, two Kinetix 6500 servo drives, one PowerFlex 753 drive, and one Kinetix 300 drive was added to the layout drawing.

#### Small Panel Layout Drawing (drive placement)



- 4. Inspect control section for required control components and proper footprints.
  - a. Open the panel layout drawing for your application.

#### Small Panel Layout Drawing (control)



X000 X000000X XX X00X X00000000X		DRIVES AND MOTION	M DRN	MT 08-02-10	
XX X000000X XX X000000X XXX X00000000X XXXXXXXX	XXXXXX_XXXX XXXXXX	ACCELERATOR TOOLKIT 150_CLX_W_LIM_SM_PANEL_LAYOUT	EXAMPLE		A
		ast RDCKWELL	aeer 20 ar		

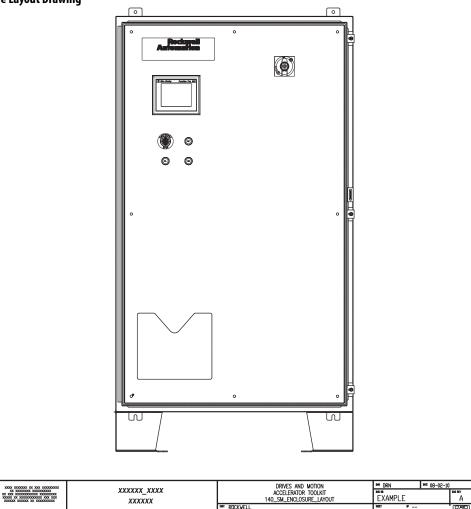
- b. Inspect controller for required processor, I/O chassis, and I/O and communication modules, and add footprints from the standard library as required.
- c. Add any other required control components for your system.

5. Edit your Enclosure Layout Drawing.

a. Open the enclosure layout drawing for your application.

For the Widg-O-matic machine application example, the 140\_SM\_Enclosure\_Layout.dwg file is opened.

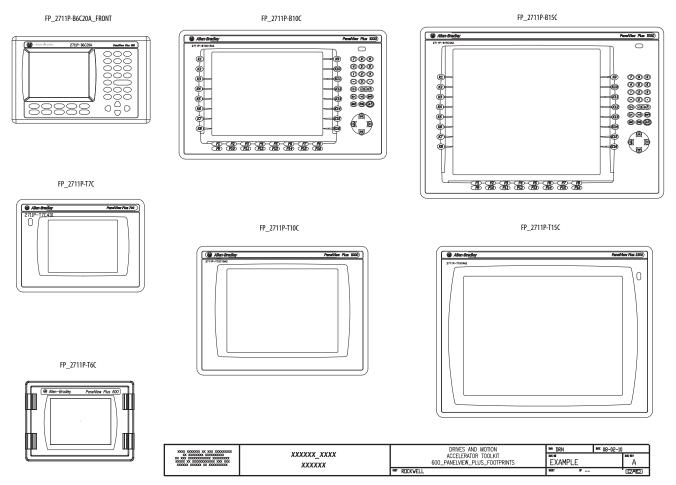
Small Enclosure Layout Drawing



- b. Inspect the drawing for operator equipment required for your system.
- c. Open the associated enclosure footprint drawings that were added to your project drawings from the toolkit library.

For the Widg-O-matic machine application example, the 600\_PanelView\_Plus\_Footprints.dwg file is opened.

#### **PanelView Plus Footprint Drawings**



- d. Copy the desired enclosure components from the footprint drawings for your enclosure layout drawing.
- e. Paste the enclosure component footprints onto your panel layout drawing.
- f. Add any other required enclosure components for your system.

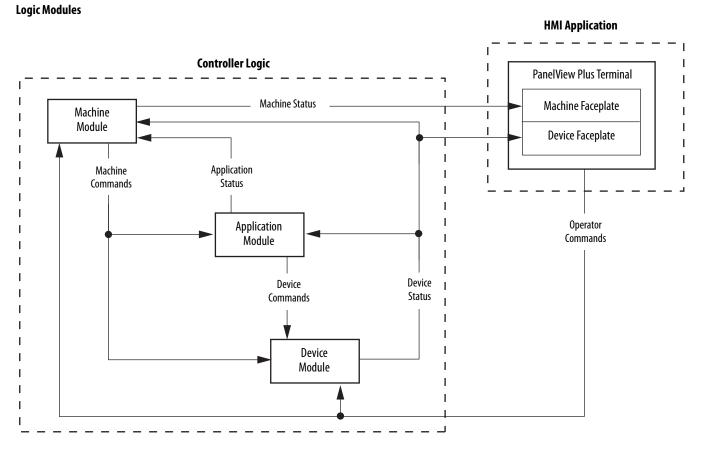
## Notes:

# **Logic Configuration**

In this chapter you edit the preconfigured logic file that the DMAT Wizard created for your specific application.

Besides initial controller, network, and device configurations, the preconfigured logic file includes machine, application, and device logic modules that significantly speed-up your application logic development. In addition, the logic modules include control, status, and diagnostic code that provides information to preconfigured operator interface faceplates that you can run on personal computers or PanelViewPlus terminals.

If you chose not to use the DMAT Wizard or desire to add or edit controller, networks, or drives since the DMAT Wizard was executed, refer to instructions in <u>Appendix G</u> before executing the steps in this chapter.



The machine module provides a state machine model that coordinates multiple devices and application logic for coordinated drives and motion applications. It provides overall machine commands, for example, start, stop, abort, clear, and reset to the application modules and the individual device modules based on the status of the applications and devices.

The application modules execute the machine commands and provide the more specific application commands to the drives and devices. It also coordinates the machine and application status, and executes the application fault commands. In addition, the toolkit includes motion logic examples to help you create your specific application logic.

The device modules translate the uniform machine and application commands and provide uniform status and diagnostics from the very specific device tags and parameters. This reduces much of the non-inventive code required to control and monitor the many unique devices.

For more information on the machine, application, and device logic modules, refer to <u>Appendix A</u> on <u>page 225</u>.

To assist you in understanding how to best use the preconfigured logic files, the Widg-O-matic machine application is used as an example in all of the logic configuration steps.

Module Type	File Names
Machine	Machine_Module
Machine	Device&Application_Status
	Application_Module
Application	Motion_Simple_Move
Application	PF_Run_Spd
	K300_EIPMove
	CIPMotion_Drive_Module
Device	PF753_Drive_Module
	K300_Drive_Module

Preconfigured Logic Modules Used in Widg-O-matic Example

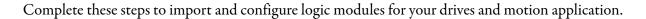
# **Before You Begin**

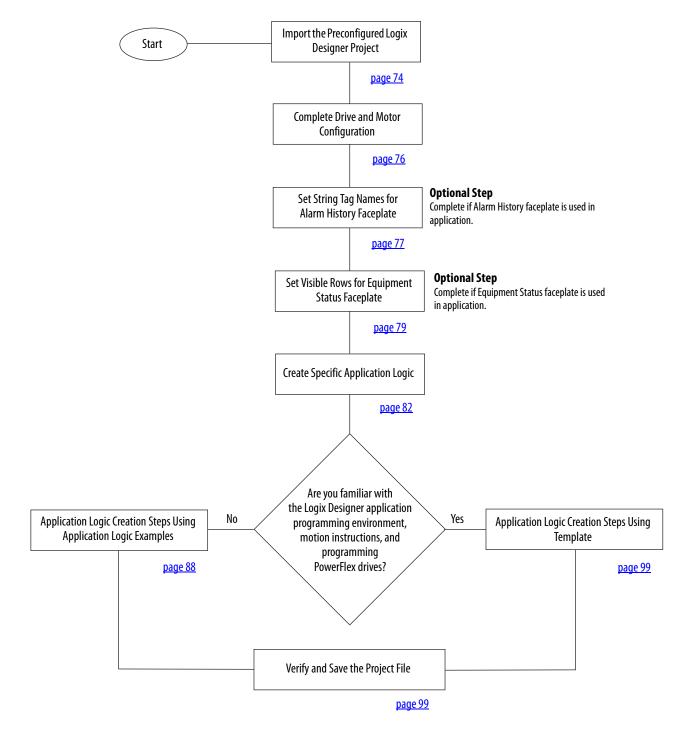
Run the DMAT Wizard (refer to <u>Chapter 1</u>) or complete <u>Appendix G</u>.

# What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative
- RSLogix 5000 software, version 19.0 or later, or the Logix Designer application, version 21.0 or later.
- RSLogix 5000 software, version 20.0 or later or the Logix Designer application, version 21.0 or later, to configure Kinetix 350 servo drives, and when using ControlLogix 1756-L7*x*S controllers.
- The user manual for your Drives and Motion hardware. Refer to <u>Additional Resources</u> on <u>page 15</u> for publication numbers.

# **Follow These Steps**





# **Import the Preconfigured Logix Designer Project**

Follow these steps to open the preconfigured RSLogix 5000 or Studio 5000 Logix Designer project. This procedure is written for the Logix Designer application, but RSLogix 5000 software is similar.

1. From the Start menu, launch the Studio 5000 Logix Designer application.

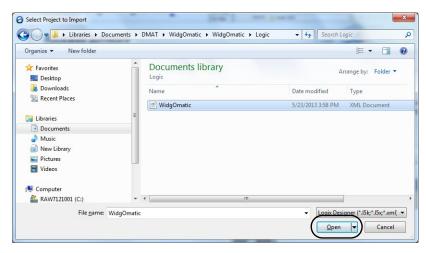


The Studio 5000° dialog box opens.

2. Under the Create menu, click From Import.



3. Navigate to the Logic directory within the DMAT project.

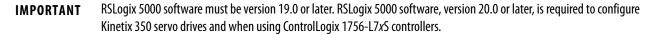


If the Drives and Motion Accelerator Toolkit was installed in the default directory you will find the XML file in: C:\Documents and Settings\My Documents\DMAT\*ProjectName\MachineName*.

For the Widg-O-matic example, the path is: C:\Program Files\RA\_Simplification\DMAT\D-Wizard\WidgOmatic\WidgOmatic\Logic.

- 4. Select the logic xml file and Click Open.
- **5.** From the Revision pull-down menu, choose the version of RSLogix 5000 software, versions 18, 19, or 20, or the Logix Designer application, version 21 or later, to import into.

Look in:	📙 Projects	•	G 🦸 📂 🛄 -			
(Ala)	Name	*	Date modified	Туре	Size	
Recent Places		This f	older is empty.			
Computer						
	•	1980 (1991) (1991)	III		· ·	
		WidgOmatic		•	Import	Revision
(i) Network	File name:					E 101
(interview Network	Files of type:	Logix Designer Project Files (*.ACD)		•	Cancel	From: 18.1
Network Revision		Logix Designer Project Files (*.ACD)		•	Help	To: 1

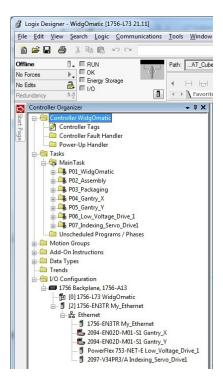


6. Click Import to save and open the project as an ACD file.

After the import process is complete, the project opens and the controller organizer displays all of the preconfigured project components including the controller, network, device configurations, the preconfigured logic program files, and the faceplate and control AOI files.

From this point on, you complete the logic module configuration for your specific drives and motion application guided by the remaining sections of this chapter.

To gain a complete understanding of the preconfigured project organization and logic refer to <u>Appendix A</u> on <u>page 225</u>.



# **Complete Drive and Motor Configuration**

The DMAT Wizard uses default values for module properties (creating your axes) and axis properties (configuring your axes). When your application requires modifications to these fields, refer to the appropriate steps in <u>Appendix G</u>.

Procedure	Go To	Do This
Complete CIP motion drive module configuration	<u>step 19</u> on <u>page 320</u>	Calculate and enter a value for the Bus Capacitance field.
Complete CIP motion axis properties	step 8 on page 324	Review the Scaling, Load, and Actions categories. Make changes, if necessary.
Complete sercos drive module configuration	<u>step 13</u> on <u>page 328</u>	Calculate and enter a value for the Additional Bus Capacitance field.
Complete sercos drive axis properties	step 8 on page 330	Review the Motor Feedback, Units, Conversion, and Fault Actions tabs. Make changes, if necessary.

## **Setting Drive Motor Ratings**

You must manually change the motor series and motor type for each axis imported into your Logix Designer project file. The DMAT Wizard Logix Designer import file sets all drive motor type selections to Rotary, MPL, and to the largest available power rating as default. This is true even if you change the motor series and type in the DMAT Wizard. Those selections are reflected in the BOM only.

X Axis Properties - Gantry X Ax

Follow these steps to edit the Drive/Motor tab.

 Under My\_MotionGroup in the Controller Organizer, double-click the Servo\_Drive\_x\_Axis.



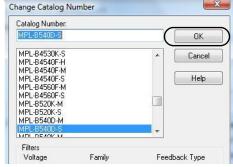
In the WidgOmatic example, Gantry\_X\_Axis was selected.

- 2. In the Axis Properties window, select Motor in the Categories tree.
- 3. Click Change Catalog.

- General	Motor Device Sp	ecification				
Motor Model	Data Source:	Catalog Number	•		Parameters	
-MotorFeedback -Scaling	Catalog Number:	MPL-8540D-S	(	Change Catalog		
- Hookup Tests	Motor Type:	Rotary Permane	nt Magnet 🛛 👻	$\square$		
– Polarity – Autotune	Units:	Rev	*			
Load	Nameplate / Dat	tasheet - Phase	to Phase paramete	rs		
Backlash Compliance	Rated Power:	3.43	k₩	Pole Count:	8	
Friction	Rated Voltage:	460.0	Volts (RMS)			
- Position Loop - Velocity Loop	Rated Speed:	2000.0	BPM	Max Speed:	2000.0	RPM
- Acceleration Loop	Rated Current:	7.42	Amps (RMS)	Peak Current	16.26	Amps (RMS)
- Torque/Current Loop - Planner	Rated Torque:	19.4	N-m	Motor Overload Limit:	100.0	% Rated

The Change Catalog Number dialog box opens.

- 4. Scroll though the available catalog numbers and select the desired motor catalog number for your actual hardware configuration.
- 5. Click OK.
- 6. Repeat for each axis configured in My\_MotionGroup.



# Set String Tag Names for Alarm History Faceplate

If you plan to use the Alarm History faceplate with your HMI application, follow these steps to set the application and device string tag names to match your application and device module names. These string names are used within the alarm messages indicating the device or application origin of the alarm.

1. Expand the Controller folder in your Controller Organizer and double-click Controller Tags.

The controller tags open in the workspace.

Controller Organizer - 4 >	Scope: 🛅 WidgOmatic 💽 Show: 🗚	ll Tags			🔽 🔽 Enter Name Fi
Controller Tags	Name IB A	Value 🔶	Force Mask 🛛 🔦	Style	Data Type
Controller Fault Handler	-Assembly	{}	{}		(UDT_AppStatus)
Power-Up Handler	Assembly.OK	1		Decimal	BOOL
🗄 🖂 Tasks	Assembly.Ready	1		Decimal	BOOL
🖻 🤯 MainTask	Assembly.Reset	0		Decimal	BOOL
E B P02_Assembly	Assembly.Running	0		Decimal	BOOL
🗄 🕞 PO3_Packaging	Assembly.Stopped	1		Decimal	BOOL
🕀 🕞 P04_Gantry_X_Drive	Assembly.Name	·Application'	{}		STRING

2. Expand one of your application status tags (UDT\_AppStatus) and/or module status tags (UDT\_ModuleStatus) and select the value field of the string tag named XXX.Name.

For the Widg-O-matic application example, the Assembly tag (UDT\_AppStatus data type) is expanded and the Assembly.Name string tag value field is selected.

**3.** Click .

The String Browser dialog box opens.

**4.** Type the name of the associated application or device module.

This string name is used within the alarm history messages providing the fault origin.

👫 String Browser - Asser \$\$ Assembly \$' \$L \$N \$P \$R \$T ΟK Cancel Apply Help ♀ 0 Error(s) 8 INS 8 of 82

5. Click OK.

The string tag value field updates with the name you typed in. For the Widg-O-matic application example, the value is Assembly.

Controller Organizer VI	Scope. My wildoniatic . Subw.	All Tags			Y. Enter Name I
Controller Tags	Name ==	🛆 Value 🔶 🍝	Force Mask 🔶	Style	Data Type
Controller Fault Handler	-Assembly	{}	{}		(UDT_AppStatus)
Power-Up Handler	Assembly.OK	1		Decimal	BOOL
🖻 🕂 🔂 Tasks	Assembly.Ready	1		Decimal	BOOL
🖻 🤕 MainTask 🕀 📴 P01_WidgOmatic	Assembly.Reset	0		Decimal	BOOL
⊕	Assembly.Running	0		Decimal	BOOL
⊕ 🕞 P03_Packaging	Assembly.Stopped			Decimal	BOOL
🕀 🚔 P04_Gantry_X_Drive	Name     28       Assembly     Assembly.OK       Assembly.Ready     Assembly.Ready       Assembly.Reset     Assembly.Reset       Assembly.Stopped     Example.Stopped	···· ('Assembly'	) ()		STRING

6. Repeat <u>step 1</u> through <u>step 5</u> for each application status (UDT\_AppStatus) tag and device status (UDT\_ModuleStatus) tag within the Controller Tags of your project.

For the Widg-O-matic application example, these application and device string tag names were entered.

Packaging

🖃 😁 🔄 Controller WidgOmatic		All Tags			
Controller Tags	Name IB	🛆 Value 🛛 🤸	Force Mask 🛛 🔦	Style	Data Type
Controller Fault Handler	-Packaging	{}	{}		UDT_AppStatus
Power-Up Handler	Packaging.0K	1		Decimal	BOOL
🖻 🔚 Tasks	Packaging.Ready	1		Decimal	BOOL
🖻 🤯 MainTask 🕀 🕞 P01 WidgOmatic	Name     ::::::::::::::::::::::::::::::::::::	0		Decimal	BOOL
P02_Assembly	Packaging.Running	0		Decimal	BOOL
🕀 🕞 P03_Packaging	Packaging.Stopped	1		Decimal	BOOL
🕀 🕞 P04_Gantry_X_Drive	+ Packaging.Name	Packaging'	<b>)</b> {}		STRING

### Conveyor\_Drive

Controller Organizer - 4 ×	Scope: 🛅 WidgOmatic 💌 Show: 🗚	ul Tags			▼ Y. Ente
Controller WidgOmatic     Controller Tags	Name IB 4	Value 🔶	Force Mask 🔶	Style	Data Type
Controller Fault Handler	Name         Image: Conveyor_Drive           Image: Conveyor_Drive Aborted         Image: Conveyor_Drive Aborted           Image: Conveyor_Drive Active         Image: Conveyor_Drive Reset           Image: Conveyor_Drive Reset         Image: Conveyor_Drive Reset	{}	{}		(UDT_ModuleStatus)
Power-Up Handler	Conveyor_Drive.Aborted	0		Decimal	BOOL
🖻 😋 Tasks	Conveyor_Drive.Active	0		Decimal	BOOL
⊡ G Main Lask ⊕ G P01 WidgOmatic	Conveyor_Drive.Reset	0		Decimal	BOOL
E B PO2_Assembly	Conveyor_Drive.OK	1		Decimal	BOOL
🕀 🕞 PO3_Packaging	Conveyor_Drive.Ready	1		Decimal	BOOL
🕀 🕞 P04_Gantry_X_Drive	Conveyor_Drive.SLSReq	0		Decimal	BOOL
P05_Gantry_Y_Drive	Conveyor_Drive.Name	'Conveyor Drive'	) ()		STRING

### Diverter\_Drive

Controller Organizer - 4 >	Scope. In widgomatic Show, A	ll Tags			<ul> <li>▼, En</li> </ul>
	Name     = biverter_Drive       Diverter_Drive.Aborted     Diverter_Drive.Active       Diverter_Drive.Active     Diverter_Drive.Reset       Diverter_Drive.NCK     Diverter_Drive.NE       Diverter_Drive.NE     Diverter_Drive.SLSReq	Value 🔶	Force Mask 🗧 🗧	Style	Data Type
Controller Fault Handler	-Diverter_Drive	{}	{}		(UDT_ModuleStatus)
Power-Up Handler	Diverter_Drive.Aborted	0		Decimal	BOOL
E-G Tasks	Diverter_Drive.Active	0		Decimal	BOOL
🖻 🧔 MainTask 🕀 🕞 P01_WidgOmatic	Diverter_Drive.Reset	0		Decimal	BOOL
⊕	Diverter_Drive.OK	1		Decimal	BOOL
🕀 🕞 P03_Packaging	Diverter_Drive.Ready	0		Decimal	BOOL
🕀 🕞 P04_Gantry_X_Drive	Diverter_Drive.SLSReq	0		Decimal	BOOL
P05_Gantry_Y_Drive		'Diverter Drive'	) ()		STRING

### Gantry\_X\_Drive

Controller Organizer 🗾 🗸 🕂 🗙	Scope: 🛐 WidgOmatic 🔻 Sh	ow: All Tags			▼ ¶. Enter/
Controller WidgOmatic     Controller Tags	Name II A	Value 🔶	Force Mask 🔶 🗲	Style	Data Type
Controller Fault Handler	Name     □□       □     Gantry_X_Drive       □     Gantry_X_Drive.Aborted       □     Gantry_X_Drive.Ative       □     Gantry_X_Drive.Ative       □     Gantry_X_Drive.Reset       □     Gantry_X_Drive.OK       □     Gantry_X_Drive.Reset	] {}	{}		(UDT_ModuleStatus)
Power-Up Handler	Gantry_X_Drive.Aborted	0		Decimal	BOOL
🖻 😁 Tasks	Gantry_X_Drive.Active	0		Decimal	BOOL
🖻 🤯 MainTask 🗊 🕞 P01_WidgOmatic	Gantry_X_Drive.Reset	0		Decimal	BOOL
	Gantry_X_Drive.0K	1		Decimal	BOOL
DO3_Packaging	Gantry_X_Drive.Ready	0		Decimal	BOOL
P04_Gantry_X_Drive	Gantry_X_Drive.SLSReq	0		Decimal	BOOL
B B P05_Gantry_Y_Drive     B B P06_Conveyor_Drive	Gantry_X_Drive.Name	('Gantry X Axis Drive'	) {}		STRING

### Gantry\_Y\_Drive

Controller Organizer 🚽 🗸 🖓	Scope: 🗊 WidgOmatic 💌 Sho	w: All Tags			▼ 7. En
Controller WidgOmatic	Name ISA	Value 🔶	Force Mask 🔶	Style	Data Type
Controller Fault Handler	Gantry_X_Drive	{}	{}		(UDT_ModuleStatus)
Power-Up Handler	Gantry_X_Drive.Aborted	0		Decimal	BOOL
🖻 📇 Tasks	Gantry_X_Drive.Active	0		Decimal	BOOL
🖻 🤯 MainTask 🔄 📴 1981 WidgOmatic	Gantry_X_Drive.Reset	0		Decimal	BOOL
PO1_widgomatic     Po1_widgomatic	Gantry_X_Drive.0K	1		Decimal	BOOL
🗄 🕞 P03_Packaging	Gantry_X_Drive.Ready	0		Decimal	BOOL
🕀 🕞 P04_Gantry_X_Drive	Gantry_X_Drive.SLSReq	0		Decimal	BOOL
P05_Gantry_Y_Drive     P06_Conveyor_Drive	Gantry_X_Drive.Name	('Gantry X Axis Drive'	) ()		STRING

# Set Visible Rows for Equipment Status Faceplate

If you plan to use the Equipment Status faceplate with your HMI application, follow these steps to set the Inp\_NumRowsVis tag value within the faceplate AOI of the device you intend to place in the first row.

1. Determine how many of the nine available rows you will use in the Equipment Status faceplate.

Refer to <u>Chapter 5</u> beginning on <u>page 101</u> for an overview of the faceplate so you can determine how many status rows you require and what device you would like to place in the first row.

For the Widg-O-matic application example, all four devices are included in the Equipment Status faceplate, with the Gantry X Axis placed in the first row.

- Gantry X Axis
- Gantry Y Axis
- Conveyor
- Diverter
- 2. Open the R02\_Monitor routine for the device located in the first row of the Equipment Status faceplate and navigate to the device specific faceplate AOI.

Controller Organizer	× 固	
Controller Tags Controller Fault Handler Power-Up Handler		CIP MOTION FACEPLATE ADD-ON INSTRUCTION This AOI interacts with the CIP Motion Drive Faceplate (HMI) and also generates the Error Code displayed by the Alarm History screen.
Tasks     MainTask     Agen1_WidpOmatic     Appl_Assembly      Appl_Assembly	10	CIP Motion Axis FT/Vew ME Faceplate CIP Faceplate CIP faceplate_AOI CIP Motion Axis FT/Vew ME Faceplate CIP_Faceplate_AOI Ref_Motion/Forup Motion_Group Ref_CIPAxis Ref_CIPAxis Servo_Axis Contry_X_Axis_CIT Inp_OperMode Servo_Cht Status Operator <contry_x_axis_cit operator<br="" status="">0 e</contry_x_axis_cit>

For the Widg-O-matic application example, the R04\_Monitor routine in the P04\_Gantry\_X\_Drive program was opened.

- 3. Click 🛄 (View Configuration Dialog) to open the AOI properties.
- 4. Navigate to the Inp\_NumRowsVis tag and select the Value.
- 5. Enter the number of devices you determined in <u>step 1</u>.

For the Widg-O-matic application example, 4 was entered.

**6.** Click OK to close AOI properties and complete the update.

0	Vis	Name	Argument	Value	Data Type	Description 🔺
L	Г	EnableIn		1	BOOL	Enable Input
D	Г	EnableOut		1	BOOL	Enable Output
0	V	+-Ref_MotionGroup	Motion_Group(P)	{}	MOTION_GROUP	
0	V	⊞-Ref_CIPAxis	Servo_Axis(P)	{}	AXIS_CIP_DRIVE	
1	<b>v</b>	Inp_OperMode		0	BOOL	
*	Г(	⊞Inp_NumRowsVis		• 4	DINT	
	Г	∃-Set_FaceplateAni		0	INT	
1	Г			0	INT	
D		Sts_Faulted		0	BOOL	-
•[						•
19	Sort P	arameters			Insert In	struction Defaults
					Insert D	efinition Defaults
					Save In	struction Defaults

## Set Visible Rows for Equipment Status Faceplate for Energy Monitoring

If you plan to use the Equipment Status faceplate with Energy Monitoring in your HMI application, follow these steps to set the Inp\_NumRowsVis tag value within the energy object AOI of the device you intend to place in the first row.

1. Determine how many of the nine available rows you will use in the Equipment Status faceplate for Energy.

Refer to <u>Chapter 5</u> on <u>page 145</u> for an overview of the faceplate so you can determine how many status rows you require and what device you would like to place in the first row.

2. Open the controller tags and expand the energy object tag for the device located in the first row of the Equipment Status faceplate for Energy (DriveName\_BEO).

- PF753_BE0	{}
+ PF753_BE0.Inp_NumRowsVis	5
+ PF753_BEU.Val_EnergyResourceType	1
+ PF753_BE0.Val_BaseEnergyObjCap	0
+ PF753_BE0.Val_EnergyAccuracy	0
+ PF753_BE0.Val_ConsEnergyOdo	{}
+ PF753_BE0.Val_GenEnergyOdo	{}
+ PF753_BE0.Val_TotalEnergyOdo	{}
PF753_BEO.Val_EnergyTransferRate	0.0
PF753_BE0.Val_ConsEnergyReal	0.0
	0.0

3. Enter the number of required rows as the tag value for the Inp\_NumRowsVis attribute.

In this example, the number of required rows is 5.

**IMPORTANT** You must use the device module routines with energy support if you plan to use the equipment status faceplate for energy monitoring.

## Set MSG Path in the E3 Plus Energy Monitoring Routine

If the device modules with energy monitoring are used, an additional routine is included in the device program named R05\_Energy. This routine gathers the energy data and energy related status and stores the data in the base energy object tag (UDT\_BEO).

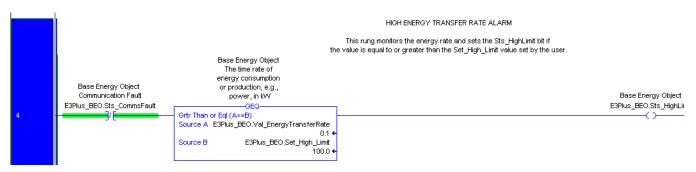
Rung 2 of the energy routine includes at least one explicit message for getting energy attributes from the device (some devices require more than one explicit message). The path for each MSG instruction is configured on import of the device module. However, for E3 Plus device modules, the path must be configured to include the port number of the 193-DNENCAT device (3) and the node address of the E3 Plus overload relay.

Follow these steps to configure the path for your E3 Plus device:

- 1. Click the ellipse button on the MSG instruction in rung 2 to launch the Message Configuration dialog box.
- 2. Click the Communication tab.
- **3.** Add the 193-DNENCAT port number and your E3 Plus node address to your path configuration in the following format: \_DeviceName, 3, #.
- 4. Click OK.

	Explicit messaging is used to gather ene	OET ENERGY DATA	y Object. The Base Energy Object provide	s a standard format for reporting energy metering results
2	Base Energy Object Exploit Message Timer E3Plus_BEO Timer_Msg.DN	Message Configuration - E3Plus_BEOmsg_Get_Status_Object       E         Configuration       Communication* Tag <ul> <li>Path:</li> <li>E3PLUS, 3.5</li> <li>Browse</li> <li>E3PLUS, 3.5</li> <li>Broadcast:</li> <li>Communication Method</li> <li>O P OH+ Channet</li> <li>Cip With Source Link:</li> <li>D estimation Node:</li> <li>O Connected</li> <li>Cache Connections</li> <li>Connected</li> </ul>	Message Control Message Control Message Control Base Energy Object The energy capabilities of the device. 0 = Energy Messured, 1 = Energy Prox, 3 = Energy Prox, 3 = Energy Aggregated, 4 = Energy Refe Fixed MOV 0	MSO E3Plus_BEOmsg_Cet_Status_Object (CN) Base Energy Object Specifies the accuracy of power and energy metring results. MOV Move Source 0
		C Enable Enable Enable Enable Extended Error Code: Timed Dut * Error Fait:  OK Cancel Apply Help	Nus_BEO.Val_BaseEnergyObjCap 0 + Base Energy Object The consumed energy value in KWh	Dest E3Plus_BEO.Val_EnergyAccuracy 0.● Base Energy Object The consumed energy value in WM

Rung 4 of the energy routine monitors the energy rate and sets a status bit if the value exceeds the high alarm limit. The high-alarm limit default setting is 100. Configure this value to set the kW high-alarm limit for your device.



# **Create Specific Application Logic**

Now that you have imported and configured all of the machine, application, and device modules, you can begin creating the specific application logic for your machine. You create your application logic within the R10\_ApplicationCode routine of the application module. There are two methods for creating specific application logic for your machine.

The first method involves selecting and importing preprogrammed logic examples into the Application Code routine. These logic examples help familiarize less experienced users with the basics behind motion instructions and/or controlling PowerFlex drives via their add-on profiles. These preprogrammed logic examples are designed to work seamlessly with the application module and can help further reduce programming time.

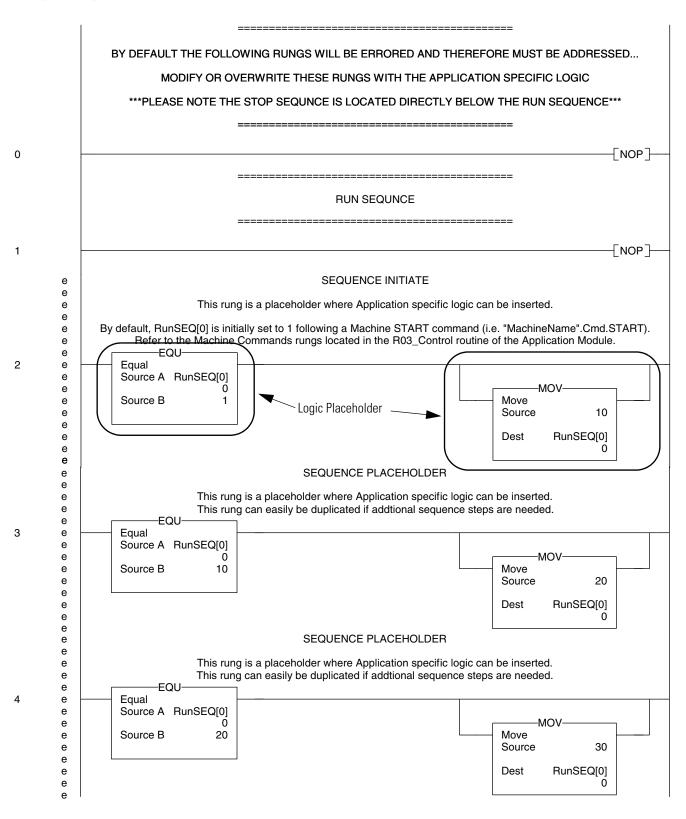
The second method provides a blank template with placeholders if you choose to write your application-specific logic from scratch. This method is recommended for users who feel comfortable with the Studio 5000 Logix Designer programming environment and who also have experience with motion instructions and/or controlling PowerFlex drives via their add-on profiles.

## **Application Code Logic Template Overview**

To assist you in creating specific-application logic that interfaces with the preconfigured machine, application, and device modules, a logic template is included in the R10\_ApplicationCode routine of the application module. It includes placeholders for both run and stop sequences. All of the application logic examples also follow this same template.

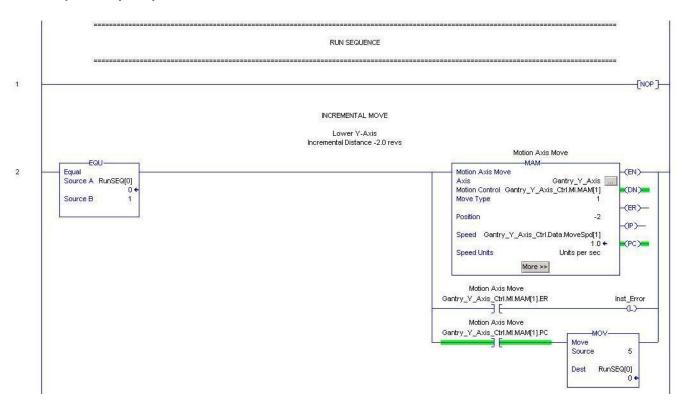
**IMPORTANT** Program the stop sequence to make sure all active devices are properly stopped.

#### **Run Sequence Template**



The run sequence is initiated by a machine START command via the start logic in the R03\_Control routine of the application module. By default, the run sequence is initiated by placing a value of 1 in the RunSEQ[0] tag. When the RunSEQ[0] tag is set to 1, the first step in the run sequence is executed, starting the run sequence. Each of the rungs in the run sequence provides a placeholder where you can insert application-specific step logic. The Run-sequence logic may include, for example, motion instructions, drive commands, and/or other conditional diagnostic logic.

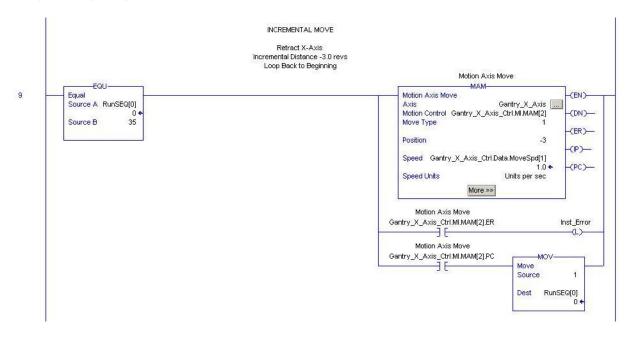
The move (MOV) instruction is a placeholder to advance the run sequence to the next step by incrementing the RunSEQ[0] tag. Each step in the run sequence requires a unique value assigned in ascending order. The steps typically increase by multiples of five or ten. By default, the run-sequence template steps 1...10...20...30, and so on. Before moving to the next step, a predetermined condition must normally be met to make sure the current step is complete.



### **First Run Sequential Step Example**

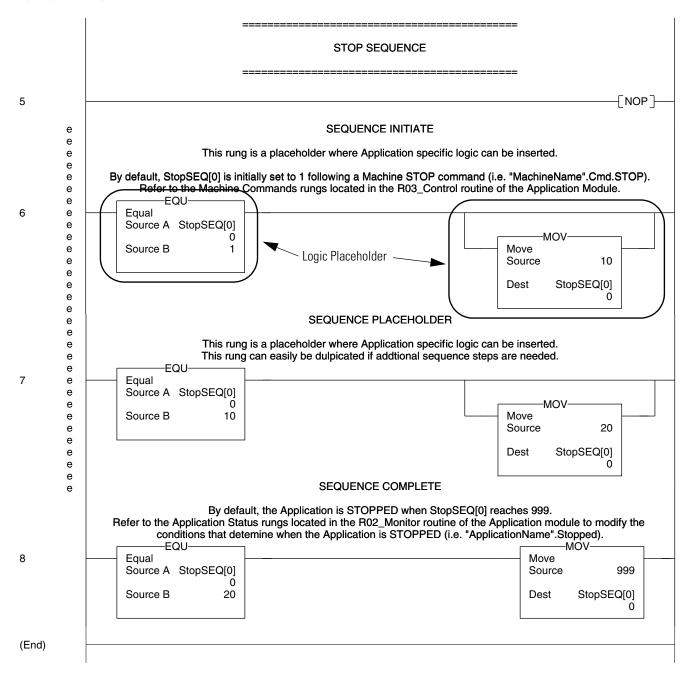
This Widg-O-matic application code first-run step (RunSEQ[0] = 1) example includes a motion axis move (MAM) instruction, an instruction error detection check, and an process complete (PC) check. Before the MOV instruction indexes to the next sequence step (for example, value 5 into RunSEQ[0] tag), the PC check must be met indicating that the move is complete. The instruction error detection check is used to detect a module fault in the application, preventing the run sequence from inadvertently hanging on a step.

#### **Final Run Sequential Step Example**



Much like the first run-step example rung, this Widg-O-matic final run step example also includes a motion axis move (MAM) instruction, an instruction error detection check, and an process complete (PC) check. The only difference is that the PC bit is used to reset the RunSEQ[0] tag back to a value of 1, which repeats the motion sequential steps for continuous operation. If continuous operation is not required, the final step could just simply end the Run Sequence or just remain at this step indefinitely.

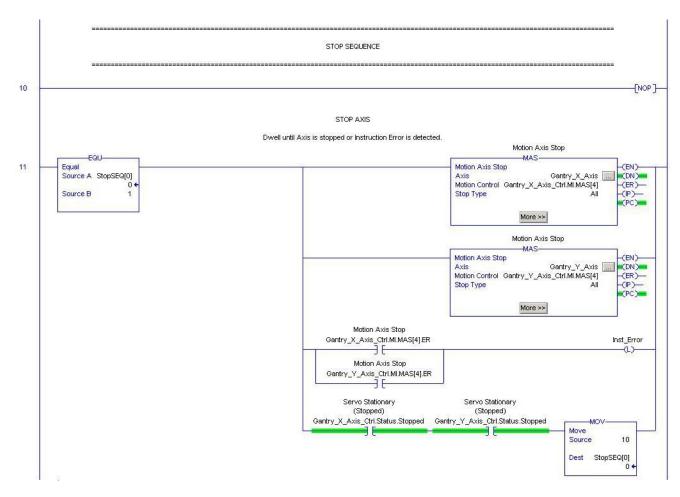
#### **Stop Sequence Template**



The stop sequence is initiated by a machine STOP command via the stop logic in the R03\_Control routine of the application module. By default, the stop sequence is initiated by placing a value of 1 in the StopSEQ[0] tag. When the StopSEQ[0] tag is set to 1, the first step in the stop sequence is executed, starting the stop sequence. Each of the rungs in stop sequence provides a placeholder where application specific step logic can be inserted. The stop sequence logic may include, for example, motion instructions, drive commands and/or other conditional diagnostic logic.

The move (MOV) instruction is a placeholder to advance the stop sequence to the next step by incrementing the StopSEQ[0] tag. Each step in the stop sequence requires a unique value be assigned in ascending order. The steps typically increase by multiples of five or ten. By default, the stop sequence-template steps 1...10...20...30 ...999. Before moving to the next step, a predetermined condition must normally be met to make sure the current step is complete.

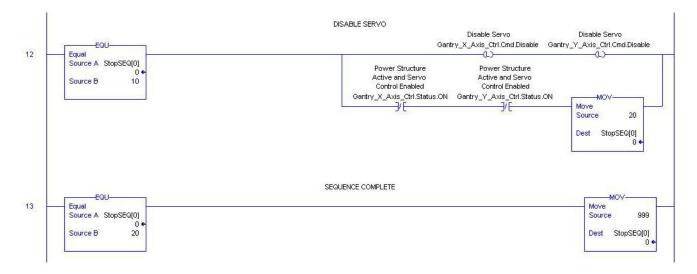
By default, the stop sequence ends when the StopSEQ[0] tag value reaches 999. The StopSEQ[0] tag is then monitored in the R02\_Monitor routine of the application module for a value of 999 and then sets the ApplicationName.Stopped tag. The machine module monitors the ApplicationName.Stopped tag to determine when the application was properly stopped.



**First Stop Sequential Step Example** 

This Widg-O-matic first-stop step example includes two motion axis stop (MAS) instructions, an instruction error detection check, and axis stopped check. Before the MOV instructions indexes to the next sequence step (for example, value 10 into the StopSEQ[0] tag), both axes must be stopped. An error detection check is used to detect a module fault in the application module, preventing the stop sequence from inadvertently hanging on a step.

#### Final Stop Sequential Step and Sequence Complete Example



This Widg-O-matic final-stop step and complete logic example includes logic to disable the two axes and confirm that the axes are disabled before confirming the application is stopped. Identical to the stop-sequence template, the stop-sequence complete rung sets the StopSEQ[0] tag value to 999 which indicates the stop sequence is complete.

## **Application Logic Creation Steps Using Application Logic Examples**

If you are unfamiliar with Rockwell Automation's general Logix5000<sup>™</sup> commands, Logix5000 motion commands, PowerFlex parameters, and/or are seeking common application methods for creating specific application logic, use these steps to create your specific application logic.

### Toolkit Application Logic Example Overview

The toolkit provides a variety of common application logic examples designed to help you create your specific application logic. The logic examples are organized by the device modules they support.

- K300 Logic Examples Supporting Kinetix 300 Ethernet drives
- Motion Logic Examples Supporting CIP Motion, sercos, and virtual motion drives
- PF Logic Examples Supporting all PowerFlex drives
- Widg-O-matic Example Supporting a combination of two Kinetix 6500 CIP Motion drives, one PowerFlex 753 drive, and one Kinetix 300 Ethernet drive.

### Kinetix 300 Logic Examples

Application Example	File Name	Description
EIP Position	K300_EIPMove_App	Enter position, speed, and accel/decel rates to perform incremental position moves.
EIP Velocity	K300_EIPVel_App	Run Kinetix 300 drive at a speed reference.
Index	K300_Index_App	Configure and run Kinetix 300 drive in indexing mode.

### **Motion Logic Examples**

Application Example	File Name	Description
2-Axis Gear	Motion_Gear_App	Gear two axes together.
Adv/Retard Phasing	Motion_Jog_PhaseMove_App	Perform advance/retard phase moves with a MAM instruction on top of MAJ instruction.
2-Axis PCAM	Motion_PCAM_App	Jog an axis and Position Cam another axis to it.
Simple Move	Motion_Simple_Move_App	Move single axis with MAM instruction by using incremental moves.
Safe Limited Speed	Motion_SLS_App	For single axis, monitor SLS request in module. Reduce speed when SLS request detected.
TCAM	Motion_TCAM_App	Time Cam an axis.

### **PowerFlex Logic Examples**

Application Example	File Name	Description	
Run Forward / Reverse	PF_Fwd_Rev_App	Run PowerFlex drive forward, stop, and then run reverse.	
Run at Speed	PF_Run_Spd_App	Run PowerFlex drive at a speed reference.	
PF525 Run Forward / Reverse	PF525Only_Fwd_Rev_App.L5X	Run PowerFlex drive forward, stop, and then run reverse.	
PF525 Run at Speed	PF525Only_Run_Spd_App.L5X	Run PowerFlex drive at a speed reference.	

### Widg-O-matic Logic Examples

Application Example	File Name	Description	Application Created From
Widg-O-Matic Assembly	WOm_Assy_App1	Execute 2-axis simple moves for gantry.	Motion_Simple_Move_App
Widg-O-Matic Packaging	WOm_Pack_App2	Intermittently run PowerFlex drive for conveyor and execute Kinetix 300 position commands for diverter.	PF_Run_Spd_App K300_EIPMove_App

### ArmorStart and ArmorStart LT Examples

Application Example	File Name	Description
Run Forward	AS2X0E_Fwd_App	Run ArmorStart forward.
Run Forward/Reverse	AS2X1E_Fwd_Rev_App	Run ArmorStart forward, stop and then run reverse.
Run For/Rev at Speed	AS2X4E_Fwd_Rev_App (at speed)	Run ArmorStart forward, stop and then run reverse at a speed reference.

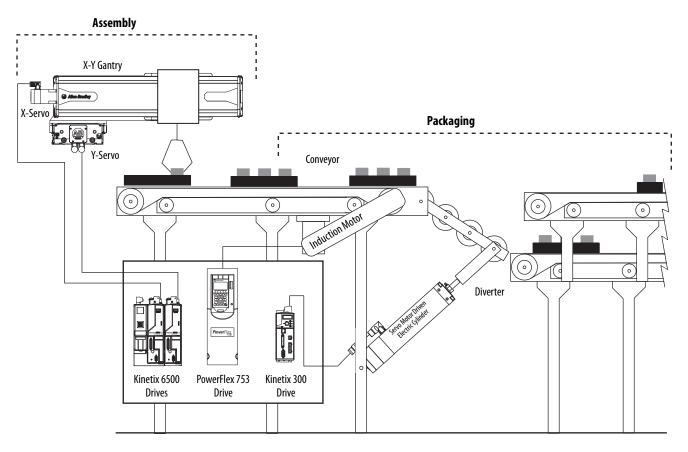
### Widg-O-matic Logic Example Overview

To assist you in understanding how to best use the logic examples, the Widg-O-matic machine application is used as an example.

We recommend you study the Widg-O-matic assembly and packaging applications to see the interaction of the machine, application, and device modules within the application logic. The Widg-O-matic examples are created by using basic drives and motion application examples included in the toolkit. After you've studied these examples, create your own applications using the basic drives and motion examples.

The Widg-O-matic application example is an excellent canvas to experiment with the other application examples. The Widg-O-matic example includes two servo axes, one PowerFlex drive, and one Kinetix 300 drive. So, it is possible for you to import and study all of the application examples.

#### Widg-O-matic Machine Application Example



The Widg-O-matic machine example has two applications (assembly and packaging) and has the following run sequences.

### **Assembly Application**

Step	Simple X-Y Gantry Run Sequence	Value
1	Lower Y-axis, incremental distance	2.0 revs
2	Dwell, time	1.0 s
3	Raise Y-axis, incremental distance	2.0 revs
4	Extend X-axis, incremental distance	3.0 revs
5	Lower Y-axis, incremental distance	2.0 revs
6	Dwell, time	1.0 s
7	Raise Y-axis, incremental distance	2.0 revs
8	Retract X-axis, incremental distance	3.0 revs
9	Repeat and run continuously until the stop sequence is initiated by a machine abort or	stop command.

### **Packaging Application**

Step	Conveyor and Diverter Run Sequence	Drive
1	Verify diverter is in EIP Incremental Position mode	Kinetix 300
2	Set conveyor drive direction forward and speed reference at 50 Hz	PowerFlex 753
3	Enable diverter	Kinetix 300
4	Configure diverter position, speed, accel/decel and start an incremental move	Kinetix 300
5	Start conveyor, run at speed 3.0 seconds	PowerFlex 753
б	Stop conveyor	PowerFlex 753
7	Configure diverter position, speed, accel/decel and start an incremental move	Kinetix 300
8	Start conveyor, run at speed 4.0 seconds	PowerFlex 753
9	Stop conveyor	PowerFlex 753
10	Repeat and run continuously until the stop sequence is initiated by a machine abort or stop command.	

### Import Application Logic Examples

Follow these steps to add logic examples to your R10\_ApplicationCode routine within your application modules.

- 1. Expand the Tasks folder in the Controller Organizer.
- 2. Navigate to and open the R10\_ApplicationCode routine within your first application program file.

RSLogix 5000 - WidgOmatic [1756-L63 18.11]		
File Edit View Search Logic Communications Tools Window	/ Help	
🔁 Controller Organizer 🛛 🚽 🗙	P02_Assembly - R10_ApplicationCode	- 🗆 ×
Conclusion Organization     Conclusion Ministration     Conclusion Ministration	BY DEFAULT THE FOLLOWING RUNGS WILL BE ERRORED AND THEREFORE MUST BE ADDRESSED	
	MODIFY OR OVERWRITE THESE RUNGS WITH THE APPLICATION SPECIFIC LOGIC	_
B → POS_cantry_Y_Drive     B → POS_cantry_Y_Drive     B → POS_conveyor_Drive     B → POS_conveyor_Drive     B → POS_convert_Drive     D → Unscheduled Programs / Phases     B → Motion Groups     P → Add-On Instructions	ои <u>)</u> о	•]—
Autor Types     Data Types     Trends     I/O Configuration	RUN SEQUNCE	-
	SEQUENCE INITIATE     Sequence in the second s	
	e Source B 1 e Source B 1 e Contraction Code e Contraction Code	

For the Widg-O-matic application example, the R10\_ApplicationCode routine within the P02\_Assembly program was opened.

🗎 P0	2_Asser	nbly - R10_Application	nCode		- 🗆 ×
町	뙮鬝	🔁 🔛 🔤 🔥 ab 🕶	<a>&gt;</a>		
					1
			BY DEFAU	LT THE FOLLOWING RUNGS WILL BE ERRORED AND THEREFORE MUST BE ADDRESSED	
			Ν	IODIFY OR OVERWRITE THESE RUNGS WITH THE APPLICATION SPECIFIC LOGIC	
			***PLEA	SE NOTE THE STOP SEGUNCE IS LOCATED DIRECTLY BELOW THE RUN SEQUENCE***	
	×	Cu <u>t</u> Rung	Ctrl+X		
n		Copy Rung	Ctrl+C	[NOP]	
	6		Ctrl+V	[Nor]	
	- E	Delete Rung	Del	-	
		Add Rung	Ctrl+R	RIN SEGUNCE	
		Edit Rung	Enter		
		Edit Rung Comment	Ctrl+D		
1		Import Rungs		[NOP]	
		Export Rungs			
-	e	Start Pending Rung Edits	Ctrl+Shift+S	SEQUENCE INITIATE	
	e	Accept Pending Rung Edits		This rung is a placeholder where Application specific logic can be inserted.	
	è	Cancel Pending Rung Edits		The rengine a presentation menor expension appearsing egge cell be inserted.	

- 3. Select all rungs of the R10\_ApplicationCode routine.
- 4. Right-click the selected rungs and choose Import Rungs.

5. Navigate to the 02\_Application Logic folder within the toolkit's files folder.

Import Rung <del>s</del>				×
Look jn:	C 02_Applicatio	on Logic 💽 🧿	• 🖽 🔁 🐧	
My Recent Documents Desktop My Documents My Computer	CT K300_Logic_E: Motion_Logic_ PF_Logic_Exar Widg-O-matic	Examples		
<b>(</b>	File <u>n</u> ame:			Import
My Network	Files of type:	RSLogix 5000 XML Files (*,L5X)	Y	Cancel
Places	Files <u>c</u> ontaining:	H Rungs	*	Help
	Int <u>o</u> :	R10_ApplicationCode (P02_Assembly)	) 👻	
	C Overwrite Sele	cted Rungs		

Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\02\_Application Logic.

6. Double-click the logic examples folder of choice.

For the Widg-O-matic application example, the Widg-O-matic\_Logic\_Examples folder was opened.

7. Select the desired logic example file to start your application logic.

	◯ Widg-O-matic └ WOm_Assy_A └ WOm_Pack_Aj	pp1.L5X	i 📂 🖽 -	
My Recent Documents Desktop My Documents My Computer		эр2.t5X		
My Network Places	File <u>n</u> ame: Files of type: Files <u>c</u> ontaining: Int <u>o</u> : O <u>v</u> erwrite Sele	RSLogix 5000 XML Files (*.L5X) Rungs R10_ApplicationCode (P02_Assembly) cted Rungs		I <u>m</u> port Cancel Help

For the Widg-O-matic application example, the WOm\_Assy\_App1.L5X file is selected.

- 8. Check Overwrite Selected Rungs.
- 9. Click Import.

The Import Configuration dialog box opens.

Import Configuration			
🗶 🕱 Find:	→ <u>AB</u> AB	Eind/Replace	
Find Within: Final Name			
nport Content:			
🚑 MainTask	Configure Rung F	Properties	
PO2_Assembly	Imported Rungs:	16	
I References	Operation:	Overwrite	💌 Rung 0 (1 Rung)
Image: Contract of the second secon		References will be imported configured in the Reference	as s folders

10. Click Tags within the Import Content organizer.

The Configure Tag References dialog box opens.

	Coninge	ire Tag References		-		_		
P02_Assembly		Import Name	Operation		Final Name	۵ 😭	Alias For	Data Type
References	9	_X_AxisName	Create	X	_X_AxisName		0	BOOL
	9	_X_AxisName_Ctrl	Create	1	_X_AxisName_Ctrl			UDT_ServoCtrl
Data Types	1	_Y_AxisName	Create		_Y_AxisName			BOOL
Errors/Warnings	9	_Y_AxisName_Ctrl	Create	1	Y_AxisName_Ctrl			UDT_ServoCtrl
		DwellTimer	Use Existing		DwellTimer			TIMER[32]
		Inst_Error	Use Existing		Inst_Error			BOOL
		RunSEQ	Use Existing		RunSEQ			DINT[4]
		StopSEQ	Use Existing		StopSEQ		8	DINT[4]

11. Replace tag names in the Final Name column with the associated axis or drive names for your application.

P02_Assembly     P02_Assembly     P02_AsplicationCode (     P02_AsplicationCode (     P02_AsplicationCode (     P02_Assembly     P02_Asse			Import Name	Operation	1	Final Name d	1	Alias For	Data Type
	*	9	_X_AxisName	Use Existing	X	Gantry_X_Axis			AXIS_CIP_DRIVE
	,	11	_X_AxisName_Ctrl	Use Existing	1	Gantry_X_Axis_Ctrl			UDT_ServoCtrl
Data Types	٣.	1	_Y_AxisName	Use Existing	*	Gantry_Y_Axis			AXIS_CIP_DRIVE
- 🔯 Errors/Warnings		11	_Y_AxisName_Ctrl	Use Existing	1	Gantry_Y_Axis_Ctrl			UDT_ServoCtrl
	-		DwellTimer	Use Existing		DwellTimer			TIMER[32]
			Inst_Error	Use Existing		Inst_Error			BOOL
			RunSEQ	Use Existing		RunSEQ			DINT[4]
			StopSEQ	Use Existing		StopSEQ			DINT[4]
	1	<u>}</u>	One or more tags in import o The existing data type will b be lost. Check to ensure tag	e used. Data values	for ti	he tag will be converted if p			lues may

For the Widg-O-matic application example, \_X\_AxisName was replaced with Gantry\_X\_Axis and \_Y\_AxisName was replaced with Gantry\_Y\_Axis.

- 12. Click OK to complete rung import.
- 13. Repeat step 2 through step 12 for each logic example you wish to import.

For the Widg-O-matic Assembly application example, the following rungs are imported. The rungs include a series of five incremental moves.

#### Sercos/CIP Motion Simple Incremental Move

0

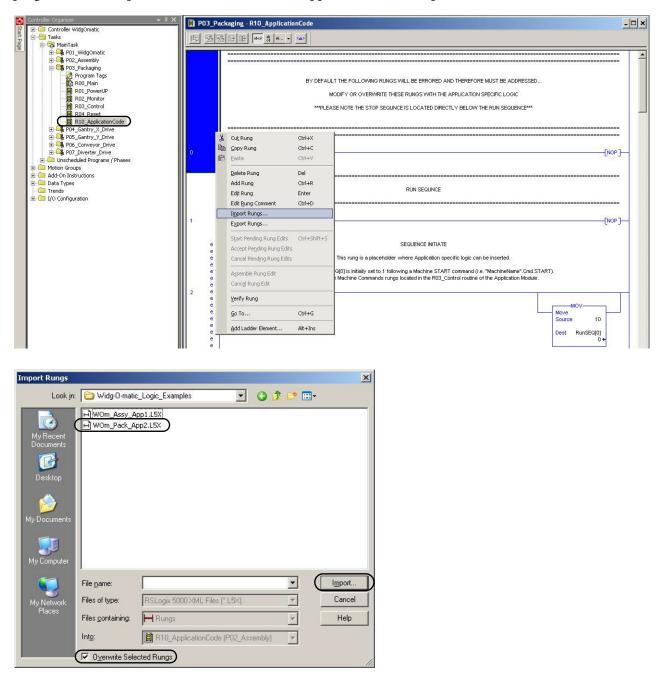
1

2

	SERCOS / CIP MOTION SIMPLE INCREMENTAL MOVE
	demonstrates how to control a SERCOS / CIP MOTION drive using sequencers Motion Instructions.
While the Machine	is STARTING / RUNNING, the drive will be operated as follows:
1)	) Lower Y-Axis - Incremental Distance -2.0 revs
з	2) DWELL - Time 1 sec 3) Raise Y-Axis - Incremental Distance 2.0 revs
4)	) Extend X-Axis - Incremental Distance 3.0 revs ) Lower Y-Axis - Incremental Distance -2.0 revs
	5) DWELL - Time 1 sec
	<ul> <li>6) Raise Y-Axis - Incremental Distance 2.0 revs</li> <li>) Retract X-Axis- Incremental Distance -3.0 revs</li> </ul>
''	8) Repeat
The Run Sequence is continuous	ly repeated until the Stop Sequence is initiated by a Machine ABORT or STOP command.
	NOP
	RUN SEQUENCE
	*======================================
	- Fuen
	INCREMENTAL MOVE
	Lower Y-Axis
	Incremental Distance -2.0 revs Motion Axis Move
EQU	MAM-
EQU Equal Source A RunSEQ[0]	Motion Axis Move
Equal Source A RunSEQ[0] 0	Motion Axis Move Axis Gantry_Y_Axis Motion Control Gantry_Y_Axis_Ctrl.MI.MAM[1]
Equal Source A RunSEQ[0]	Motion Axis Move Axis Gantry_Y_Axis Motion Control Gantry_Y_Axis_Ctrl.MI.MAM[1] Move Type 1 (ER)-
Equal Source A RunSEQ[0] 0	Motion Axis Move Axis Gantry_Y_Axis Motion Control Gantry_Y_Axis_Ctrl.MI.MAM[1] Move Type 1 Position -2 (IP)-
Equal Source A RunSEQ[0] 0	Motion Axis Move Axis Gantry_Y_Axis Motion Control Gantry_Y_Axis_Ctrl.MI.MAM[1] Move Type 1 Position -2

14. Repeat step 1 through step 12 for every application program you have in your drives and motion system.

For the Widg-O-matic application example, the R10\_ApplicationCode routine within the P03\_Packaging program was also opened and the WOm\_Pack\_App2.L5X file was imported.



For the Widg-O-matic WOm\_Pack\_App2.L5X file import, the PowerFlex 753 faceplate \_Conveyor\_DriveName is replaced with Conveyor\_Drive and the Kinetix 300 input, output, and control tag\_Diverter\_DriveName are replaced with Diverter\_Drive.

🚑 MainTask	Configu	e Tag References	_	-		_	_	
P03_Packaging		Import Name	Operation	-	Final Name	4	Alias For	Data Type
Big R10_ApplicationCode       G References	🚩 🖞	_Conveyor_DriveName_FP	Use Existing	A	Conveyor_Drive_FP		1	PFlex_753_20COMM
	× 9	_Diverter_DriveName:I	Use Existing		Diverter_Drive:I		1	AB:K300:1:0
Add-On Instruction:	× 9	_Diverter_DriveName:0	Use Existing	G	Diverter_Drive:0		1	AB:K300:0:0
- M Data Types	_* 1)	_Diverter_DriveName_Ctrl	Use Existing	1	Diverter_Drive_Ctrl		1	UDT_K300_Ctrl
Components		DwellTimer	Use Existing		DwellTimer		1	TIMER[32]
- 🔯 Errors/Warnings		Inst_Error	Use Existing		Inst_Error		1	BOOL
		ONS	Use Existing		ONS		1	DINT[4]
		RunSEQ	Use Existing		RunSEQ		1	DINT[4]
		StopSEQ	Use Existing		StopSEQ			DINT[4]

**IMPORTANT** For application examples with Kinetix 300 devices, it is required that you also configure the component reference tag name for the Kinetix 300 drive.

MainTask 803_Packaging		nfigure Componer				
R10_Application	Code   -	Import Name	Operation	Final Name	△ Class Name	
References	_	_Diverter_DriveN	Use Existing	Diverter_Drive	Module	
- 🖉 Tags - 📴 Add-On Insti	n ation					
- M Data Types	*15X172140000					
- Other Comp	onents					
- 🔯 Errors/Warnings						
- 😡 Errorsz w amings	4			1		
- 😡 Errorsz w amings	-	Dre or more t	ads in import content use a	data tune that alreadu evists in	project and is different	
- 😡 Errorsz warnings	-	!\		i data type that already exists in		
trois/wainings	-	L The existing of	data type will be used. Data	a values for the tag will be conve		alues may
Chois/waihings	2	L The existing of		a values for the tag will be conve		alues may
Errors/wamings	-	L The existing of	data type will be used. Data	a values for the tag will be conve		alues may

For the Widg-O-matic packaging example, the following rungs are imported. The rungs include a series of incremental moves for the Kinetix 300 Diverter\_Drive and Start/Stop and Speed reference commands for the PowerFlex Conveyor\_Drive.

### Kinetix 300 and PowerFlex Drives Incremental Move

K300/POWERFI	
K300- EIP POSITION	-
POWERFLEX-RUN FC	-
Widg-O-Matic Packagin	
The following application example demonstrates how to control	I a K300 and a PowerFlex drive using sequence
Note that the K300 MUST be in EIP Incremental Position in For this example, the mode is set in the K300 Module Reset Set	
The Run sequence will Configure and run incremental position reference	-
and Start/Stop a Power While the Machine is STARTING / RUNNING, th	
1) Verify K300 is in EIP Increme	ntal Position mode.
1) Set Direction FWD, Speed	
2) Enable K300 d	
<ol> <li>Configure Position, Speed, Accel/Decel a</li> <li>Start drive, run at sp</li> </ol>	
3) Stop drive	
<ol> <li>Configure Position, Speed, Accel/Decel a</li> </ol>	and start an Incremental Move.
2) Start drive, run at sp	
3) Stop drive 6) Repeat	
The Run Sequence is continuously repeated until the Stop Sec command.	
	[NC
command.	[NC
Command.	[NC
command.	CE CE CE CE CE CE CE CE CE CE
Command.	CE CE CE CE CE CE CE MOV Move

0

1

2

## **Application Logic Creation Steps Using Template**

If you are familiar with Rockwell Automation's general Logix5000 commands, Logix5000 motion commands, PowerFlex parameters, and have a good idea of your specific run/stop sequences, use these steps to guide you through your specific application logic creation.

- 1. Formulate and list your run sequence steps.
- 2. Add your initial run sequence step (RunSEQ[0] = 1) to the R10\_ApplicationCode routine of your imported application module.
- **3.** Add remaining run sequence steps (RunSEQ[0] > 1) and interlocks to remaining R10\_ApplicationCode routine rungs and adding run sequence rungs as required.
- 4. Formulate and list your stop sequence steps.
- 5. Add your initial stop sequence step (StopSEQ[0] = 1) to the R10\_ApplicationCode routine of your imported application module.
- **6.** Add remaining stop sequence steps (1 < StopSEQ[0] < 999) and interlocks to remaining R10\_ApplicationCode routine rungs and adding stop sequence rungs as required.
- 7. Add your final stop sequence step (StopSEQ[0] = 999) to the R10\_ApplicationCode routine of your imported application module.
- 8. Determine any special reset logic requirements for your application and edit the R04\_Reset Routine in the application module. Refer to <u>Appendix B</u> on <u>page 241</u> for more information on logic module customization.

For other common application code requirements, not included in preprogrammed application modules or logic examples, refer to <u>Appendix B</u> on <u>page 241</u>.

# Verify and Save the Project File

1. Click 🖻 on the Logix Designer application toolbar to verify your controller.

This software function verifies your controller programs and displays errors/warnings, if any.

2. Make corrections to programs as needed.

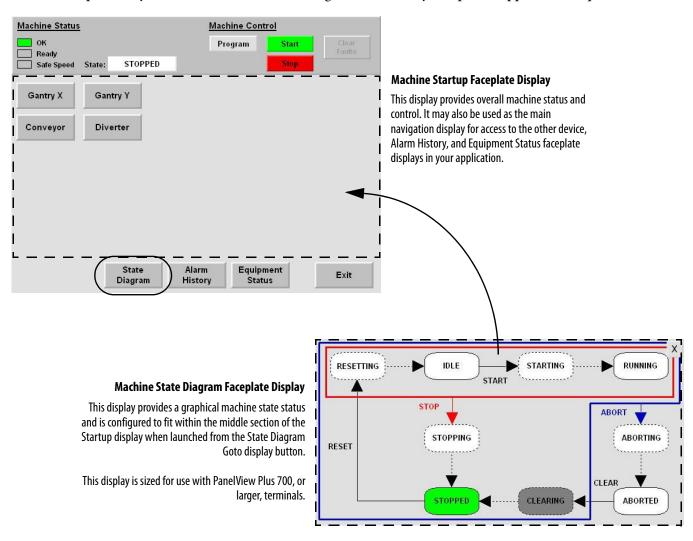
**IMPORTANT** If a PowerFlex 70 drive is used as part of the Low Voltage Drive configuration, you need to manually set the data type for each PowerFlex 70 drive AOI.

3. Click 🔤 to save your Logix Designer project file.

# Notes:

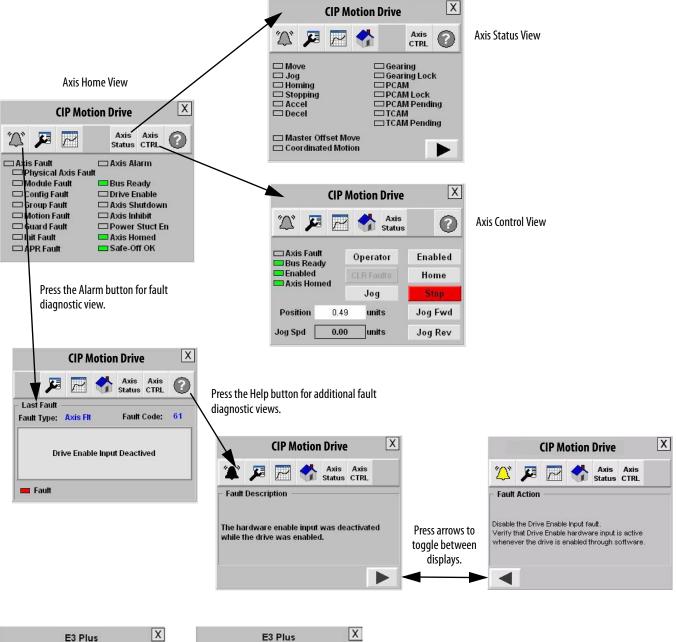
# FactoryTalk View ME Configuration

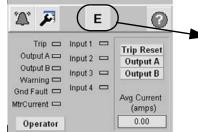
In this chapter you create the operator interface application file for your system using FactoryTalk View Studio software. The toolkit includes a variety of preconfigured machine and device faceplate displays providing status, control, and diagnostics for your drives and motion system. Like the logic modules, the faceplates are designed to be used independently of each other or assembled together based on your specific application requirements.



#### **Device Faceplate Display Example**

- The device faceplates are complex displays providing status, control, and fault diagnostic views for a specific device.
- The toolkit includes device faceplates for CIP Motion, Sercos interface, PowerFlex, Kinetix 300, SMC-50, E300, and E3 Plus overload relay (with 193-DNENCAT) devices.
- This example shows specific views for the CIP Motion faceplate, other devices are similar, however, differences do exist.





E3	Plus X
🌋 🎜 🚳	0
Resource Type:	Electrical
Capabilities:	Measured
Consumed (kWh):	009010011.012
Generated (kWh):	0000000000000
Total (kWh):	009010011.012
Power (kW):	6.00

#### Energy Monitoring

Two versions of the faceplates for the E3 Plus, E300, SMC-50, PF755, PF753 and PF7 series faceplates are provided, one with and one without energy monitoring. The faceplate with energy monitoring includes an Energy tab. The Energy tab provides kWh and kW values along with information on the type of energy being monitored (Resource Type), and how the values are being generated (Capabilities).

				Alarm Hi	story			
Alarm tir 10/13/20 10/13/20 10/13/20 10/13/20	010 9:25: 010 9:25: 010 9:24:	01 AM 01 AM 40 AM	cknowledg	e time	Gantry Gantry	X Axis Drive X Axis Drive	Drive Fault Drive Enab	le Input Deactive
	Ack Alarm	Silence Alarms	T	\$		Print	Alarm Status	
	Ack All	Clear All	T	¥		History	Sort Alarms	Close

#### **Alarm History Faceplate Display**

The Alarm History display provides time and date stamped machine and device faults and alarms. This display is sized for use in PanelView Plus 700 or larger terminals.

	WidgOmatic									
Device	State	Value 1	Value 2	Value 3	Value 4					
Gantry X Axis	READY	0.047 units	0.000 units	0.000 Percent Rated	0.000 units					
Gantry Y Axis	READY	0.636 units	0.000 units	0.000 Percent Rated	0.000 units					
Conveyor	READY	0.000 Hz	0.000 Amps	0.000 units	0.000 units					
Diverter	NOT READY	10.000 units	0.001 units	0.000 Percent Rated	0.000 units					

#### **Equipment Status Faceplate Display**

This Equipment Status display provides a summary status of the devices in your system and a launch site for your individual device faceplate displays. This display is sized for use in PanelView Plus 700 or larger terminals.

	Ed	Equipment Energy Status				
Device	State	Value 1	Value 2	Value 3	Value 4	
PF 753	DISABLED	0.000 kW	0.000	0.000	0.000	
PF755	DISABLED	0.000 kW	0.000	0.000	0.000	
E3 Plus A	DISABLED	6.000 kW	0.000	0.000	0.000	
SMC 50	ACTIVE	2.000 kW	0.000	0.000	0.000	
PF70EC	DISABLED	0.000 kW	0.000	0.000	0.000	

#### **Equipment Status Faceplate for Energy Monitoring Display**

In addition to the standard Equipment Status Faceplate, an additional equipment status faceplate is provided specifically for displaying energy related status. This Equipment Status display for Energy Monitoring provides an energy status summary of the devices in your system and a launch site for your individual device faceplate displays. This display is sized for use in PanelView Plus 700 or larger terminals.

# **Before You Begin**

- Complete your logic configuration (refer to <u>Chapter 4</u>) or
- Complete <u>Appendix G</u>

# What You Need

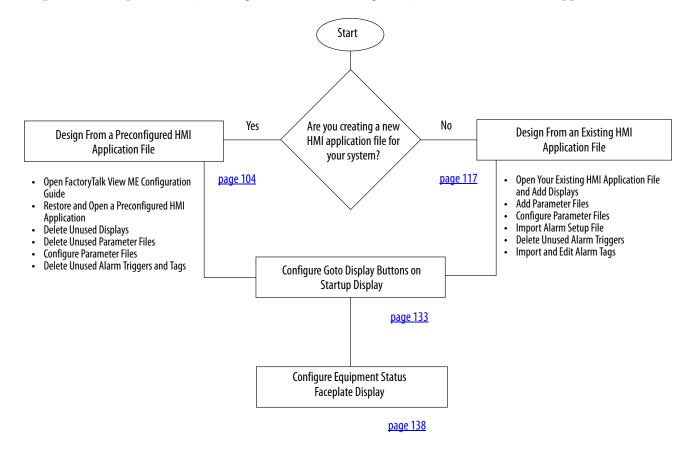
- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative.
- FactoryTalk View Studio software, version 5.1 or later.
- The user manual for FactoryTalk View Studio, Volume 1. Refer to the FactoryTalk View Machine Edition User's Guide, publication <u>VIEWME-UM004</u>.
- The user manual for FactoryTalk View Studio, Volume 2. Refer to the FactoryTalk View Machine Edition User's Guide, publication<u>VIEWME-UM005</u>.

# **Follow These Steps**

This chapter provides two HMI application configuration options:

- Designing from a preconfigured HMI application file
- Designing from an existing HMI application file

Complete these steps to create your Logix5000 controller logic for your drives and motion application.



# **Design From a Preconfigured HMI Application File**

If you are creating a new HMI application file for your system, use this section to configure your application file. Using the preconfigured HMI application file is the most efficient way to create your application file. It includes all of the displays, parameter files, and alarm setup-tags and messages required for all faceplates and devices.

If your existing HMI application file is not too extensive, it may still be more efficient to start from the preconfigured HMI application file and copy your existing application displays, parameter files, and alarm messages. Otherwise, follow the steps in Design From an Existing HMI Application File starting on page 117.

## **Open FactoryTalk View ME Configuration Guide**

If the DMAT Wizard was used to create the initial system configuration, then there is a corresponding FactoryTalk View ME Configuration Guide for your project to assist you in designing your FactoryTalk View ME application.

1. Navigate to your project's FactoryTalk View ME Configuration Guide.

If the default DMAT Wizard directory was used, you will find your project's FactoryTalk View ME Configuration Guide Microsoft Word doc in C:\Documents and Settings\PC Name My Documents\DMAT\*ProjectName\MachineName*\FactoryTalkViewMEConfigurationGuide directory.

The Widg-O-matic example file may be found in: C:\Program Files\RA\_Simplification\DMAT\B-Files\6-Project Examples\Widg-O-matic.

2. Open the guide and use it for assistance in the completing the remaining steps in this section.

Your project file name will be: *ProjectName* FactoryTalk View ME Configuration.

#### Factory Talk View ME Configuration Guide

This guide was created based on your DMAT Wizard selections and is meant to assist you in designing your Factory Talk View ME application using the DMAT Pre-configured HMI application files. Use this document as a supplement to the *Design From a Preconfigured HMI Application File* section in Chapter 5 of the *Drives and Motor Accelerator Toolkit Quick Start* guide, *IASIMP-QS019A-EN-P*.

## This document will define specific steps to help you: • Restore and Open a Preconfigured HMI Application

- Restore and open a
   Delete Unused Displays
   Deremote
- Delete Unused Parameter Files
   Configure Parameter Files
- Delete Unused Alarm Triggers and Tags
- Configure Goto Display Buttons on Startup Display Configure Equipment Status Faceplate Display

#### **Design From a Preconfigured HMI Application File**

#### Restore and Open a Preconfigured HMI Application

- 1. Navigate to the Panelview Plus 1000 folder
- 2. Double-click the PVP1000 Application.apa archive file

#### Delete Unused Displays

#### List of Required Faceplates

[ALARM] [DIAGNOSTICS] [INFORMATION] CIPMotion Faceplate K300, Faceplate K300, Faceplate PowerFlex\_753\_755\_Faceplate PVP1000\_StateDiagram\_Faceplate PVP1000\_AlarmHistory\_Faceplate PVP1000\_AlarmHistory\_Faceplate

#### **Delete Unused Parameter Files**

#### List of Required Parameter Files

CIPMotion\_Parameter K300\_Parameter PF\_Parameter Startup\_Parameter StateDiagram\_Parameter EquipmentStatus\_Parameter

## **Restore and Open a Preconfigured HMI Application**

Follow these steps to restore the preconfigured HMI file and open in FactoryTalk View Studio software.

1. Navigate to the HMI application files within the toolkit's file folder and open either the PanelView Plus 1000 or PanelView Plus 600 folder, based on the terminal size and faceplate requirements of your application.

IMPORTANT	The Equipment Status faceplate is compatible with PanelView Plus 700 or larger terminals. To take full advantage of all
	faceplates, choose the PanelView Plus 1000 folder.

Your personal computer's harddrive path is

 $C:\Program Files\RA\_Simplification\DMAT\B-Files\5-HMI\ME\HMI Applications.$ 

🛤 Drives and Motion Accelerator Tool	kit			<u>- 🗆 ×</u>
LISTEN. THINK. SOL	VE: DRIVES AND M	IOTION ACCELERATO	R TOOLKIT	
- INTRODUCTION AND OVERVIEW				
	PowerF	and Motion Accelerator Tool lex® and Kinetix® Drive Appl		
-Start Here: QUICK START MANUAL	machine	easy-to-use tools and templates or our time developing the unique fea — not on the routine tasks that ac can include:	n this DVD, you can tures of your Id to overhead costs.	
	• Great fasto devo	atly reduced engineering and design er time to market. Users have reporte <u>elopme</u> nt time by as much as 50%.	time, resulting in d reducing control	
- DISCRETE DEVELOPMENT TOOLS -	Architecture and Hardware Selection	onfigured logic can get you u	p and running quickly.	
SUPPORT MATERIAL	CAD Drawing Libraries Controller Logic	the HMI screen templates can costs.	n help you reduce	1
Help and Other Information	HMI Application	Designing from an HMI Application	PanelView Plus 1000	dir
Terms and Conditions Version Changes and Updates Info	dir Miscellaneous Example Software doc Project Examples	Designing with HMI Modules	PanelView Plus 600 notion control.	dir

For the Widg-O-matic machine application example, the PanelView Plus 1000 folder was selected.

Application Folder	PanelView Plus Terminals Supported	<b>Faceplates Displays</b>		
PVP600	<ul><li>PanelView Plus 400</li><li>PanelView Plus 600</li></ul>	<ul> <li>Machine Startup Display</li> <li>Machine State Diagram Display</li> <li>All Device Displays</li> <li>Alarm History Display</li> </ul>		
PVP1000	<ul> <li>PanelView Plus 700</li> <li>PanelView Plus 1000</li> <li>PanelView Plus 1250 <sup>(1)</sup></li> <li>PanelView Plus 1500 <sup>(1)</sup></li> </ul>	<ul> <li>Machine Startup Display</li> <li>Machine State Diagram Display</li> <li>All Device Displays</li> <li>Alarm History Display</li> <li>Equipment Status Display</li> </ul>		

(1) The PanelView Plus 1000 Machine, Alarm History, and Equipment Status faceplate displays are sized at 640x480 (VGA) resolution. If full-sized displays are desired, open display, select all (objects), group, and resize group. Some text editing for new display size may also be required.

2. Double-click the PVPxxxx\_Application.apa archive file.

For the Widg-O-matic machine application example, the PVP1000\_Application.apa file was opened.

The Application Manager dialog box opens.

Application M	ation archive to re	store.		
ser\My Docume	nts\DMAT_HMI\H	IMI Applications\F	PVP1000_Applicat	ion.apa
		Machine Edition a		
<ul> <li>Restore the Directory</li> </ul>	actoryTalk View	Machine Edition a	application and Fa	ctoryTalk Local

**3.** Verify the application archive to restore and that Restore the FactoryTalk View Machine Edition application is selected.

**IMPORTANT** Selecting Restore the FactoryTalk View Machine Edition application and FactoryTalk Local Directory causes the local security settings on your personal computer to substitute for the security setting from the preconfigured application.

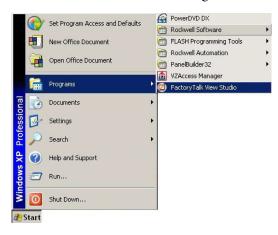
4. Click Next.

Application	Manager			2
Enter a name for	r the new applicatio	n.		
Widg_0_Matic	6			
	< <u>B</u> ack	Finish	Cancel	Help
		1 II IISTI		nep

5. Rename the application to match your machine name.

For the Widg-O-matic machine application example, the application name is Widg\_O\_Matic.

- 6. Click Finish.
- 7. From the Start menu, select Programs>FactoryTalk View Studio.

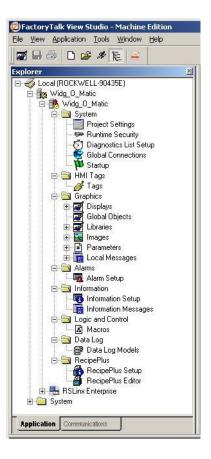


The New/Open Machine Edition Application dialog box opens.

_	Existing						
	cation Nan					1	
	age_640x4						
	age_800x6 kes_ME	100					
	PVP1000	0 1 00					
	htFizz_ME						
	ouse Clgx						
	ouse Clgx						
	ots 5 Scree ots 640x48		2				
	ts 800x60						
	_0_Matic						
-		<u>.</u>					
Langu	age:	11	English (Un	ited State	es), en-US		•
		8					

- From the Existing tab, select the application file that you just restored. For the Widg-O-matic machine application example, Widg\_O\_Matic is selected.
- 9. Click Open.

The application opens in FactoryTalk View Studio software.



## **Delete Unused Displays**

Follow these steps to remove displays not used in your application.

- 1. Determine the required faceplates for your application based on the Faceplate Displays table.
  - **TIP** Only one faceplate display is required for devices/modules of the same type.

Faceplate Display Name	Parameter File	Supported Devices/Modules	Supported PanelView Plus Terminals	
CIPMotion_Faceplate	CIPMotion_Parameter	Kinetix 6500, Kinetix 5500, Kinetix 350, PowerFlex 527, and PowerFlex 755 drives configured as CIP Motion drives		
E3Plus_Faceplate	F2 Devementer			
E3Plus_Faceplate_Energy	E3_Parameter	E3 Plus overload relay		
E300_Faceplate	F200 Devementer			
E300_Faceplate_Energy	E300_Parameter	E300 Electronic overload relays		
K300_Faceplate	K300_Parameter	Kinetix 300 drives		
PowerFlex_4_40_400_Faceplate		PowerFlex 4, PowerFlex 40, and PowerFlex 400 drives		
PowerFlex_40P_Faceplate		PowerFlex 40P drives	All	
PowerFlex_70_700_Faceplate	-	PowerFlex 70EC and		
PowerFlex_70_700_Faceplate_Energy		PowerFlex 700VC drives		
PowerFlex_700S_700S2_Faceplate		Devention 70002 defect		
PowerFlex_700S_700S2_Faceplate_Energy	PF_Parameter	PowerFlex 700S2 drives		
PowerFlex_753_755_Faceplate	-	PowerFlex 753 and PowerFlex 755 drives		
PowerFlex_753_Faceplate_Energy	-			
PowerFlex_755_Faceplate_Energy	-			
PowerFlex_525_Faceplate	-	PowerFlex 525 drives		
PVP1000_AlarmHistory_Faceplate	Not Required			
PVP1000_EquipmentStatus_Faceplate	P1000_EquipmentStatus_Faceplate EquipmentStatus_Parameter All devices		<ul> <li>PanelView Plus 700</li> <li>PanelView Plus 1000</li> </ul>	
PVP1000_Startup_Faceplate	Startup_Parameter	Machine logic module	<ul> <li>PanelView Plus 1250 <sup>(1)</sup></li> <li>PanelView Plus 1500 <sup>(1)</sup></li> </ul>	
PVP1000_StateDiagram_Faceplate	StateDiagram_Parameter	Machine logic module (states)	Tunerview Hus 1500	
PVP600_Startup_Faceplate	Startup_Parameter	Machine logic module	<ul><li>PanelView Plus 400</li><li>PanelView Plus 600</li></ul>	
SERCOS_Faceplate	SERCOS_Parameter	Kinetix 2000, Kinetix 6000, Kinetix 6000M, Kinetix 6200, Kinetix 7000, and Ultra3000-SE drives		
SMC_50_Faceplate			All	
SMC_50_Faceplate_Energy	SMC_50_Parameter	SMC_50 soft starters		
ArmorStart_280E_Faceplate	ArmorStart_280E_Faceplate	ArmorStart 280E motor controllers		
ArmorStart_281E_Faceplate	ArmorStart_281E_Faceplate	ArmorStart 281E motor controllers	1	
ArmorStart_284E_Faceplate	ArmorStart_284E_Faceplate	ArmorStart 284E motor controllers	1	
ArmorStart_290E_Faceplate	ArmorStart_290E_Faceplate	ArmorStart LT 290E motor controllers	All	
ArmorStart_291E_Faceplate	ArmorStart_291E_Faceplate	ArmorStart LT 291E motor controllers	1	
ArmorStart_294E_Faceplate	ArmorStart_294E_Faceplate	ArmorStart LT 294E motor controllers	1	

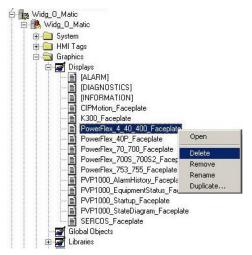
#### **Faceplate Displays**

(1) The PanelView Plus 1000 Machine, Alarm History, and Equipment Status faceplate displays are sized at 640x480 (VGA) resolution. If full-sized displays are desired, open display, select all (objects), group, and resize group. Some text editing for new display size may also be required.

For the Widg-O-matic example, these displays are used:

Widg-O-matic Application Example Display Names		
PVP1000_AlarmHistory_Faceplate		
PVP1000_EquipmentStatus_Faceplate		
PVP1000_Startup_Faceplate		
PVP1000_StateDiagram_Faceplate		
CIPMotion_Faceplate		
K300_Faceplate		
PowerFlex_753_755_Faceplate		

2. Expand the Displays component under the Graphics folder.



- 3. Right-click displays not needed in your application and choose Delete.
- 4. Confirm deleting each un-needed display by clicking Yes.

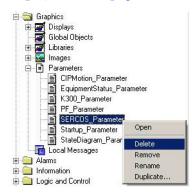
#### **Delete Unused Parameter Files**

Follow these steps to remove parameter files not used in your application.

- 1. Determine required parameter files for your application based on Faceplate Displays table on page 109.
- 2. Expand the Parameters component under the Graphics folder.
- 3. Right-click Parameter files not needed in your application and choose Delete.

For the Widg-O-Matic example, the SERCOS\_Parameter file is deleted.

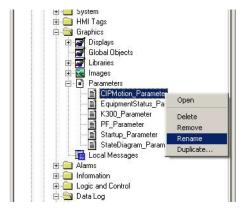
4. Confirm deleting each un-needed file by clicking Yes.



### **Configure Parameter Files**

Follow these steps to configure a parameter file for each device or logic module in your application supported by a faceplate.

1. Right-click a parameter file for a device in your application and choose Rename.



2. Rename the parameter file with the name of the corresponding device in your Logix Designer application.



If more than one device uses the same faceplate then another parameter of the same type must be duplicated and renamed. Refer to step  $\frac{4}{2}$  and step  $\frac{5}{2}$  on page 112.

For the Widg-O-Matic example, these	e are the parameter files:
-------------------------------------	----------------------------

Base Parameter File Name	Widg-O-matic Parameter File Name	
CIPMotion Parameter	Gantry_X_Axis	
CIPMOLIOII_Paralileter	Gantry_Y_Axis	
PF_Parameter	Conveyor_Drive	
K300_Parameter	Diverter_Drive	
EquipmentStatus_Parameter	EquipmentStatus	
Startup_Parameter	Startup	
StateDiagram_Parameter	StateDiagram	

3. Click OK.

**4.** To create another parameter file based on an existing one, right-click the parameter file and choose Duplicate.

For the Widg-O-matic machine application example, Gantry\_X\_Axis and Gantry\_Y\_Axis use the same CIP\_Motion\_Faceplate, but require individual parameter files. For example, Gantry\_X\_Axis is duplicated and renamed to Gantry\_Y\_Axis in <u>step 5</u>.

- 5. Rename the parameter file as needed for your application.
- 6. Click OK.
- 7. Repeat <u>step 1</u> through <u>step 6</u> for each device or logic module parameter file.

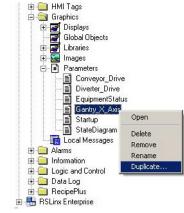
This is the completed Widg-O-matic renamed parameter file listing.

8. Assign the parameters in each of the parameter files.

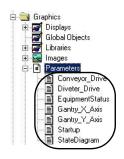
In each parameter file, there are references to controller links (shortcuts) or specific tag names. The '!' before any text indicates that line is a comment and each parameter file contains instructions on how to configure it. The '#' before a number indicates a parameterized tag.

	Gantry_X_Axis - /Widg_0_Matic/ (Parameters)	- 🗆 ×
Comments	I======= Parameter File Created 2010/07/21 =======         I Parameter files are used with graphic displays to specify the tags a display         I uses at run time. You assign parameter files in certain application components         I and object properties dialog boxes. Please see the Help for details.         I Syntax:         I #replacement=tagname         ! Example:         I #1=::[CLX]         ! #2=::[CLX]AxisName_FP         ! #1 an usexpression is replaced by the tag ::[CLX]	
	<pre>! #2 in any expression is replaced by the tag ::[CLX]AxisName_FP ! ! For Example: ! ::[CLX]&gt; Represents the 'Device Shortcut' name of Logix controller you configured in ! RSLinx Enterprise Communication Setup. ! ! AxisName_FP&gt; Represents the AOI name for the device configured in your Logix application !</pre>	file.
Parameters	#1=::[CLX] #2=::[CLX[ <u>AxisName_FP</u> ]	¥.

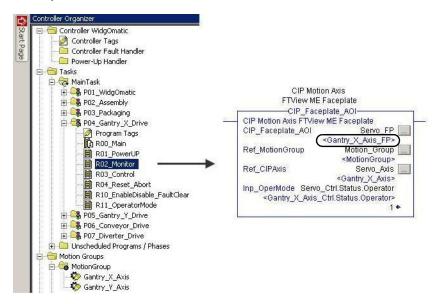
For example, in the Widg-O-matic Gantry\_X\_Axis parameter file Parameter #1 contains the shortcut name [CLX]. This should match the shortcut name created in your RSLinx Enterprise communication setup. Parameter #2 represents the tag name for the specific Faceplate AOI, within your Logix Designer project, which the faceplate requests data from.







The Widg-O-matic Gantry\_X\_Axis parameter #2 is assigned to the faceplate AOI tag named Gantry\_X\_Axis\_FP found in the R02\_Monitor routine of the P04\_Gantry\_X\_Drive program.



a. Double-click the parameter file to open it.



b. Enter your application controller's shortcut name in all parameters.



- **TIP** Less editing is required when assigning HMI alarm tags if you name your controller shortcut [CLX]. Refer to Chapter 6 on page 149 for configuring your controller shortcuts in RSLinx Enterprise communication setup.
- c. Enter the associated faceplate AOI tag name of the device or module for this faceplate parameter.



- d. Close parameter file and acknowledge the Save Changes dialog box.
- 9. Repeat step 8 for each of your device or module faceplate parameters.

Widg-O-Matic Parameter File	Parameter File Configuration	
Contra V Avia	#1=::[CLX]	
Gantry_X_Axis	#2=::[CLX]Gantry_X_Axis_FP	
Contrue V. Avie	#1=::[CLX]	
Gantry_Y_Axis	#2=::[CLX]Gantry_Y_Axis_FP	
Conveyor_Drive	#1=::[CLX]Conveyor_Drive_FP	
Diverter Drive	#1=::[CLX]	
Diverter_Drive	#2=::[CLX]Diverter_Drive_FP	
	#1=::[CLX]Gantry_X_Axis_FP	
	#2=::[CLX]Gantry_Y_Axis_FP	
	#3=::[CLX]Conveyor_Drive_FP	
	#4=::[CLX]Diverter_Drive_FP	
EquipmentStatus	#5=::[CLX]Diverter_Drive_FP	
	#6=::[CLX]Diverter_Drive_FP	
	#7=::[CLX]Diverter_Drive_FP	[
	#8=::[CLX]Diverter_Drive_FP	
	#9=::[CLX]Diverter_Drive_FP	
Ctartun	#1=::[CLX]	
Startup	#2=::[CLX]WidgOmatic	
StateDiagram	#1=::[CLX]WidgOmatic	

For the Widg-O-Matic example, the parameters are edited as follows:

The Equipment Status faceplate requires that parameters are set for all rows #1...9 even if they are not visible. Typically, the last visible row parameter is entered in the remaining parameters. For example, Diverter\_Drive\_FP parameter entered for #4...9.

Refer to Configure Equipment Status Faceplate Display on page 138 for more information.

## **Delete Unused Alarm Triggers and Tags**

Follow these steps to delete any alarm triggers for hardware devices not used in your application. This could improve performance of your PanelView Plus terminal communication.

Displays Teal Global Objects

**IMPORTANT** These steps must be completed if a machine module is not used in your Logix Designer project.

- 1. Expand the Alarms folder.
- 2. Double-click Alarm Setup.

The Alarm Setup dialog box opens.

- 3. Click the Triggers tab.
- **4.** Select any unused alarm trigger tags from the Select trigger organizer.

Unused trigger tags are any associated devices not configured in your Logix Designer project.

🕀 🧰 Information				
⊞ 🦲 Logic and Control ⊞ 📄 Data Log				
ılarm Setup - /P¥P1000_Appli	cation/			_
riggers Dessages Advanced				
	<b>▼</b> 1			
Select trigger:	Trigger settings			
PowerFlexAlarmTrigger KinetixAlarmTrigger	<u>Trigger type:</u>	Trigger la <u>b</u> el:		
SafeIOAlarmTrigger	Value 💌	Label4		
E3AlarmTrigger	Use ack all value:	0		
SMCAlarmTrigger Kinetix2AlarmTrigger		0		
ModuleAlarmTrigger	Optional trigger connectio	ins:		
CIPMotionAlarmTrigger K300AlarmTrigger	Name	Tag or expression	Tag	Exprr
	Handshake	E3AlarmHandshake	•••	
1	Ack		•••	
Add	Remote Ack		•••	•••
	Remote Ack Handshake		•••	
Edit	Message		•••	
	Message Notification		+++	
	Message Handshake		***	***
	E Contraction of the second se	N/		

For the Widg-O-matic application example, these alarm triggers are used, so all other trigger tags can be removed.

Alarm Triggers Used	
PowerFlexAlarmTrigger	
ModuleAlarmTrigger	
CIPMotionTrigger	
K300AlarmTrigger	

- 5. Click Remove.
- 6. Repeat step  $\frac{4}{2}$  and step  $\frac{5}{5}$  for all unused trigger tags.
- 7. Click OK in the Alarm Setup dialog box to save edits.

8. Expand the HMI Tags folder and double-click Tags.

Explorer - Widg_O_Matic X	×蜀•॰•       ×□	800		
🚊 🙀 Widg_0_Matic	💣 Tags - /Widg_0_	Matic/		
G ∰ Widg_O_Matic ⊕ G System ⊡ ∰ HIT Tags	Tag Name: E3AlarmH	landshake		Close
Tags	Type: Digital	<b>Y</b>		Prev
🕀 🧰 Alarms	Description:			Next
Degic and Control				
E ⊡ Data Log				New
🕀 🧰 RecipePlus	Data Source			Help
⊞ 🖶 RSLinx Enterprise ⊕ 💮 System	Type: 💽 Device	C Memory		
	Address: [CLX]E3A	larmHandshake		
	Search For:	Tag Name	Туре	Description
		1 CIPMotionAlarmHandshake	Digital	
		2 CIPMotionAlarmName	String	
	L C system	3 CIPMotionAlarmTrigger	Analog	
	- system	4 E3AlarmHandshake	Digital	
		5 E3AlarmName	String	
	II N	6 E3AlarmTrigger	Analog	
		7 K300AlarmHandshake	Digital	
		8 K300AlarmName	String	
		9 K300AlarmTrigger	Analog	
Application Communications	•	•	8	

The HMI Tags editor appears in the workspace.

9. Select each of the xxxAlarmHandshake, xxxAlarmName, and xxxAlarmTrigger tags associated with each of the Alarm Triggers that were deleted in the previous steps.

For example, the circled tags are the three tags you would delete if the E3AlarmTrigger had been deleted previously.

- 10. Click 🔤 to delete the tags.
- 11. Repeat step 8 through step 10 for all unused Alarm tags associated with unused Alarm Triggers.
  - TIPLess editing is required when assigning HMI<br/>alarm tags if you name your controller<br/>shortcut [CLX]. Refer to Chapter 6 on<br/>page 149 for configuring your controller<br/>shortcuts in RSLinx Enterprise communication<br/>setup.
- 12. Click Close to complete tag editing.
  - TIPBecause you used the pre-configured HMI file<br/>instructions, you can skip Design From an<br/>Existing HMI Application File, and go directly<br/>to Configure Goto Display Buttons on Startup<br/>Display starting on page 133.

🐠 Tags - /Wi	idg_0_Ma	tic/			×
Tag				Close	
Name: CIPMotionAlarmHandshake					
Type:	igital 🔄	]		Brev	
Description:				Next	- 1
				New	
Data Source				Help	
Type: 💽	Device (	C Memory			-
Address:	CLX] [IPMoti	onAlarmHandshake		[	
2			1		1.000
Search For:		Tag Name	Туре	Description	_
	1	CIPMotionAlarmHandshake	Digital		
	2	CIPMotionAlarmName	String		
	3	CIPMotionAlarmTrigger	Analog		
🖵 🛄 system	<sup>0</sup> 4	E3AlarmHandshake	Digital		
	5	E3AlarmName	String		
	6	E3AlarmTrigger	Analog		
	7	K300AlarmHandshake	Digital		
	8	K300AlarmName	String		
	. 9	K300AlarmTrigger	Analog		-
					• //

# **Design From an Existing HMI Application File**

If your existing HMI application file is not too extensive, it may still be more efficient to start from the preconfigured HMI application file and copy your existing application displays, parameter files, and alarm messages. Refer to Design From a Preconfigured HMI Application File starting on <u>page 104</u>.

Otherwise, follow the steps in this section to add the HMI components to your existing FactoryTalk View Machine Edition application file.

## **Open Your Existing HMI Application File and Add Displays**

- **TIP** Only one faceplate display is required for devices/modules of the same type.
- 1. Determine the required faceplates for your application based on the Determine the required faceplates for your application based on the table.

Faceplate Display Name	Parameter File	Supported Devices/Modules	Supported PanelView Plus Terminals	
CIPMotion_Faceplate	CIPMotion_Parameter	Kinetix 6500, Kinetix 5500, Kinetix 350, PowerFlex 527, and PowerFlex 755 drives configured as CIP Motion drives		
E3Plus_Faceplate	E3 Parameter	E3 Plus overload relay		
E3Plus_Faceplate_Energy		ES Flus overload leidy		
E300_Faceplate	E300_Parameter	E300 Electronic overload relays		
E300_Faceplate_Energy		ESOU Electronic overload relays		
K300_Faceplate	K300_Parameter	Kinetix 300 drives		
PowerFlex_4_40_400_Faceplate		PowerFlex 4, PowerFlex 40, and PowerFlex 400 drives		
PowerFlex_40P_Faceplate		PowerFlex 40P drives	All	
PowerFlex_70_700_Faceplate		PowerFlex 70EC and		
PowerFlex_70_700_Faceplate_Energy		PowerFlex 700VC drives		
PowerFlex_700S_700S2_Faceplate	PF Parameter	PowerFlex 700S2 drives		
PowerFlex_700S_700S2_Faceplate_Energy	rr_raidilleter	Powerriex 70052 drives		
PowerFlex_753_755_Faceplate			_	
PowerFlex_753_Faceplate_Energy		PowerFlex 753 and PowerFlex 755 drives		
PowerFlex_755_Faceplate_Energy				
PowerFlex_525_Faceplate		PowerFlex 525 drives		
PVP1000_AlarmHistory_Faceplate	Not Required	All devices		
PVP1000_EquipmentStatus_Faceplate	EquipmentStatus_Parameter	All devices	<ul> <li>PanelView Plus 700</li> <li>PanelView Plus 1000</li> </ul>	
PVP1000_Startup_Faceplate	Startup_Parameter	Machine logic module	<ul> <li>PanelView Plus 1250 <sup>(1)</sup></li> <li>PanelView Plus 1500 <sup>(1)</sup></li> </ul>	
PVP1000_StateDiagram_Faceplate	StateDiagram_Parameter	Machine logic module (states)		
PVP600_Startup_Faceplate	Startup_Parameter	Machine logic module	<ul><li>PanelView Plus 400</li><li>PanelView Plus 600</li></ul>	

#### Faceplate Displays

Faceplate Display Name	Parameter File	Supported Devices/Modules	Supported PanelView Plus Terminals
SERCOS_Faceplate	SERCOS_Parameter	Kinetix 2000, Kinetix 6000, Kinetix 6000M, Kinetix 6200, Kinetix 7000, and Ultra3000-SE drives	
SMC_50_Faceplate	SMC 50 Parameter	SMC 50 soft starters	All
SMC_50_Faceplate_Energy			
ArmorStart_280E_Faceplate	ArmorStart_280E_Faceplate	ArmorStart 280E motor controllers	
ArmorStart_281E_Faceplate	ArmorStart_281E_Faceplate	ArmorStart 281E motor controllers	
ArmorStart_284E_Faceplate	ArmorStart_284E_Faceplate	ArmorStart 284E motor controllers	All
ArmorStart_290E_Faceplate	ArmorStart_290E_Faceplate	ArmorStart LT 290E motor controllers	
ArmorStart_291E_Faceplate	ArmorStart_291E_Faceplate	ArmorStart LT 291E motor controllers	]
ArmorStart_294E_Faceplate	ArmorStart_294E_Faceplate	ArmorStart LT 294E motor controllers	]

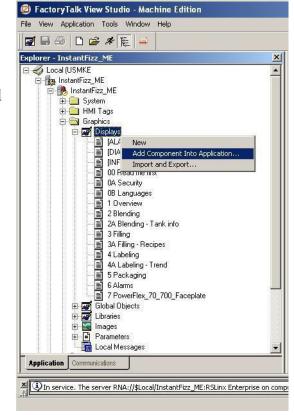
#### Faceplate Displays (continued)

(1) The PanelView Plus 1000 Machine, Alarm History, and Equipment Status faceplate displays are sized at 640x480 (VGA) resolution. If full-sized displays are desired, open display, select all (objects), group, and resize group. Some text editing for new display size may also be required.

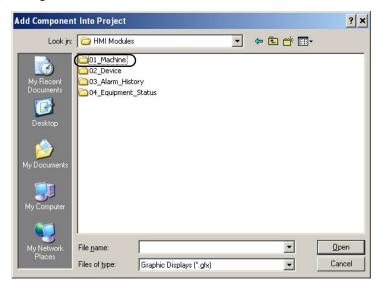
**2.** Launch FactoryTalk View Studio software and open your existing application file.

For this example, the InstantFizz\_ME application file is opened.

**3.** Right-click Displays within Graphics folder and select Add Component Into Application.



4. Navigate to the HMI Modules folder within the toolkit's files folder.



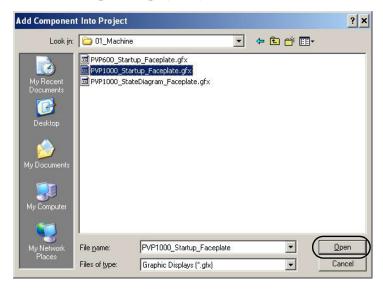
Your personal computer's harddrive path is

 $C:\Program Files\RA\_Simplification\DMAT\B-Files\5-HMI\ME\HMI Modules.$ 

5. Select the folder representing the type of the first faceplate you desire to add.

For this example, the 01\_Machine folder was selected for the PVP1000\_Startup\_Faceplate file.

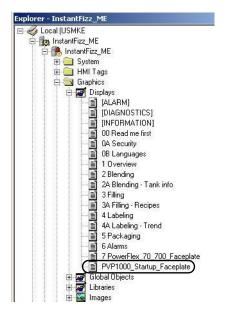
6. Select the faceplate display file you desire to add.



For this example, the PVP1000\_Startup\_Faceplate.gfx was selected

7. Click Open.

The selected display is added to the Displays folder.



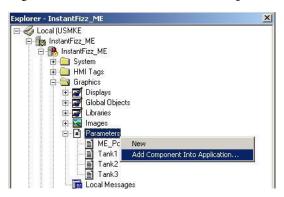
- 8. Repeat step 3 through step 7 for each faceplate required for your application.
  - TIP Only one faceplate is required for multiple device/modules of the same type. For example, if your application has two Kinetix 6500 drives requiring a faceplate, only one CIPMotion\_Faceplate.gfx display is required.

#### **Add Parameter Files**

1. Determine required parameter files for your application.

Refer to the Determine the required faceplates for your application based on the Determine the required faceplates for your application based on the table. table on <u>page 117</u> for the parameter file required for each faceplate.

2. Right-click Parameters within the Graphics folder and select Add Component Into Application.



3. Navigate to the HMI Modules folder within the toolkit's files folder.

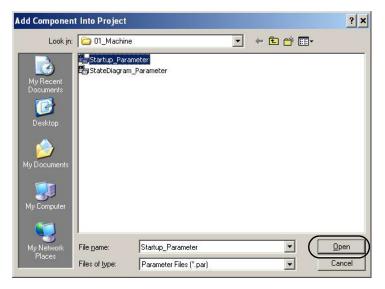


Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files\5-HMI\ME\HMI Modules.

4. Select the folder representing the type of the first parameter you desire to add.

For this example, the 01\_Machine folder was selected for the Startup\_Parameter supporting the PVP1000\_Startup\_Faceplate.

5. Select the parameter file you desire to add.



For this example, Startup\_Parameter.par was selected to support the PVP1000\_Startup\_Faceplate added earlier.

6. Click Open.

The selected parameter is added to the Parameter folder.

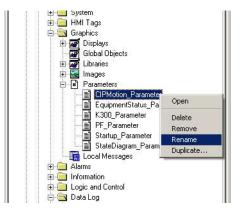


7. Repeat step 2 through step 6 for each parameter file required for your application.

#### **Configure Parameter Files**

Follow these steps to configure a parameter file for each device or logic module in your application supported by a faceplate.

1. Right-click a parameter file for a device in your application and choose Rename.



2. Rename the parameter file with the name of the corresponding device in your Logix Designer application.

ne	<u>×</u>
Gantry_X_Parameter	ОК
Gantry_X_Parameter	Cancel
	ne Gantry_X_Parameter  Gantry_X_Parameter

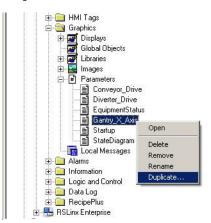
If more than one device uses the same faceplate then another parameter of the same type must be duplicated and renamed. Refer to <u>step 4</u> and <u>step 5</u> on <u>page 112</u>.

Base Parameter File Name	Widg-O-matic Parameter File Name
CIPMotion Parameter	Gantry_X_Axis
cirmotion_ratameter	Gantry_Y_Axis
PF_Parameter	Conveyor_Drive
K300_Parameter	Diverter_Drive
EquipmentStatus_Parameter	EquipmentStatus
Startup_Parameter	Startup
StateDiagram_Parameter	StateDiagram

For the Widg-O-Matic example, these are the parameter files:

3. Click OK.

**4.** To create another parameter file based on an existing one, right-click the parameter file and choose Duplicate.



For the Widg-O-matic machine application example, Gantry\_X\_Axis and Gantry\_Y\_Axis use the same CIP\_Motion\_Faceplate, but require individual parameter files. For example, Gantry\_X\_Axis is duplicated and renamed to Gantry\_Y\_Axis in <u>step 5</u>.

- 5. Rename the parameter file as needed for your application.
- 6. Click OK.
- 7. Repeat step 1 through step 6 for each device or logic module parameter file.

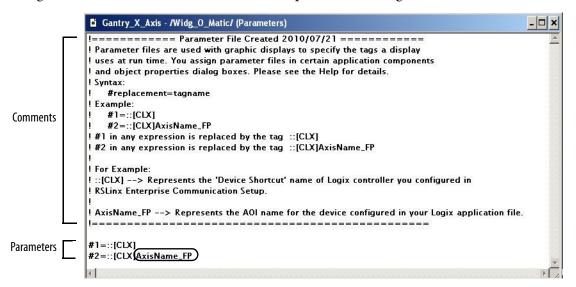
This is the completed Widg-O-matic renamed parameter file listing.



8. Assign the parameters in each of the parameter files.

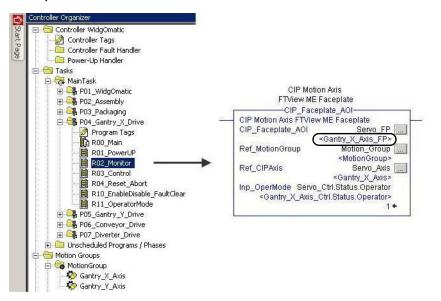
×
Cancel

In each parameter file, there are references to controller links (shortcuts) or specific tag names. The '!' before any text indicates that line is a comment and each parameter file contains instructions on how to configure it. The '#' before a number indicates a parameterized tag.



For example, in the Widg-O-matic Gantry\_X\_Axis parameter file Parameter #1 contains the shortcut name [CLX]. This should match the shortcut name created in your RSLinx Enterprise communication setup. Parameter #2 represents the tag name for the specific Faceplate AOI, within your Logix Designer project, which the faceplate requests data from.

The Widg-O-matic Gantry\_X\_Axis parameter #2 is assigned to the faceplate AOI tag named Gantry\_X\_Axis\_FP found in the R02\_Monitor routine of the P04\_Gantry\_X\_Drive program.



a. Double-click the parameter file to open it.



b. Enter your application controller's shortcut name in all parameters.



- **TIP** Less editing is required when assigning HMI alarm tags if you name your controller shortcut [CLX]. Refer to Chapter 6 on page 149 for configuring your controller shortcuts in RSLinx Enterprise communication setup.
- c. Enter the associated faceplate AOI tag name of the device or module for this faceplate parameter.
  - #2=::[CLX(Gantry\_X\_Axis\_FP

#1=::[CLX]

- d. Close parameter file and acknowledge the Save Changes dialog box.
- 9. Repeat step 8 for each of your device or module faceplate parameters.

Widg-O-Matic Parameter File	Parameter File Configuration	
Contru V Avic	#1=::[CLX]	
Gantry_X_Axis	#2=::[CLX]Gantry_X_Axis_FP	
Contry V Avie	#1=::[CLX]	
Gantry_Y_Axis	#2=::[CLX]Gantry_Y_Axis_FP	
Conveyor_Drive	#1=::[CLX]Conveyor_Drive_FP	
Diverter Drive	#1=::[CLX]	
Diverter_Drive	#2=::[CLX]Diverter_Drive_FP	
	#1=::[CLX]Gantry_X_Axis_FP	
	#2=::[CLX]Gantry_Y_Axis_FP	
	#3=::[CLX]Conveyor_Drive_FP	
	#4=::[CLX]Diverter_Drive_FP	
EquipmentStatus	#5=::[CLX]Diverter_Drive_FP	
	#6=::[CLX]Diverter_Drive_FP	
	#7=::[CLX]Diverter_Drive_FP	
	#8=::[CLX]Diverter_Drive_FP	
	#9=::[CLX]Diverter_Drive_FP	
Startup	#1=::[CLX]	
Startup	#2=::[CLX]WidgOmatic	
StateDiagram	#1=::[CLX]WidgOmatic	

For the Widg-O-Matic example, the parameters are edited as follows:

The Equipment Status faceplate requires that parameters are set for all rows #1...9 even if they are not visible. Typically, the last visible row parameter is entered in the remaining parameters. For example, Diverter\_Drive\_FP parameter entered for #4...9.

Refer to Configure Equipment Status Faceplate Display on <u>page 138</u> for more information.

#### **Import Alarm Setup File**

Importing the Alarm Setup file is optional and required only if you are using the Alarm History faceplate in your application.

**IMPORTANT** When importing the Alarm Setup file, your existing alarm configuration is lost. When prompted to backup your existing alarm configuration, you can choose to save it as an XML file.

1. Right-click Alarm Setup within Alarms folder and choose Import and Export.

The Alarm Import Export Wizard opens.

xplorer - InstantFizz_ME		×
🗄 🎻 Local (USMKE		
🚊 💼 InstantFizz_ME		
📄 🥵 InstantFizz_ME		
庄 🦲 System		
庄 🦲 HMI Tags		
🕀 🧰 Graphics		
🖻 🔄 Alarms		
Alarm Setup		
🕀 🧰 Information	Open	
😟 🧰 Logic and Contr	Import and Export	
🕀 🧰 Data Log 🖉		
😟 🧰 RecipePlus		
😟 🖶 RSLinx Enterprise		
🗄 🧰 System		

- 2. Select Import alarm configuration into application.
- 3. Click Next.

larm Import E	port Wizard - Select Operation	×
Select the opera	ion to perform.	
C Export alarr	n configuration from application	
( Import alarr	n configuration into application	
	< <u>₿</u> ack ( <u>N</u> ext>) Can	ncel Help

- **4.** Select Yes, if you have an existing Alarm Configuration.
- 5. Click Next.

ur existing ala	rm configural	ion?	
	klaud x		Help
	< Back	< Back	<back< th=""></back<>

- 6. In the backup file name field, type a backup file name.
- 7. Click low to browse for the backup file destination.
- 8. Click Next.

Alarm Import Expo	ort Wizard - Sel	lect Backup	Destination	×
Enter a name for the	backup file.			
Did Instant Fiz Alam				
Select where to stor	e the backup file.			
C:\Documents and Projects\InstantFizz	Settings\All Users\I _ME	Documents\RS	View Enterprise\	
	G		<u> </u>	
	< <u>B</u> ack	<u>N</u> ext>	Cancel	Help

**9.** Navigate to the 03\_Alarm\_History folder within the toolkit's files folder.

Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\ DMAT\B-Files\5-HMI\ME\HMI Modules.

- 10. Select the Alarms.xml file.
- 11. Click Open.

The Alarm Import Export Wizard opens.

12. Click Finish.



? ×

- 🔁 🖆 📰

Choose alarm configuration file to import

Look in: Contraction Contracti

4

B

13. Expand the Alarms folder and double-click Alarm Setup to verify import.

💋 FactoryTalk View Studio - Machi	ine Edition				- 🗆 🗙
Eile View Application Tools Window E	lelp				
] 🖬 🖶 😂   D 📽 🗶 🖳 🚔					
Explorer - InstantFizz_ME	Alarm Setup - /InstantFizz Triggers Messages Advanced Select trigger: PowerFlexAlarmTrigger KinetixAlarmTrigger E3AlarmTrigger SMCAlarmTrigger Kinetix2AlarmTrigger ModuleAlarmTrigger ModuleAlarmTrigger	ME/ Trigger settings Trigger type: Value Use ack all value: Optional trigger connectio			×
⊕-) Data Log ⊕-) RecipePlus ⊕ RSLinx Enterprise	CIPMotionAlarmTrigger K300AlarmTrigger	Name Handshake	Tag or expression PowerFlexAlarmHandshake	Tag •••	Exprn
🗄 🧰 System		Ack	-	•••	
	<u>A</u> dd	Remote Ack Bemote Ack Handshake	r		
	Edit	Message	r	•••	
		Message Notification	·	•••	
	<u>R</u> emove	Message Handshake		***	•••
Application Communications			OK Cancel		Help

The triggers listed within the Triggers tab appear as shown.

14. Click OK to close the Alarm Setup dialog box.

#### **Delete Unused Alarm Triggers**

**IMPORTANT** Deleting Unused Alarm Triggers is optional and applies only if you have imported the Alarm Setup file in the last section.

Follow these steps to delete any alarm triggers for hardware devices not used in your application. This could improve performance of your PanelView Plus terminal communication.

E 🙀 PVP1000\_Application

System
 HMI Tags
 HMI Tags
 Graphics
 Global Objects
 Global Objects
 Global Charies
 Global Charles
 For Images
 For Parameters
 Global Messages

🖂 🌏 Local

- 1. Expand the Alarms folder.
- 2. Double-click Alarm Setup.

🔏 Alarm Setup - /P¥P1000_Ap	oplication/			
Triggers Nessages Advanced	-1			
Select trigger:	Trigger settings			
PowerFlexAlarmTrigger KinetixAlarmTrigger	Trigger type:	Trigger la <u>b</u> el:		
SafeIOAlarmTrigger	Value	Label4		
E3AlarmTrigger SMCAlarmTrigger	Use ack all value:	0		
Kinetix2AlarmTrigger		10		
ModuleAlarmTrigger	Optional trigger <u>c</u> onnect	tions:		
	Optional trigger <u>c</u> onnect	tions: Tag or expression	Tag	Ex
ModuleAlarmTrigger CIPMotionAlarmTrigger			Tag •••	Ex
ModuleAlarmTrigger CIPMotionAlarmTrigger	Name	Tag or expression		Ex
ModuleAlarmTrigger CIPMotionAlarmTrigger K300AlarmTrigger	Name Handshake	Tag or expression		Ex •
ModuleAlarmTrigger CIPMotionAlarmTrigger	Name Handshake Ack	Tag or expression E3AlarmHandshake	•••	
ModuleAlarmTrigger CIPMotionAlarmTrigger K300AlarmTrigger	Name Handshake Ack Remote Ack	Tag or expression E3AlarmHandshake		
ModuleAlarmTrigger CIPMotionAlarmTrigger K300AlarmTrigger	Name Handshake Ack Remote Ack Remote Ack Handshak	Tag or expression E3AlarmHandshake	···· ···· ····	

The Alarm Setup dialog box open

3. Click the Triggers tab.

4. Select any unused alarm trigger tags from the Select trigger organizer.

Unused trigger tags are any associated devices not configured in your Logix Designer project.

For the Widg-O-matic application example, these alarm triggers are used, so all other trigger tags can be removed.

Alarm Triggers Used	
PowerFlexAlarmTrigger	
ModuleAlarmTrigger	
CIPMotionTrigger	
K300AlarmTrigger	

5. Click Remove.

- **6.** Repeat  $\underline{\text{step 4}}$  and  $\underline{\text{step 5}}$  for all unused trigger tags.
- 7. Click OK in the Alarm Setup dialog box to save edits.

### **Import and Edit Alarm Tags**

Importing and editing Alarm Tags is optional and required only if you intend to use the Alarm History faceplate in your application.

1. From the Tools menu, choose Tag Import and Export Wizard.



×

😑 Tag Import and Export Wizard

Operation

Help

Select the operation you would like to perform.

Export FactoryTalk View tag database to CSV files

Export FactoryTaik View tag database to CSV files Import FactoryTaik View tag CSV files Merge FactoryTaik View tag database Import A.I. Series or Logic 5 database files Import RSLogix 5/500 Address & Symbol ASCII files

Cancel

The Tag Import and Export Wizard dialog box opens.

- 2. From the Operation pull-down menu, select Import FactoryTalk View tag CSV files.
- 3. Click Next.
- 4. Click low to browse for your existing FactoryTalk View.med project file.
- 5. Click Next.

6. Click to browse for the 03\_Alarm\_History folder within the toolkit's files folder.

Choose the Fa	actoryTalk View project you want to import into.	
Destination pro	oject	
Project <u>t</u> ype:	Machine Edition	•
Project:	Enterprise\ME\HMI projects\InstantFizz_ME\InstantFizz_ME.med	C
	Cancel   <back next=""></back>	Finish

<u>N</u>ext>

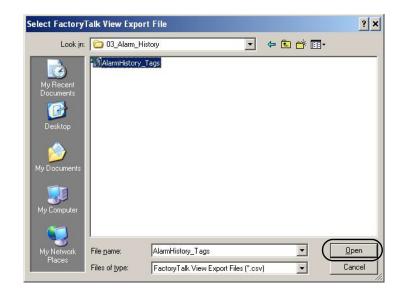
🖲 Tag Import	and Export Wiza	ard		×
Choose the Facto	oryTalk View CSV file	s you want to im	port.	
Import files				
<u>H</u> elp	<u>C</u> ancel	< <u>B</u> ack	<u>N</u> ext>	Einish

Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\5-HMI\ME\HMI Modules\03\_Alarm\_History.

The Select FactoryTalk View Export File dialog box opens.

- 7. Select AlarmHistory\_Tags.
- 8. Click Open.



9. Verify selected file and Click Next.

10. Select Skip existing and Click Next.



\varTheta Tag Import and Export Wizard



- 11. Click Finish to execute import.
- 12. Close database confirmation dialog box.

🥮 Tag Import a	nd Export Wiza	ard		×
Click the Finish bu	tton to import the da	atabase.		
Source:				
100110\DMAT\B-	ISettings\jwnovak\ Files\5-HMI\ME\HM _History\AlarmHisto	4I .	Splash	
	l Settings\All Users\ z_ME\InstantFizz_N		View Enterprise\N	ИЕЛНИІ
Number of lines in im	port files:			
Tags: 27 lines Al	arms: O lines		_	
Help	<u>C</u> ancel	< <u>B</u> ack	Next [	Einish

13. Expand the HMI tags folder in project Explorer<sup>™</sup> and double-click Tags.

🕺 FactoryTalk View Studio - Machine	Edition			
File Edit View Application Tools Window	Help			
<b>1 1 3 1 1 1 1 1 1 1 1 1 1</b>	T			
Explorer - InstantFizz_ME	×留龄→留 ▲ ×□			
Local (USMKE     InstantFizz_ME     InstantFizz_ME	💣 Tags - /InstantF	izz_ME/		<u>- 🗆 ×</u>
E System	Tag			
🗄 🔄 HMI Tags	Name: Available	eRAM		Close
Tags	Type: Analog	×		Prev
	Description:			
🗄 🦲 Information	Minimum: 0	Scale: 1		Ne <u>x</u> t
E Cojic and Control	Maximum: 100	Offset: 0 Data Type:	(m. (h)	▼ <u>N</u> ew
i⊞ 📄 Data Log i⊞ 💼 RecipePlus		Offset: To Data Type:	(Derault)	
🗄 🖶 RSLinx Enterprise	Data Source	e 🕫 Memory		Help
🕀 🧰 System		s 💀 Memory		
	Initial Value: 0			
	Reten	ltive		
	Search For:	Tag Name	Туре	Description 🔺
		1 AvailableRAM	Analog	
		2 CIPMotionAlarmHandshake	Digital	$\mathbf{i}$
	- C Program	3 CIPMotionAlarmName	String	
		4 CIPMotionAlarmTrigger	Analog	
	- 🗀 system	5 E3AlarmHandshake	Digital	
		6 E3AlarmName 7 E3AlarmTrigger	String	/
	N N	7 E3AlarmTrigger	Analog	/

The HMI Tags editor appears in the workspace.

- 14. Verify a number of Alarm Tags have been added to the HMI tags listing.
- **15.** Select each of the *xxx*AlarmHandshake, *xxx*AlarmName, and *xxx*AlarmTrigger tags associated with each of the Alarm Triggers that were deleted in the previous section.

For example, the circled tags are three tags you would delete if the E3AlarmTrigger had been deleted previously.

- 16. Click  $\underline{\times}$  to delete the tags.
- Repeat step 15 through step 16 for all unused Alarm tags associated with unused Alarm Triggers.
- 18. Click Close to complete tag editing.

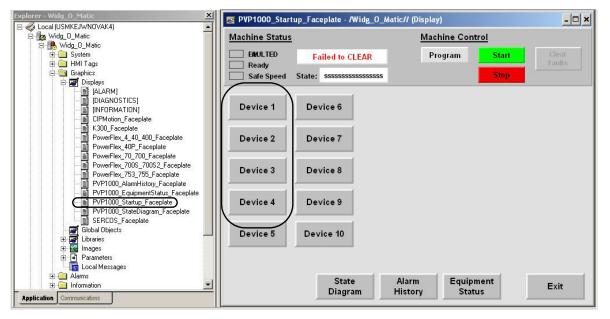
💅 Tags - /Instant	Fizz_	ME/			- 0
Tag Name: E3Alarr	mliand	chaka		-(	Close
	innanu	Shake			-
Type: Digital	<u> </u>				Prev
Description:					Ne <u>x</u> t
					New
Data Source					Help
Type: 💽 Devi	ce (	Memory			-
		or memory			
Address: [CLX]E	25	Handshake			
Address: [CLX]E	25				
	25		Туре	Descrip	tion
	25	Handshake	Type Analog		tion
Search For:	3Alarm	Handshake Tag Name	24		tion
Search For:	3Alarm	Handshake Tag Name AvailableRAM	Analog		tion
Search For:	3Alarm	Handshake Tag Name AvailableRAM CIPMotionAlarmHandshake	Analog Digital		tion
Search For:	3Alarm	Handshake Tag Name AvailableRAM CIPMotionAlarmHandshake CIPMotionAlarmName CIPMotionAlarmTrigger E3AlarmHandshake	Analog Digital String		tion
Search For:	3Alarm 1 2 3 4 5 6	Handshake Tag Name AvailableRAM CIPMotionAlarmHandshake CIPMotionAlarmName CIPMotionAlarmTrigger	Analog Digital String Analog		tion
Search For:	3Alarm 1 2 3 4 5	Handshake Tag Name AvailableRAM CIPMotionAlarmHandshake CIPMotionAlarmName CIPMotionAlarmTrigger E3AlarmHandshake	Analog Digital String Analog Digital		tion

# **Configure Goto Display Buttons on Startup Display**

There are ten Goto Display button placeholders on the PVP1000\_Startup\_Faceplate display and six on the PVP600\_Startup\_Faceplate display. If more display buttons are required, simply duplicate one and configure it for the additional display.

Follow these steps to configure Goto Display buttons for each of the device faceplates on your machine startup display.

1. Expand the Displays folder and double-click PVP*xxxx*\_Startup\_Faceplate display.



For the Widg-O-matic machine application example, the PVP1000\_Startup\_Faceplate display is opened. In this example, device buttons 1...4 will be configured for the Gantry X, Gantry Y, Conveyor, and Diverter device faceplates.

**2.** Double-click one of the device buttons.

BAULTED	General Label Common	Slear
Ready	Appearance	aults
Safe Speed	Border style: Border width:	
	Raised	
Device 1	Back style: Pattern style: Border color	
	Solid  None  Pattern color	
Device 2	Shape:	
	Rectangle	
Device 3		
Device 5	Display settings	
	Display:	
Device 4	Parameter file:	
	O Parameter list:	
Device 5	✓ Display position Top position: 130 Left position: 300	
	Touch margins	
	Horizontal margin: Vertical margin:	
	0	Exit
	Other	
	✓ Audio	

The Goto Display Button Properties dialog box opens.

3. Click to browse for the desired display.

For the Widg-O-matic machine application example, the Device 1 button is selected and configured to launch a faceplate for the Gantry X device.

The display Component Browser dialog box opens.



4. Select the desired display to launch when this device button is pressed.

For the Widg-O-matic machine application example, the CIPMotion\_Faceplate display is selected as it supports the Gantry X device (Kinetix 6500 drive). Refer to the Determine the required faceplates for your application based on the Determine the required faceplates for your application based on the table. table. table on page 117 for faceplate supported devices.

5. Click OK to close the Component Browser dialog box.

Appearance Border style: Raised Back style: Solid	Border width: 3 Pattern style: None	Border uses bad     Back color     Border color     Pattem color	ck color	
Shape: Rectangle Display settings Display: CIPMotion_ © Parameter file:		Highlight color	Component Browser Select a component: Conveyor_Drive Diveter_Drive EquipmentStatus Gantuy X Axis Gantuy X Axis	
C Parameter list:	op position: 130 Vertical margin:	Left position: 300	Startup StateDiagram	
Other				

6. Click 🔄 to browse for the Parameter file.

The component Component Browser dialog box opens.

For the Widg-O-matic machine application example, the Device 1 button is assigned to the Gantry\_X\_Parameter that populates the Gantry\_X tag data into the CIPMotion\_Faceplate display when launched.

7. Click OK to close the Component Browser dialog box.

The Goto Display Button Properties dialog box updates with the Display and Parameter file settings you just entered.

- 8. Set Display position settings as needed.
- **9.** Click the Label tab to configure the desired button caption text.

Border style:	Border width:
Raised	3     Border uses back cold
Back style:	Back color Pattern style: Border color
Solid	None
Shape:	Highlight color
Rectangle	F Blink
<ul> <li>Parameter list:</li> <li>Display position</li> </ul>	Top position: 130 Left position: 300
Touch margins	
	Vertical margin:
Horizontal margin:	0

- 10. The Label tab dialog box opens.
- **11.** Type the desired text in Caption field.

For the Widg-O-matic machine application example, Gantry X is entered.

12. Click OK to save button properties.

Caption Gantry X		
		Insert Variable
Font Arial	Size:	B Z U
Caption color     Caption back color     Caption blink     Word wrap	Alignment CCC CCC	Caption back style: Transparent 🗨
Image settings		
Image:	Image back s Transparent	tyle:
Image color Image back color Image blink Image scaled	Alignment CCC CCC	-

The display updates with button changes. Device 1 is now Gantry X.

🛃 PVP1000_Startu	ıp_Faceplate - /Widg_0_A	Matic// (Display)		- 🗆 ×
Machine Status		Machir	e Control	
EMULTED     Ready     Safe Speed	Failed to CLEAR State: ssssssssssssssssss	Prog	ram <mark>Start</mark> Stop	Clear Faults
Gantry X Device 2	Device 6 Device 7			
Device 3	Device 8			
Device 4	Device 9			
Device 5	Device 10			
	State Diagram	Alarm History	Equipment Status	Exit

13. Repeat step 2 through step 12 for each Goto Display Button required for your application.

For the Widg-O-matic machine application example, the four Goto display buttons were configured.

Device Goto Display Button	Display Setting	Parameter Setting
Gantry X	CIPMotion_Faceplate	Gantry_X_Axis
Gantry Y	CIPMotion_Faceplate	Gantry_Y_Axis
Conveyor	PowerFlex_753_755_Faceplate	Converyor_Drive
Diverter	K300_Faceplate	Diverter_Drive

Prog	ram Start	Clear Faults
	Stop	

14. Select all unused Goto Display buttons and delete.

15. Select the State Diagram, Alarm History, and Equipment Status Goto display buttons and verify their display settings or delete them if not required.

System Goto Display Button	Default Display	Default Parameter
State Diagram	PVPxxx_StateDiagram_Faceplate	StateDiagram_Parameter
Alarm History	PVP1000_AlarmHistory_Faceplate	None required
Equipment Status	PVP1000_EquipmentStatus_Faceplate	EquipmentStatus_Parameter

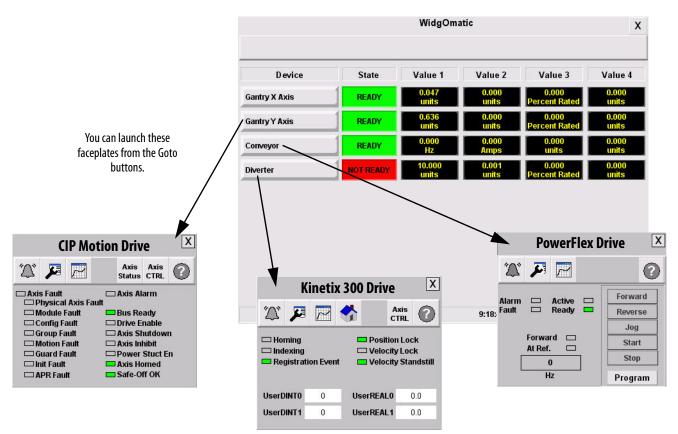
# **Configure Equipment Status Faceplate Display**

The Equipment Status faceplate display provides a summary status of the devices in your system and another launch site for your individual device faceplates.

**IMPORTANT** This section is optional and necessary only if you intend to use the Equipment Status faceplate.

The Equipment Status faceplate files let you quickly load and configure a summary display of preconfigured status and diagnostic displays or faceplates for FactoryTalk View Machine Edition. The Equipment Status faceplate works in conjunction with individual device faceplates and provides a single summary display of all of the device faceplates that may be configured for an application. You can configure up to nine device faceplates to run with the Equipment Status faceplate and you can launch each device faceplate directly from it.

#### Example of Equipment Status Display Configured with Four Device Faceplates



#### Add the Equipment Status Faceplate Display

1. Right-click Displays within the Graphics folder and select Add Component Into Application.

File View Application	Tools Window	Help	
🖬 🖬 🍜 🗅 🖬	* * 🗄 🖴		
xplorer - InstantFizz	_ME		×
⊟-∰g InstantFizz_N ⊡-∰g InstantFi ⊕ Syst ⊕ HMI ⊟ Grap ⊕ ∰	zz_ME em Tags		
Ē.		nt Into Application	
+ 🔀	Import and Ex	10000 0 10	

2. Navigate to the 04\_Equipment\_Status folder within the toolkit's files folder.

Add Component	: Into Project				? ×
Look jn:	04_Equipmer	nt_Status	•	E 🔺 🎹	
My Recent Documents Desktop My Documents My Computer	PVP1000_Equi	pmentStatus_Faceplate.gfx			
My_Network	File <u>n</u> ame:	PVP1000_EquipmentStatus_	Faceplate	• (	<u>Open</u>
Places	Files of type:	Graphic Displays (*.gfx)		•	Cancel

Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files 5-HMI\ME\HMI Modules04\_Equipment\_Status.

- 3. Select the PVP1000\_EquipmentStatus\_Faceplate.gfx file.
- 4. Click Open.

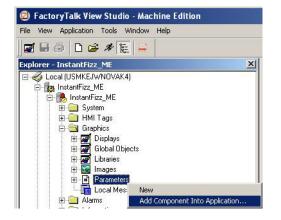
#### Add the ME\_Equipment\_Parameter File

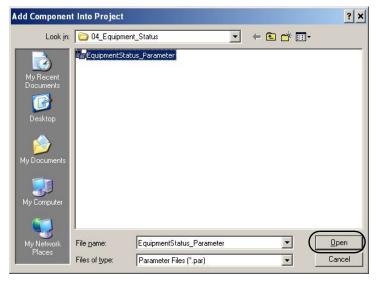
1. Right-click Parameters within the Graphics folder and select Add Component Into Application.

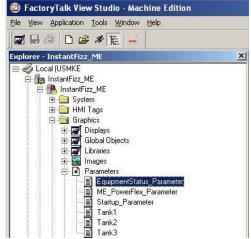
**2.** Navigate to the 04\_Equipment\_Status folder within the toolkit's files folder.

Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\ DMAT\B-Files\5-HMI\ME\HMI Modules\04\_Equipment\_Status.

- **3.** Select the EquipmentStatus\_Parameter.par file.
- 4. Click Open.
- **5.** Verify the ME\_Equipment\_Parameter file appears under Parameters.
- 6. Double-click ME\_Equipment\_Parameter to open the parameter editor.

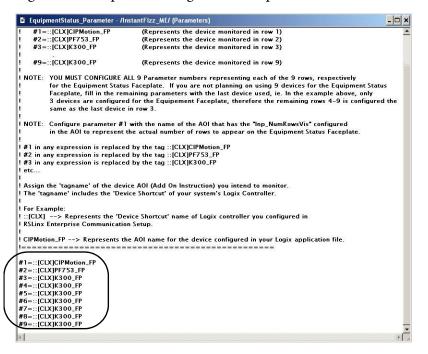






The EquipmentStatus\_Parameter dialog box opens.

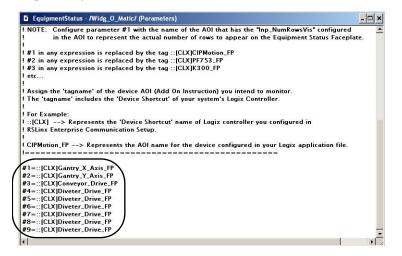
7. Assign device faceplate AOI tags to all nine parameters.



Each parameter #1...9 corresponds to the device AOI tag name of each Equipment Status faceplate Row #1...9. You must assign the #1 parameter to a device faceplate AOI that includes the Inp\_NumRowsVis assignment that was configured in <u>Chapter 4</u>.

The remaining parameters #2...9 must be assigned to valid device faceplate AOI tag names for the Equipment Status faceplate to operate without errors, even if corresponding Equipment Status faceplate rows are not being used or assigned to non-preconfigured devices. It is recommended to fill in the unused parameters with the last valid AOI tag name.

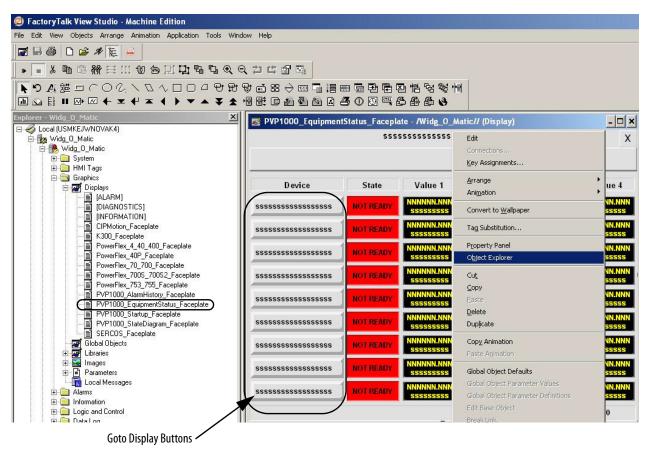
In the Widg-O-matic example, we are only using four rows, therefore, parameter #1...4 are assigned to the corresponding device AOI tags that we display in rows #1...4. The remaining parameters, #5...9, are assigned to the #4 row device AOI tag name, [CLX]Diverter\_Drive\_FP, as a place holder for those faceplate objects in the non-visible rows #5...9.



8. Close the EquipmentStatus\_Parameter dialog box and acknowledge the Save Changes dialog box.

### **Configure Goto Buttons on the Equipment Status Faceplate**

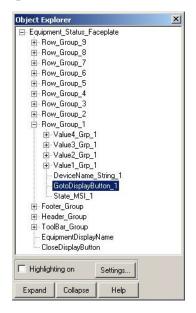
1. Expand Displays within the Graphics folder and double-click PVP1000\_EquipmentStatus\_Faceplate.



2. Right-click the display and choose Object Explorer.

The Object Explorer dialog box opens.

3. Expand Row\_Group\_1 and double-click GotoDisplayButton\_1.



The Goto Display Button Properties dialog box opens.

4. Click 🔙 to browse the display faceplates.

The Component Browser opens.

5. Select the faceplate display to launch from the first row Goto display button.

For the Widg-O-matic application example, the CIPMotion\_Faceplate is selected.

6. Click OK to close the Component Browser dialog box.

Border style:	Border width:	
Raised 💌	5 🔽 🔽 Border uses back col	or
Back style:	Back color Pattern style:	
Transparent	Pattern style: Border color None V Dettern color	
Shape:		
	Component Browser	
Rectangle 💌	Select a component:	
Parameter file:     Parameter list:     Display position     Touch margins	PowerFlex, 70, 700, Faceplate           PowerFlex, 700S, 70052, Faceplate           PowerFlex, 703, 755_Faceplate           PowerFlex, 753, 755_Faceplate           PVP1000_AlamHistory_Faceplate           PVP1000_Startup_Faceplate           PVP1000_Startup_Faceplate           PVP1000_Startup_Faceplate           PVP1000_Startup_Faceplate           PVP1000_Startup_Faceplate           Vertical           (ALAPM)	late

7. Click to browse the parameter files.

The Component Browser opens.

8. Select the parameter associated with the display to be launched from the first row Goto display button.

For the Widg-O-matic application example, the Gantry\_X\_Axis parameter is selected.

- 9. Click OK to close the Component Browser dialog box.
- **10.** Click OK to save your edits to the Goto Display Button Properties dialog box.

Appearance Border style: Raised Back style: Transparent Shape:	Border width: 5 Pattern style: None	Border uses ba     Back color     Border color     Pattern color     Highlight color     Bink	ack color		
Rectangle       Display settings       Display:       CIPMotion_F       © Parameter file:       © Parameter list:       © Display position Tr	aceplat	Left position: 0	Select a comp Conveyor_Dr Diveter_Drive EquipmentStt Gantry_Y_Ax Gantry_Y_Ax Startup StateDiagram	ponent: ive atus is is	
Touch margins Horizontal margin: 0 0 − Other ✓ Audio	Vertical margin:				

 Repeat steps step 3 through step 10 for each Goto Display Button used in the Equipment Status faceplate. Unused buttons can remain on the display, but won't be visible based on the Inp\_NumRowsVis tag value set in <u>Chapter 4</u>.

Goto Display Button Pr

### **Configure Additional Device Value Columns**

Not all device faceplates used with the Equipment Status faceplate are configured to display four Value fields. If unused value fields are needed then additional logic will need to be added to the existing device AOI to move the additional AOI tag values to the corresponding Sts\_Valuexx tags.

In this example, pre-configured logic within a PowerFlex faceplate AOI is used to write values to Values 1 and 2. Simply add additional MOV instructions to move other values to Values 3 and 4 if desired.

This rung is used to move PF Faceplate tags, for actual computed speed and current, t	o tags used in the Equipment Faceplate
	Move Source Val_OutputFreq 0 Dest Sts_Value1 0.0
	Move Source Val_OutputCurrent 0 Dest Sts_Value2 0.0

The same is true for the units displayed for each additional Value field desired. You can write Logic to move a string value to the SetValueXUnits tag in the AOI, or you can set the default string for this tag by locating it in the Local tags section of the AOI as shown below.

1			
Name	△ Data Type	Default	Style
⊞-CommFaultTimer	TIMER	{}	
⊞-CommStatusValue	DINT	0	Decimal
OperONS	BOOL	0	Decimal
⊞-Set_DeviceNameOper	STRING	'PF 70'	
⊞-Set_EquipmentDisplayName	STRING	'Equipment Stat	
⊞-Set_SpeedUnitsOper	STRING	'RPM'	
⊞-Set_Value1Units	STRING	'rpm'	
⊞-Set_Value2Units	STRING	'Amps'	
* ⊞-Set_Value3Units	STRING	🛄 'Torque'	
⊞-Set_Value4Units	STRING	'units'	
		0.0	Float
SpeedRate	REAL	0.0	Float

## **Configure Equipment Status Faceplate for Energy Monitoring**

The Equipment Status Faceplate for Energy display provides a summary of the energy status of the devices in your system and also provides another launch site for your individual device faceplates.

This equipment status display works in the same manner as the standard Equipment Status faceplate described in the previous section, however, it displays only energy related data.

	Ed	quipment Ene	rgy Status		
Device	State	Value 1	Value 2	Value 3	Value 4
PF 753	DISABLED	0.000 kW	0.000	0.000	0.000
PF755	DISABLED	0.000 kW	0.000	0.000	0.000
E3 Plus A	DISABLED	6.000 kW	0.000	0.000	0.000
SMC 50	ACTIVE	2.000 kW	0.000	0.000	0.000
PF70EC	DISABLED	0.000 KW	0.000	0.000	0.000

**IMPORTANT** You must use the device module routines with energy support to support the equipment status faceplate for energy.

## Add the Equipment Status Faceplate for Energy Display

- 1. Right-click Displays within the Graphics folder and select Add Component Into Application.
- 2. Navigate to the 04\_Equipment\_Status folder within the toolkit's files folder.

Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files\ 5-HMI\ME\HMI Modules\04\_Equipment\_Status.

- 3. Select the PVP1000\_EquipmentStatus\_Faceplate\_Energy.gfx
- **4.** Click Open.

## Add the ME\_Equipment\_Parameter File

- 1. Right-click Parameters within the Graphics folder and select Add Component Into Application.
- 2. Navigate to the 04\_Equipment\_Status folder within the toolkit's files folder.

Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files 5-HMI\ME\HMI Modules04\_Equipment\_Status.

- 3. Select the Energy\_EquipmentStatus\_Parameter.par file.
- 4. Click Open.
- 5. Verify the Energy\_EquipmentStatus\_Parameter file appears under Parameters.

6. Double-click Energy\_EquipmentStatus\_Parameter to open the parameter editor.

The Energy\_EquipmentStatus\_Parameter dialog box opens.

7. Configure all nine parameters with your shortcut name and drive name.

The equipment status faceplate display for energy reads data from both the device faceplate AOI tag (DriveName\_FP) and the device energy object AOI tag (DriveName\_BEO). The parameters combine with \_FP and \_BEO within the faceplate as required.

```
!========= Parameter File Created 2013/01/06 ===========
!This parameter file is for use with the Equipment_Status_Faceplate_Energy display
_____
! Use this parameter file in conjunction with a Goto display button that represents the Equipment Energy Status Display
that you intend to monitor. Simply assign this parameter file within the Goto display button's Properties – Display Settings.
! General Parameter Syntax:
   #replacement=::[controller shortcut]device name
Example:
   #1=::[CLX]My_PowerFlex_Motor_1
                                         (This will represent the device monitored in row 1 of the Equipment Faceplate)
   #2=::[CLX]My_PowerFlex_Motor_2
                                         (This will represent the device monitored in row 2 of the Equipment Faceplate)
   #3=::[CLX]My_Kinetix_Axis_1
                                         (This will represent the device monitored in row 3 of the Equipment Faceplate)
   #4=::[CLX]My_E3_Plus_Motor_3
                                         (This will represent the device monitored in row 4 of the Equipment Faceplate)
   #9=::[CLX]My_E3_Plus_Motor_3
                                         (This will represent the device monitored in row 9 of the Equipment Faceplate)
 **NOTE: YOU MUST CONFIGURE ALL 9 Parameter numbers representing each of the 9 rows, respectively
        for the Equipment Status Faceplate. If you are not planning on using 9 devices for the Equipment Status
        Faceplate, fill in the remaining parameters with the last device used, ie. In the example above, only
        4 devices are configured for the Equipement Faceplate, therefore the remaining rows 5-9 are configured the
        same as the last device in row 4.
 **NOTE: Configure parameter #1 with the name of the device that has the "Inp_NumRowsVis" configured in its energy
        object tag (_BEO) to represent the actual number of rows to appear on the Equipment Status Faceplate.
 **NOTE: The parameters will be combined with _FP or _BEO within the faceplate to form valid tagnames.
#1=::[CLX]PF753
 #2=::[CLX]PF755
 #3=::[CLX]E3PLUS
 #4=::[CLX]SMC50
 #5=::[CLX]PF70EC
 #6=::ICLX1PF70EC
 #7=::[CLX]PF70EC
 #8=::[CLX]PF70EC
 #9=::[CLX]PF70EC
```

Each parameter #1...9 corresponds to the device to be displayed in each Equipment Status faceplate Row #1...9.

You must assign the #1 parameter to a device that includes the Inp\_NumRowsVis assignment in its energy object tag (DriveName\_BEO.Inp\_NumRowsVis).

- PF753_BE0	{}
+ PF753_BE0.Inp_NumRowsVis	5
+ PF753_BEU.Val_EnergyResourceType	1
+ PF753_BE0.Val_BaseEnergyObjCap	0
+ PF753_BE0.Val_EnergyAccuracy	0
+ PF753_BE0.Val_ConsEnergyOdo	()
+ PF753_BE0.Val_GenEnergyOdo	()
+ PF753_BE0.Val_TotalEnergyOdo	()

The remaining parameters #2...9 must be assigned to valid device names for the Equipment Status faceplate to operate without errors, even if corresponding Equipment Status faceplate rows are not being used. It is recommended to fill in the unused parameters with the last valid AOI tag name.

## Configure Goto Buttons on the Equipment Status Faceplate with Energy

To configure the goto buttons on the equipment status faceplate with energy, follow the same steps as shown on Configure Goto Buttons on the Equipment Status Faceplate, beginning on <u>page 142</u>, for the standard equipment status faceplate.

# Notes:

# System Commissioning

In this chapter you download your Logix5000 and PanelView Plus applications, prepare and tune your drive hardware, verify network communications, and verify general operator/program control.

# **Before You Begin**

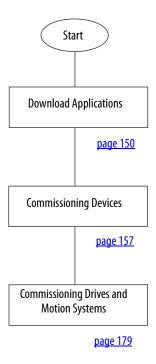
- Complete your logic configuration (refer to <u>Chapter 4</u>) or complete <u>Appendix G</u>
- Complete your FactoryTalk View Machine Edition configuration (refer to Chapter 5)

## What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative
- RSLogix 5000 software, version 19.0 or later, or the Logix Designer application, version 21.0 or later.
- RSLogix 5000 software, version 20.0 or later or the Logix Designer application, version 21.0 or later, to configure Kinetix 350 servo drives, and when using ControlLogix 1756-L7*x*S controllers.
- FactoryTalk View Studio software, version 5.10 or later
- The user manual for your Drives and Motion hardware. Refer to <u>Additional Resources</u> on <u>page 15</u> for publication numbers.

# **Follow These Steps**

Complete these steps to complete the commissioning process for your drives and motion application.



# **Download Applications**

This section provides general steps for downloading the Logix Designer project to the controller, and downloading the FactoryTalk View project to the PanelView Plus terminal.

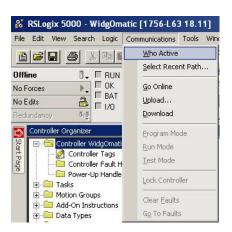
## **Download Logix Designer Project**

Follow these steps to download your Logix Designer project file to the Logix5000 controller.

**IMPORTANT** The download steps assume controller power and communication wiring is connected, controller power is applied and RSLinx communication driver is configured. Refer to <u>Appendix D</u>, on <u>page 257</u>, for more information on these topics.

1. Open your Logix Designer project file.

2. From the Communications menu, choose Who Active.



The Who Active dialog box opens.

Autobrowse Refresh	
E 📕 Workstation, ROCKWELL-446DB9	<u>G</u> o Online
田一器 Linx Gateways, Ethernet 日一器 Widg-O-matic, Ethernet	Upload
☐	
<ul> <li>00, 1756-L63 LOGIX5563, WidgOmatic</li> <li>01, 1756-EN3TR, 1756-EN3TR/A</li> </ul>	Update <u>F</u> irmware
<ul> <li>         ⊕ 02, 1756-M165E, 16 Axis SERCOS interface         ⊕         ⊕ 03, 1756-L63 LOGIX5563, RealTimeAttributeLogging         </li> </ul>	Close
	Help
ath: Widg-0-matic\192.168.1.101\Backplane\0	Set Project Path
ath in Project: Widg-O-matic\192.168.1.101\Backplane\0	Clear Project Path

- 3. Browse to and select your Logix5000 controller and click Set Project Path.
- 4. Verify the key switch on your controller module is in the REM (remote) position.
- 5. Click Download.

The Download dialog box opens.

- 6. Click Download.
- 7. From the Communications menu, choose Run mode to switch the controller to Run mode.



## **Configure and Download FactoryTalk Project to PanelView Plus Terminal**

**IMPORTANT** These download steps assume PanelView Plus power and communication wiring is connected, PanelView Plus terminal power is applied.

## Create a New RSLinx Enterprise Configuration

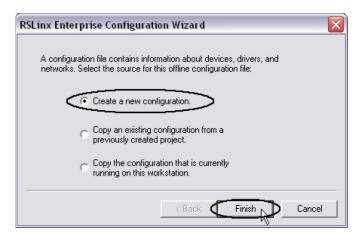
In this example, we use RSLinx Enterprise software to configure communication between your personal computer and/or PanelView Plus terminal and your system's Logix5000 controller.

Follow these steps to create a New RSLinx Enterprise configuration.

- 1. Open your HMI project file in FactoryTalk View Studio software.
- 2. Expand RSLinx Enterprise and double-click Communication Setup

Explorer	2
🖃 🎻 Local (CORE)	
E PowerFlex	
🖻 🦺 PowerFlex	
🕀 🧰 System	
😟 🧰 HMI Tags	
🕀 🧰 Graphics	
😟 🧰 Alarms	
🕀 🧰 Information	
🕀 🧰 Logic and Control	
🕀 🧰 Data Log	
😟 🧰 RecipePlus	
🖻 🏪 RSLinx Enterprise	
Communication Setup	
± ⊆ System	
Application Communications	

The RSLinx Enterprise Configuration Wizard opens.



- 3. Select Create a new configuration.
- **4.** Click Finish.

## Configure Design (Local) Communication

The local tab in Communication Setup reflects the view of the topology from the RSLinx Enterprise server on the development computer. In this example, the development computer is configured to communicate with an L63 ControlLogix controller via Ethernet.

Follow these steps to setup the Design Time path.

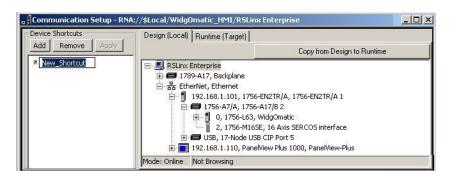
- 1. Expand your system's Ethernet network.
- 2. Expand your system's Ethernet module.
- **3.** Expand your controller bus or backplane.
- 4. Select your system's controller.

In this example, the controller is a ControlLogix 1769-L63 controller.

5. Click Add.

A new device shortcut appears.

6. Name the shortcut.



For this example, the shortcut is named CLX.

7. Select the new device shortcut and the controller.

For this example, CLX shortcut and 1756-L63 controller is selected.

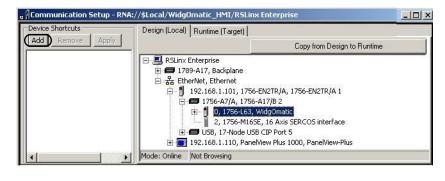
8. Click Apply.

A verification dialog box appears showing that the shortcut was assigned to the design path.

9. Close the verification dialog box.

, Communication Setup - RNA://\$Local/WidgOmatic\_HMI/RSLinx Enterprise \_ 🗆 × Shortcuts Design (Local) Runtime (Target) Add Remove Apply Copy from Design to Runtime CLX 🖃 🖳 RSLinx Enterprise 📾 1789-A17, Backplane 器 EtherNet, Ethernet 192.168.1.101, 1756-EN2TR/A, 1756-EN2TR/A 1 📾 1756-A7/A, 1756-A17/B 2 0, 1756-L63, WidgOmatic 2, 1756-M16SE, 16 Axis SERCOS interface 🖅 🛲 USB, 17-Node USB CIP Port 5 🗄 🦲 192.168.1.110, PanelView Plus 1000, PanelView-Plus Mode: Online Not Browsing Offline Tag File Browse ... OK Cancel Verify Help

The Apply button dims indicating the shortcut is attached to the path.



## Configure Runtime (Target) Communication

The target tab displays the offline configuration from the perspective of the device that will be running the application and comprises the topology that will be loaded into a PanelView Plus or PanelView Plus CE terminal.

Follow these steps to copy the configuration from Design time to Runtime.

1. Click Copy from Design to Runtime.

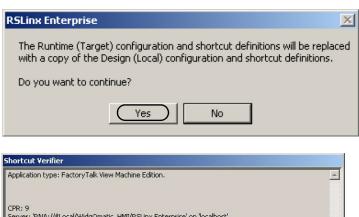
n ICommunication Setup - RNA:,	//\$Local/WidgOmatic_HMI/R5Linx Enterprise		
Device Shortcuts	Design (Local) Runtime (Target)		
Add Remove Apply		Copy from Design to Runtime	1
× CIX		interface	
Offline Tag File			Browse
		OK Cancel V	erify Help

This RSLinx Enterprise dialog box opens.

- 2. Click Yes.
- **3.** Click Verify to make sure communication is setup correctly.

The Shortcut Verifier dialog box opens.

4. Verify that the path to the Design device and



- 5. Click Close.
- 6. Click OK to save the configuration.

the Runtime device are assigned.

Application type: FactoryTalk View Machine Edition.	<u> </u>
CPR: 9 Server: 'RNA://\$Local/WidgOmatic_HMI/RSLinx Enterprise' on 'localhost'.	
Shortcut 'CLX': - Note: Path to Design device is assigned [Logix Device], - Note: Path to Runtime device is assigned [Logix Device],	
1	¥ F
How to use the Shortcut Verifier	Close

- 🗧 🖆 📰 -

? ×

## Create Your FactoryTalk View Runtime Application File

Follow these steps to create a runtime file for downloading to a PanelView Plus terminal.

FactoryTalk View Studio - Machine Editio
 File View Application Tools Window Help

Iest Application Create Runtime Application

Save in: 🗀 Runtime

Create Runtime Applicatio

1. From the Application menu, choose Create Runtime Application.

The Create Runtime Application dialog box opens.

- 2. From the Save as type pull-down menu, choose Runtime 5.10 Application (\*.mer).
- 3. Enter a File Name for the application.

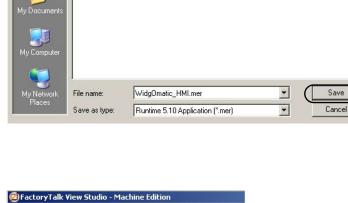
For the Widg-O-matic application example, the file name is WidgOmatic\_HMI.mer.

4. Click Save.

The Runtime application (\*.mer) file is created. This may take a few minutes.

## Download Runtime File to PanelView Plus Terminal

- 1. Open FactoryTalk View Studio Machine Edition software.
- 2. From the Tools menu, choose Transfer Utility.





The Transfer Utility window opens.

Download	Upload	Compare Down
Source file:		E×
		( ) He
Download as:		
Destination storage type: Internal Storage	WARNING:	
	Include a goto configur	e mode button in your application if configuration mode screens.

3. Click and browse to the runtime file.

The Select File to Download dialog box opens.



4. Select the runtime file you created earlier.

For the Widg-O-matic application example, WidgOmatic\_HMI is selected.

- 5. Click Open.
- 6. Select the PanelView Plus terminal.

Download	Upload	Compare	Downlo
Source file:			Exit
C:\Documents and Settings\All Users\Documents\P	RSView Enterprise\ME\Runtime\WidgOma	tic_HMI.mer	Help
Download as: WidgOmatic_HMI			
Destination storage type:			9
Internal Storage 🗾	WARNING:		
Run application at start-up		mode button in your application if	
When application runs:		configuration mode screens.	
Delete Log Files	Include a shutdown butt be able to shut it down	on in your application if you want to	
lect destination terminal:			
- 🗐 RSLinx Enterprise, ROCKWELL-446DB9			
由 📟 1789-A17, Backplane 🔄 器 EtherNet, Ethernet			
	-EN2TR/A		
	PanelView Plus 1000 2		

7. Click Download.

The file transfers to the PanelView Plus terminal.

- 8. Click OK when transfer is complete and prompted to do so.
- 9. Click Exit, to close the Transfer Utility window.
- 10. From the File menu, choose Exit to close FactoryTalk View software.

# **Commissioning Devices**

This section provides general procedures for preparing and verifying the function of CIP Motion, sercos, and PowerFlex drives, electronic overload relays, and ArmorStart distributed motor controllers.

**IMPORTANT** These commissioning procedures assume that drive power and communication wiring is connected and a personal computer with the Logix Designer application and internet browser is available.

## **Commissioning CIP Motion Drives**

These CIP Motion drive commissioning procedures apply to Kinetix 6500, Kinetix 5500, Kinetix 350, PowerFlex 527, and PowerFlex 755 drives.

For more information on drive commissioning for these CIP Motion drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Set the Base Address

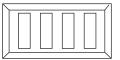
- For the Kinetix 6500 drives, set the base EtherNet/IP address on the IAM power module by using the node address switches. In multi-axis configurations, these switches set the addresses for all of the drives on the power rail.
- For Kinetix 5500 and PowerFlex 527 drives, set the EtherNet/IP address via the drive display soft menus and navigation buttons. Set parameters via path Network>Static IP>IP address.

**IMPORTANT** You must cycle control power to make Kinetix 5500 and PowerFlex 527 network configuration changes persistent.

- For the Kinetix 350 drives, set the EtherNet/IP address via the drive display and keypad. Set parameters IP\_1, IP\_2, IP\_3, and IP\_4.
- For the PowerFlex 755 drives, set the base address using the rotary switches on the main control board.

## Apply Power to the Drive

For the Kinetix 6500 drives, apply control power to the IAM power module and observe the four-character display. If the four-character display is ON, apply three-phase power.

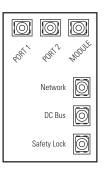


Four-character Display

Kinetix 6500 Status Indicators

#### **Control Module Status Indicators**

Status Indicator	Status
Module	Steady green (normal operation)
Network	Steady green (normal operation)
Bus	Flashing green (bus power is up, drive disabled, no major faults)



For the Kinetix 5500 drives, apply power as required for your system configuration and observe the two status indicators.

#### **Module Status Indicator**

Condition	Status	
Steady Off	No power applied to the drive.	
Steady Green	Drive is operational. No faults or failures.	
Flashing Green	Standby (drive not configured).	
Flashing Red	Major recoverable fault. The drive detected a recoverable fault, for example, an incorrect or inconsistent configuration.	
Steady Red	Major fault. The drive detected a non-recoverable fault.	
Flashing Green/Red	Self-test. The drive performs self-test during powerup.	

Network Status Indicator

Condition	Status
Steady Off	No power applied to the drive or IP address is not configured.
Flashing Green	Drive connection is not established, but has obtained an IP address.
Steady Green	Drive connection is established. Normal operation.
Flashing Red	Connection timeout. One or more of the connections, for which this drive is the target, has timed out.
Steady Red	Duplicate IP address. IP address specified is already in use.
Flashing Green/Red	Self-test. The drive performs self-test during powerup.

For the Kinetix 350 drives, apply 120, 240, or 460V AC mains input power to the IPD connector. If logic power is from (24V DC) back-up power, apply backup power to the BP connector first and then apply input power.

#### **Drive Status Indicators**

Status Indicator	Status	Status
	Flashing red/green or flashing green	Self-test/no connections
Network	Steady green	Communication is ready
	Steady or flashing red	Communication error
	Flashing red/green or flashing green	Self-test/standby
Module	Steady green	Operational condition
	Steady or flashing red	Drive is faulted
	Flashing red/green, flashing green, flashing amber	Self-test/initialization
Axis	Steady green	Operational condition
	Steady or flashing red	Drive is faulted

 N
 Kinetix 350

 M
 Status Indicators

🗆 A

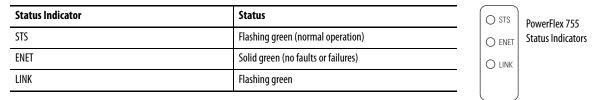
Kinetix 5500 Servo Drive

Module Status

Network Status

For the PowerFlex 755 drives, apply control power first, if using an auxiliary power supply option, and then apply three-phase drive power.

#### **Drive Status Indicators**



For the PowerFlex 527 drives, apply power and wait for the startup sequence to complete. Verify that the MOD and NET status indicators are steady green.

#### **Drive Status Indicators**

Status Indicator	Status	
MOD	Steady green (no faults or failures)	MOD O PowerFlex 527 NET O Status Indicators
NET	Steady green (no faults or failures)	LINKAO
LINK A, LINK B	Flashing green	LINKBO

## Four-character Status Indicator Display

The Kinetix 6500 and PowerFlex 755 drive displays should be scrolling STOPPED. The drives may take up to 60 seconds to reach the STOPPED (ready) state.

Four-character Message	Drive Status
BOOT, INIT, LOAD, DONE, TEST	The drive is initializing. This sequence of four-character words continues to scroll up to three times.
Scrolling FW Version: x.xxx	The drive is scrolling the current drive firmware revision.
Scrolling IP = 192.168.1.1	The drive is scrolling the drive IP address.
Scrolling CONFIGURING	The drive is receiving configuration information from the controller.
Scrolling STANDBY	The drive is trying to establish communication with the Logix5000 EtherNet/IP module.
Scrolling STOPPED	The drive is fully configured, but the control loops are not enabled.
Scrolling error code message	The drive is faulted. Refer to drive user manual.

#### Kinetix 6500 and PowerFlex 755 Status Display

The Kinetix 350 four-character display should be displaying -00-.

## LCD Display

For the Kinetix 5500 drives, the home screen displays PRECHARGE after completing the startup sequence.

#### Axis States on the Home Screen

Axis State	Description
STANDBY	The drive is waiting to receive configuration information from the controller.
CONNECTING	The drive is trying to establish communication with the EtherNet/IP controller.
CONFIGURING	The drive is receiving configuration information from the controller.
SYNCING	The drive is waiting for a successful Group Sync service.
STOPPED	The drive is fully configured, but the control loops are not enabled.
PRECHARGE	The drive is ready for mains input power.
STARTING	The drive is enabled and checking various conditions before entering the RUNNING or TESTING state. For example, the drive checks the Brake Release delay time during the STARTING state.
RUNNING	<ul> <li>The drive is enabled, configured with an active control mode, and actively tracking a command.</li> <li>The drive is configured for No Control and is fully operational.</li> </ul>
TESTING	The drive is actively executing a test procedure, for example, a hookup test.
STOPPING	The drive is decelerating to a stop as the result of a disable.
ABORTING	The drive is decelerating to a stop as the result of a fault or an abort request.
MAJOR FAULTED	The drive is faulted due to an existing or past fault condition.
START INHIBITED	The drive has an active condition that inhibits it from being enabled.
SHUTDOWN	The drive has been shut down.

PRECHARAGE 192.168.1.1 DC BUS: 0.3V

Kinetix 5500 Home Screen Display The PowerFlex 527 drive initializes upon startup and status information scrolls across the LCD display. After initialization, the Device/Axis state is shown on the LCD display. In this example, the current state is STANDBY.

Device State	Description
STANDBY	The drive is waiting to receive configuration information from the controller.
CONNECTING	The drive is trying to establish communication with the EtherNet/IP controller.
CONFIGURING	The drive is receiving configuration information from the controller.
SYNCING	The drive is waiting for a successful Group Sync service.
CONN_TIMEOUT	The drive is trying to establish communication with the EtherNet/IP controller, but the connection has timed out.
DUPLICATE_IP	The drive has detected another device on the network with the same IP address.
FWUPDATE	The drive is updating the firmware.

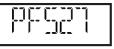
Axis States	Description
INITIALIZING	The drive is waiting to receive configuration information from the controller.
PRECHARGE	The drive is ready for mains input power.
STOPPED	The drive is fully configured, but the control loops are not enabled.
STARTING	The drive is enabled and checking various conditions before entering the RUNNING or TESTING state. For example, the drive checks the Brake Release delay time during the STARTING state.
RUNNING	<ul> <li>The drive is enabled, configured with an active control mode, and actively tracking a command.</li> <li>The drive is configured for No Control and is fully operational.</li> </ul>
TESTING	The drive is actively executing a test procedure, for example, a hookup test.
STOPPING	The drive is decelerating to a stop as the result of a disable.
ABORTING	The drive is decelerating to a stop as the result of a fault or an abort request.
MAJOR FAULTED	The drive is faulted due to an existing or past fault condition.
START INHIBITED	The drive has an active condition that inhibits it from being enabled.
SHUTDOWN	The drive has been shut down.

## Test and Tune the Axis

Use the Logix Designer application to access Axis Properties and run the Hookup test and Tune test.

- The Hookup test verifies encoder connections and direction.
- The tuning values for position units, velocity gains, acceleration, and deceleration rates are set in Axis Properties based on the drive/motor combination and motor inertia only. The Autotuning procedure calculates the gain values dynamically after determining inertia.

For more information on test and tune procedures, refer to the appropriate user manual listed in <u>Additional</u> <u>Resources</u> on <u>page 15</u>.





LCD Display

## **Commissioning Sercos Drives**

These sercos interface drive commissioning procedures were written specifically for Kinetix 6200 drives. The Kinetix 6000, Kinetix 2000, Kinetix 7000, and Ultra3000 sercos drive configuration steps are similar. You can also use the Kinetix 6000M integrated drive-motor (IDM) system when the IDM power interface module (IPIM) is added to the Kinetix 6000 power rail.

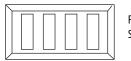
For more information on drive commissioning for sercos drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Set the Base Address

Set the base sercos address on the IAM power module by using the node address switches. In multi-axis configurations these switches set the addresses for all of the drives on the power rail.

## Apply Power to the Drive

Apply control power to the IAM power module and observe the fourcharacter display. If the four-character display is ON, apply three-phase power.



Four-character Status Indicator

## Four-character Status Indicator Display

Four-character Status Indicator	Status
Scrolling CP-0	The drive is looking for a closed sercos ring (phase 0). Wait for CONFIGURING or take corrective action.
Scrolling CP-1	The drive is looking for active nodes (phase 1). Wait for CONFIGURING or take corrective action.
Scrolling CP-2	The drive is configuring nodes for communication (phase 2). Wait for CONFIGURING or take corrective action.
Scrolling C O N F I G U R I N G	The drive is configuring device specific parameters (phase 3). When phase 4 is reached the drive displays the drive state.
Scrolling drive state (for example, S H U T D O W N or S T O P P E D)	The drive is configured and active (phase 4).
Scrolling error code message	Drive is faulted.

## **Control Module Status Indicators**

Status Indicator	Status	[
Drive	Steady green (normal operation)	_ <u>_</u>
Comm	Steady green (no faults or failures)	Ŕ
Bus	Flashing green (bus power is up, drive disabled, no major faults)	



Kinetix 6200 Status Indicators

## Test and Tune the Axis

Use the Logix Designer application to access Axis Properties and run the Hookup test and Tune test.

- The Hookup test verifies encoder connections and direction.
- The tuning values for position units, velocity gains, acceleration, and deceleration rates are set in Axis Properties based on the drive/motor combination and motor inertia only. The Autotuning procedure calculates the gain values dynamically after determining inertia.

For more information on test and tune procedures for sercos drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## **Commissioning PowerFlex 7-class Drives**

These commissioning procedures cover PowerFlex 70EC, PowerFlex 700, PowerFlex 753, and PowerFlex 755 drives.

For more information on drive commissioning, refer to the appropriate user manual listed in <u>Additional</u> <u>Resources</u> on <u>page 15</u>.

## Apply Power to the Drive

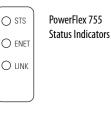
Apply control power first if using an auxiliary power supply option, and then apply three-phase drive power.

## **Status Indicators**

Verify the drives are ready.

## **PowerFlex 755 Drive Status Indicators**

Status Indicator	Status	
STS	Flashing green	
ENET	Solid green	
LINK	Flashing green (indicating network activity)	



#### **PowerFlex 753 Drive Status Indicators**

Status Indicator	Status
STS	Flashing green



#### PowerFlex 700 Drive Status Indicators

Status Indicator	Status
Pwr	Solid green
STS	Flashing green
Port	Flashing green (depending on communication module)

#### **PowerFlex 70 EC Drive Status Indicators**

Status Indicator	Status
STS	Flashing green
Port	Flashing green (depending on communication module)

# PORT O MOD O NET A O NET B O STS O

PWR O

STS

0

PORT O MOD O NET A O NET B O PowerFlex 700 Status Indicators

## Start-up Routines

Start-up routines are available for the PowerFlex 7-class drives through

Assisted Start-Up on the HIM module or the Start-Up Wizard from one of the software tools. The start-up routines do not apply for a PowerFlex 755 drive used in CIP Motion applications.

- The drive-mounted HIM module provides an assisted start-up and will step through configuration and tuning.
- A software-based start-up wizard is available in DriveExplorer<sup>™</sup> software, DriveTools<sup>™</sup>, or with the Custom Download AOP for the PowerFlex 7-class drives. The start-up wizard steps through configuration and tuning.

For more information on drive start-up routines for PowerFlex 7-class drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on page 15.

## **Commissioning PowerFlex 5-class Drives**

These commissioning procedures apply to PowerFlex 525 AC drives.

For more information on drive commissioning, refer to the appropriate user manual listed in <u>Additional</u> <u>Resources</u> on <u>page 15</u>.

## Apply Power to the Drive

Apply single or three-phase power to the respective PowerFlex 525 AC drive.

## **Status Indicators**

Verify that the drives are ready.

## **PowerFlex 525 Status Indicators**

Display	Display State	Description	PowerFlex 525 Status Indicators
	Off	Adapter is not connected to the network.	
ENET	Steady	Adapter is connected to the network and the drive is controlled through Ethernet.	
	Flashing	Adapter is connected to the network, but the drive is not controlled through Ethernet.	EtherNet/IP
	Off	Adapter is not connected to the network.	FAULT
LINK	Steady	Adapter is connected to the network, but not transmitting data.	
	Flashing	Adapter is connected to the network and transmitting data.	
FAULT	Flashing red	Indicates the drive is faulted.	

## Start-up Routines

The drive integral keypad and LCD display can assist in configuration and start-up by organizing the commonly used parameters into the basic group. A software-based start-up wizard is available in Connected Components Workbench<sup>™</sup> software, or with the RSLogix 5000 / Studio 5000 Add-On Profile (AOP) for the PowerFlex 525 AC drive. The start-up wizard steps you through configuration and tuning.

For more information on the PowerFlex 525 drives, refer to the appropriate user manual listed in <u>Additional</u> <u>Resources</u> on <u>page 15</u>.

## **Commissioning PowerFlex 4-class Drives**

These commissioning procedures apply to PowerFlex 4, PowerFlex 40, PowerFlex 40P, and PowerFlex 400 drives.

For more information on drive commissioning, refer to the appropriate user manual listed in <u>Additional</u> <u>Resources</u> on <u>page 15</u>.

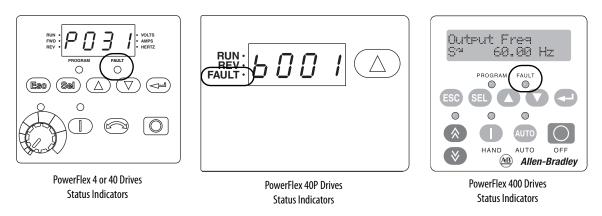
## Apply Power to the Drive

Apply control power first if using an auxiliary power supply option, and then apply three-phase drive power.

## Status Indicators

Drives are ready when the Fault status indicator is off.

## PowerFlex 4, 40, 40P, and 400 Drive Status Indicators



## Start-up Routines

The drive integrated keypad can assist in configuration and start-up by organizing the commonly used parameters into the basic group. An assisted start-up routine is available for the PowerFlex 4-class drives through the Start-Up Wizard from one of the software tools. The software-based start-up wizard is available in DriveExplorer software, DriveTools, or with the Custom Download AOP for the PowerFlex 4-class drives. The start-up wizard steps through configuration and tuning.

For more information on drive start-up routines for PowerFlex 4-class drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on page 15.

## **Commissioning Kinetix 300 Drives**

These commissioning procedures apply specifically to the Kinetix 300 drives.

For more information on drive commissioning for Kinetix 300 drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Apply Power to the Drive

If using separate 24V DC logic power, apply 24V DC and observe the four-character display. If the four-character display is ON, apply mains drive power. If not using separate 24V DC logic power, apply mains drive power.

## **Status Indicators**

Verify the drives are ready.

## Four-character Display Status Indicators

Status Indicator	Function	Description	Kinetix 300 Status Indicators
А	Enable	Orange status indicator means that the drive is enabled (running).	
В	Regen	Yellow status indicator means the drive is in Regeneration mode.	
C	Data entry	Yellow status indicator flashes when changing.	
D	Drive fault	Red status indicator illuminates upon a drive fault.	
E	Comm activity	Green status indicator flashes to indicate communication activity.	

## Configure the Drive

Use MotionView OnBoard software to configure the drive/motor combination and the mode required for your application.

## Test and Tune the Drive

Use MotionView OnBoard software to run the Hookup test and Tune test.

- For testing the drive if using an incremental encoder, use MotionView OnBoard software to perform the Check Phasing test. This test isn't required if using an absolute encoder.
- For tuning the drive, use MotionView OnBoard software to perform Autotuning. The Auto Tune procedure calculates the gain values dynamically after determining inertia. To perform Auto Tune, the drive must be in Auto Tune mode.

For more information on test and tune procedures for Kinetix 300 drives, refer to the appropriate user manual listed in <u>Additional Resources</u> on page 15.

## **Commissioning E3 Plus Overload Relays**

These commissioning procedures apply specifically to the E3 Plus overload relays when communicating with the 193-DNENCAT module.

For more information on commissioning for E3 Plus overland relays, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Apply Power to the Relay

When power is applied to the DeviceNet connector, the trip relay closes if no fault exists, and the NETWORK STATUS indicator flashes green. When the E3 Plus overload relay has been allocated by a Master, the NETWORK STATUS indicator turns solid green. If a fault exists, the TRIP/WARN status indicator flashes.

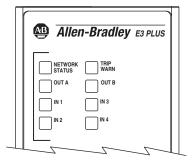
## Status Indicators

The E3 Plus overload relay provides the following status indicators.

## E3 Plus Status Indicators

Status Indicator	Function	Description
Network Status	DeviceNet network status	Refer to the E3 and E3 Plus Solid-state Overload Relay User Manual, publication <u>193-UM002</u> .
Trip/Warn	Device status	The Trip/Warn status indicator indicates device status by flashing a red trip code or an amber warning code. The flash pattern followed by a pause identifies the specific trip or warning. Refer to the E3 and E3 Plus Solid-state Overload Relay User Manual, publication <u>193-UM002</u> .
OUT A	Output command	The amber OUT A or OUT B status indicator illuminates when the output is commanded on. However, an illuminated status indicator does not guarantee that the output is actually on.
OUT B	status	
IN 1		
IN 2	Customer-supplied	The amber IN1, IN2, IN3, or IN4 status indicator illuminates when a customer-
IN 3	contact status	supplied contact is closed.
IN 4		

E3 Plus Status Indicators



## DeviceNet Commissioning

- 1. Launch RSNetWorx for DeviceNet software.
- 2. Add the E3 Plus overload relay to your network configuration.
- 3. Open the Motor Overload folder and double-click the desired E3 Plus overload relay.
- 4. Assign the node number and desired name for the E3 Plus overload relay.
- 5. Click the Parameters tab.

#### 6. Set the following parameters:

Parameter	Value
59, Output Assembly	105
60, Input Assembly	100
61, Assy Word 0 Param	21 (Param 21 supplies status of Inputs and Outputs)
62, Assy Word 1 Param	4 (Param 4 supplies Avg current)
63, Assy Word 2 Param	14 (Param 14 supplies Trip Status)
64, Assy Word 3 Param	15 (Param 15 supplies Warning Status)

**IMPORTANT** You must set these parameters or the AOI will not verify in your Logix Designer application.

- 7. Refer to the E3 and E3 Plus Solid-state Overload Relay User Manual, publication <u>193-UM002</u>, to determine which trips and warnings to enable and which corresponding parameter limits to configure.
- 8. Add the DeviceNet scanner to your network.
- 9. Assign the desired name and node number for the scanner.
- **10.** Click the Scanlist tab.
- 11. Select your E3 Plus overload relay from the Available Devices dialog box and using the arrows, move the E3 Plus overload relay to the Scanlist dialog box.

## **Commissioning E300 Electronic Overload Relays**

These commissioning procedures apply specifically to the E300 electronic overload relays.

For more information on drive commissioning for E300 electronic overload relays, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Set the IP Address

1. Slide the relay cover down revealing the node address switches and network display.

The IP address is set to 999 and DHCP is enabled as the factory default settings.

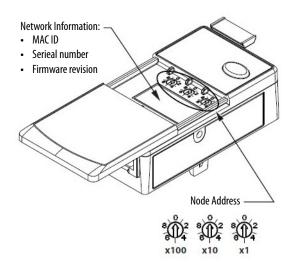
2. Set the network address by adjusting the three rotary switches.

Valid IP addresses are 001 through 254. When the switches are set to a valid number, the IP address will be 192.168.1.xxx (where xxx represents the last octet set on the switches).

The subnet mask is set to 255.255.255.0 and the gateway address is set to 0.0.0.0.

Cycle power to the E300 relay by removing/replacing the 120V AC connector behind the EtherNet/IP ports.

**IMPORTANT** You must cycle power when the IP address switches are used for the new setting to take effect.



Node Address	Function
001254	Set IP address to 192.168.1.xxx
255887 889999	Set IP address via DHCP or use static IP address
888	Reset to factory defaults
000	Administrative mode

## Apply power to the E300 Electronic Overload Relay

Refer to the E300 Electronic Overload Relay User Manual, publication <u>193-UM015</u>, and apply power to your E300 device.

## Interpret Status Indicators

Observe the status indicators to make sure the device is ready. The E300 relay provides status indicators and a reset button on the front of the module.

## E300 Front Panel Status Indicators



## E300 Electronic Overload Relay Status Indicators

Status Indicator	Display State	Description	
	Blinking green	Device ready, Operation mode.	
	Solid green	Device active, current detected, Run mode.	
POWER	Solid red	Device error.	
	Blinking red	Communication error.	
	Blinking red/green	Copy cat in progress.	
TRIP/WARN	Blinking red	Trip event.	
TRIP/WARN	Blinking yellow	Warning event.	
	None	Module is not receiving power.	
	Green, red, not illuminated sequence	Normal power-up sequence.	
MS	Blinking green	Module is not being scanned by the EtherNet/IP master.	
(module status)	Solid green	Normal operating state. Module is allocated to a master.	
	Blinking red	One or more EtherNet/IP connections timed out. Module is faulted.	
	Solid red	Diagnostics test failed on power-up or reset.	
	None	Module is not receiving power.	
	Green, red, not illuminated sequence	Normal power-up sequence.	
	Blinking green	Module is online, but with no connections established.	
NS	Solid green	Normal operating state. Module is allocated to a master.	
(network status)	Blinking red	One or more EtherNet/IP connections timed out.	
	Solid red	Diagnostics test failed on power-up or reset: • Internal fault • Duplicate IP address • Communication error	
	None	Module is not properly connected to the EtherNet/IP network.	
LINK1, LINK2	Blinking green	The EtherNet/IP network is properly connected.	
	Solid green	EtherNet/IP network is communicating.	

## Configure the E300 Electronic Overload Relay

Follow these steps to configure your E300 device using the E300 Web server.

1. Turn all three of the node-address rotary switches to 0.

This sets the device in Administrative mode.

- 2. Cycle power on the device by removing/replacing the 120V AC connector behind the EtherNet/IP ports.
- 3. Enter the IP address of the E300 relay (192.168.1.10) in the browser's URL window.
- 4. Press Enter to access the web server.

The device is now in Administrative mode. You can modify parameter settings by using the E300 Web server.

(a) (b) (http://192.168.1.10/		P → C 📓 Rockwell Automation ×	
File Edit View Favorites Tools	Help		
Allen-Bradley E30	0 4In3Out120VAC	VIGPt5to30Amp	Rockwell Automation
Expand Minimize	Home		
Parameters	Device Name	E300 4In3Out120VAC VIGPt5to30Amp	
Device Monitor	Device Description		
Current Monitor	Device Location		
Voltage Monitor	Ethernet Address (MAC)	00:1D:9C:F0:8E:4A	
Power Monitor	IP Address	192.168.1.10	
Energy Monitor	Product Revisions:		Resources
Analog Monitor     Trip/Warn Histry     Trip Snapshot     Command     Overload Setup     Device Setup     Options Setup	E300 Overload Relay 139=ECM-ETR Application 139=ECM-ETR Application 139=ECM-ETR FIG Application 139=ECM-ETR FIG Application 139=E10 Boot Code 139=E10 Boot Code 139=E10 Boot Code 139=E10 Boot Code 139=E10 Boot Fides	5.048 Build 6 1.004 Build 1 2.001 Build 1 1.002 Build 2 2.000 Build 2 2.000 Build 2 2.000 Build 1 1.001 Build 1 1.001 Build 1	Visit AB.com for additional information Contacts
Current Setup	Firmware Version Date	Oct 7 2014, 11:25:52	
Comms Setup	Serial Number	600600C8	
Output Setup	Status	Run	
DeviceLgx Setup Voltage Setup Power Setup DiagDsply Setup	Uptime	0 days, 0h:56m:8s Seconds Between Refresh: 15 Disable Refresh with 0.	
Analog1 Setup	Copyright © 2012 Rockwell Automation, :		

For more information on the E300 Web server and parameter setup, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## **Commissioning SMC-50 Soft Starter Modules**

These commissioning procedures apply specifically to the SMC-50 soft starter modules.

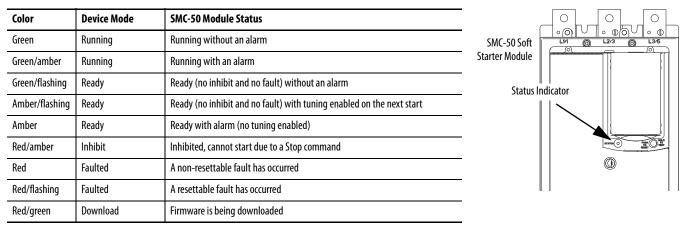
For more information on drive commissioning for SMC-50 soft starters, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Apply Power to the Relay

Apply power to the SMC-50 soft starter module.

## Status Indicators

The SMC-50 soft starter has one status indicator on the front of the module that displays fault and alarm codes as described in the following table.



## SMC-50 Module Status Indicator

## Startup Routines

Start-up routines are available for the SMC 50 soft starter through the Start-Up Configuration Tool on the 20-HIM-A6, 20-HIM-C6S module, or the Start-Up Wizard available in DriveExplorer software. The start-up wizard steps through general configuration.

For more information on the SMC-50 soft-starter startup routine, refer to the SMC-50 Solid-state Smart Motor Controller User Manual, publication <u>150-UM011</u>.

## **Commissioning ArmorStart LT Distributed Motor Controllers**

These commissioning procedures apply specifically to the Bulletin 290E, 291E and 294E ArmorStart LT distributed motor control devices.

For more information on drive commissioning for ArmorStart LT distributed motor controllers, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Set the IP Address

1. Remove the protective caps from the IP address rotary switches on the front of the module.

The IP address is set to 999 and DHCP is enabled as the factory default settings.

2. Set the network address by adjusting the three rotary switches.

Valid IP addresses are 001 through 254. When the switches are set to a valid number, the IP address will be 192.168.1.xxx (where xxx represents the last octet set on the switches).

The subnet mask is set to 255.255.255.0 and the gateway address is set to 0.0.0.0.

3. Cycle power to the ArmorStart device.

**IMPORTANT** You must cycle power when the IP address switches are used for the new setting to take effect.



## Apply power to the ArmorStart LT

Refer to the ArmorStart LT Distributed Motor Controller User Manual, publication <u>290E-UM001</u>, and apply power to your ArmorStart LT device.

## Interpret Status Indicators

Observe the status indicators to make sure the device is ready. The ArmorStart LT motor controller provides status indicators and a reset button on the front of the module.

## ArmorStart LT Front Panel Status Indicators



## **ArmorStart LT Status Indicators**

Indicator	Description	Color_1	Color_2
PWR	The bicolor (green/yellow) status indicator indicates the state of the control voltage.	<ul> <li>Solid green indicates switched and unswitched control power is within its specified limits and has the proper polarity.</li> <li>Off indicates switched and/or unswitched power is not present.</li> </ul>	<ul> <li>Solid yellow is indicates switched or unswitched control power is outside its specified limits or has incorrect polarity.</li> <li>Flashing yellow indicates line voltage is not present (Bulletin 294 units only).</li> </ul>
RUN/FLT	The bicolor (green/red) status indicator combines the functions of the Run and Fault status indicators.	Solid green indicates a Run command is present.	Blinking red indicates a prescribed fault pattern when a protection fault (trip) condition is present.
NS (network status)	<ul> <li>The bicolor (green/red) network status indicator indicates the status of the Integrated Motion over EtherNet/IP network connection.</li> <li>Flashing bicolor (red/green) status indicator indicates a self-test on power up.</li> </ul>	<ul> <li>Flashing green indicates an IP address is configured, no integrated motion connections are established, and an Exclusive Owner connection has not timed out.</li> <li>Steady green indicates at least one integrated connection is established and an Exclusive Owner connection has not timed out.</li> </ul>	<ul> <li>Flashing red indicates the connection has timed out.</li> <li>Steady red indicates a duplicate IP address is detected.</li> </ul>
LS1 and LS2 (Link1 and Link2)	The bicolor (green/yellow) status indicators indicate the Link/Activity status of each EtherNetIP port.	Solid green indicates a link is established at 100 Mbps.	Solid yellow indicates a link is established at 10 Mbps.
MS (module status)	The bicolor (green/red) status indicator indicates the status of the module.	<ul> <li>Flashing green indicates the device has not been assigned an IP address.</li> <li>Steady green indicates the device is configured and operational.</li> </ul>	<ul> <li>Flashing red indicates a resettable protection fault exists or the node address switches have been changed without a power cycle and do not match the in-use configuration.</li> <li>Steady red indicates a non-resettable protection fault exists.</li> </ul>
I/O (status indicators 15)	These six yellow status indicators (numbered 05) indicate the status of the input/output connectors. One indicator for each I/O point.	Yellow indicates the input is valid or output is on.	Indicator is off when input is not valid or the output is not turn on.
Reset	The blue reset button causes a protection fault reset to occur.	_	_

## **Commissioning ArmorStart Distributed Motor Controllers**

These commissioning procedures apply specifically to the Bulletin 280E, 281E, and 284E ArmorStart distributed motor control devices.

For more information on drive commissioning for ArmorStart distributed motor controller, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## Set the IP Address

1. Remove the protective caps from the IP address rotary switches in the I/O section of the module.

The IP address is set to 999 and DHCP is enabled as the factory default settings.

2. Set the network address by adjusting the three rotary switches.

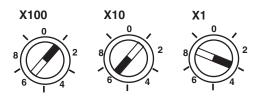
Valid IP addresses are 001 through 254. When the switches are set to a valid number, the IP address will be 192.168.1.xxx (where xxx represents the last octet set on the switches).

The subnet mask is set to 255.255.255.0 and the gateway address is set to 0.0.0.0.

3. Cycle power to the ArmorStart device.

**IMPORTANT** You must cycle power when the IP address switches are used for the new setting to take effect.





In this example, the final octet is set to 153 (DHCP).

## Apply power to the ArmorStart

Refer to the ArmorStart Distributed Motor Controller User Manual, publication <u>280E-UM001</u>, and apply power to your ArmorStart device.

## Interpret Status Indicators

Observe the control module status indicators to make sure the device is ready. The ArmorStart motor controller provides four status indicators and a reset button on the front of the module.

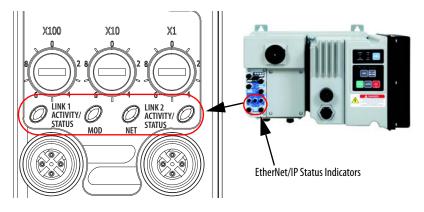
## **ArmorStart Front Panel Status Indicators**



#### ArmorStart Status Indicators

Status Indicator	Status	Recommended Action
POWER	Solid green indicates switched control power is present and has the proper polarity.	Make sure 24V DC is present on A1 and A2. Check if the local disconnect is in the OFF position.
RUN	Solid green when a start command and control power is present.	Make sure 24V DC is present on A1 and A3. Check if the user is properly commanding to RUN via Instance 162 or 166. See the ArmorStart Distributed Motor Controller User Manual, publication <u>280E-UM001</u> , for status indicator troubleshooting information.
NETWORK	This bicolor status indicator is used to indicate the status of the internal network connection.	See the <u>Network Status Indicator</u> table on <u>page 178</u> , for more information.
FAULT	When the unit is faulted, the unit responds with a specific blink pattern to identify the fault.	See the ArmorStart Distributed Motor Controller with EtherNet/IP User Manual, publication <u>280E-UM001</u> , for more information.

Observe the EtherNet/IP status indicators to make sure the device is ready.



Refer to these tables on the next page for status indicator descriptions:

- Link 1 or Link 2 Port Activity/Status (LINK 1 and LINK 2)
- Module Status Indicator (MOD)
- <u>Network Status Indicator</u> (NET)

## Link 1 or Link 2 Port Activity/Status

Status	Description	Recommended Action
OFF	No link established	Verify network cabling, and correct, as needed.
Green	Link established at 100 Mbps	None
Flashing green	Transmit or receive activity present at 100 Mbps	None
Yellow	Link established at 10 Mbps	None
Flashing yellow	Transmit or receive activity present at 10 Mbps	None

#### **Module Status Indicator**

Status <sup>(1)</sup>	Description	Requirement			
Steady OFF	No power	If no power is supplied to the device, the module status indicator shall be steady OFF.			
Steady Green	Device operational	If the dev	If the device is operating correctly, the module status indicator shall be steady green.		
Flashing Green	Standby	If the dev	vice has not been co	nfigured, the module status indicator shall be flashing green.	
Flashing Red	Minor fault		<ul> <li>If the device has detected a recoverable minor fault, the module status indicator shall be flashing red.</li> <li>An incorrect or inconsistent configuration would be considered a minor fault.</li> </ul>		
	Major fault	0	EEPROM Fault	Non-volatile memory value out of range for a local parameter or a write failure detected. This fault is also reflected by a solid red module status indicator.	
		1	Internal Comm2	The internal communication connection has timed out. This fault is also reflected by a flashing red module status indicator.	
Steady Red		2	Hardware Fault	Internal diagnostics checks failed. This fault is also reflected by a solid red module status indicator.	
		3	Control Module	<ul> <li>An illegal or unsupported control module product code or revision has been detected.</li> <li>No control module is detected on power up. This fault is also reflected by a solid red module status indicator</li> </ul>	
		415	Reserved	Reserved	
Flashing Green/ Red	Self-test	While the device is performing its power up testing, the module status indicator shall be flashing green/red.			

(1) Refer to Parameter 63 "Base Trip" for the Base Module Trip Status.

#### **Network Status Indicator**

Status	Description	Requirement	
Steady OFF	No power, no IP address	If the device does not have an IP address (or power is OFF), the network status indicator shall be steady OFF.	
Flashing Green	No connections	If the device has no established connections, but has obtained an IP address, the network status indicator shall be flashing green.	
Steady Green	Connected	If the device has at least one established connection (even to the message router), the network status indicator shall be steady green.	
Flashing Red	Connection timeout	<ul> <li>If one or more of the connections (for which this device is the target) has timed out, the network status indicator shall be flashing red.</li> <li>This shall be left if only all timed out connections are reestablished or if the device is reset.</li> </ul>	
Steady Red	Duplicate IP	If the device has detected that the IP address is already in use, the network status indicator shall be steady red.	
Flashing Red/ Green	Self-test	While the device is performing its power up testing, the network status indicator shall be flashing green/red.	

# **Commissioning Drives and Motion Systems**

This section provides general procedures for verifying the function of a completed Drives and Motion Accelerator Toolkit system.

**IMPORTANT** These commissioning procedures assume all applications are downloaded, all system devices are commissioned, a personal computer with the Logix Designer application is available, and a PanelView Plus terminal is powered and connected to the system's EtherNet/IP network.

## **Verify Network Communication**

Verify network communication between HMI terminal, Logix5000 controller, and devices.

## HMI Terminal to Logix5000 Controller Communication

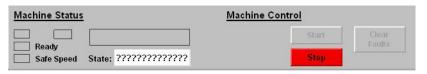
To determine if communication is lost between the HMI terminal and Logix5000 controller, look for:

- Error messages on the diagnostic display
- Wireframes on the display.

If there are communication problems with the controller, the diagnostic display lists messages (for example, CIP Connection Error). If the HMI terminal can communicate with the controller, but it cannot read/write specific tags, the diagnostic display lists similar messages (for example, Error Writing to *xxxxx*\_Tag).

The HMI terminal displays wireframes and "?????" on objects with tags it cannot read from the controller.

## **HMI Terminal Display**



A few of the most common problems are:

- Hardware problem such as a Ethernet cable disconnected.
- Communication path not properly configured in FactoryTalk View software, Communication Setup.
- Tag names in the parameter files not matching the tag names in the controller.

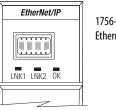
## Controller to Device Communication

Verify controller to device communication by observing the indicators on the controller's communication module and the devices in the controller's I/O tree.

Observe the controller's communication module. Refer to the user manual for the specific module you are using.

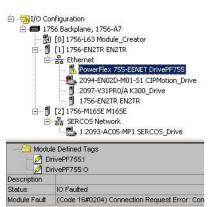
#### Ethernet Module Status Indicators

Status Indicator	Status
ОК	Solid green
LNK1	Flashing green (indicates network activity)
LNK2	Off (flashing green if in a Device Level Ring configuration)



1756-EN2TR Ethernet Module

Open your Logix Designer project, go online with the controller, and observe the devices in the I/O tree. A device with a yellow exclamation mark (!) indicates a fault. The fault could be a configuration fault, a device fault, or a communication fault. View the quick pane in the Controller Organizer to determine fault.



## **Clearing Faults**

After all of the devices are connected and functioning on the network, clear faults to put the machine in a STOPPED state.

## HMI Clear Faults

When the controller powers-up and the program goes into Run mode, the machine is faulted and in the ABORTED state. Refer to <u>Appendix A</u>, on <u>page 225</u>, for more information on the logic program modules.

You can attempt to clear the machine faults by pressing the Clear Faults push button on the HMI terminal. If there are no faults, the machine state goes to STOPPED. Refer to <u>Chapter 5</u>, on <u>page 101</u>, for more information on the HMI application programming.

#### HMI Test Faults

Test the functionality of the state machine, device modules, and fault handling by simulating faults. By creating a fault, the machine state should go to ABORTED and a fault should be logged on the HMI Alarm History faceplate. Try creating a fault for each of the device modules in the system. You can create a fault by unplugging an encoder cable or communication cable on a drive or servo. Verify that the machine goes to the ABORTED state. After each fault, correct the simulated fault and verify that you can clear the faults. The machine goes to the STOPPED state after the faults are cleared.

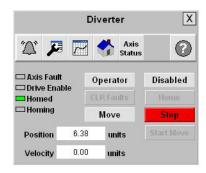
Refer to <u>Chapter 7</u> on page 183 for more information on the faceplate fault diagnostic views.

### **Operator (manual) Control**

Before attempting to run the machine, manually move or jog the drives if your configuration allows. With the faults cleared and the machine state in STOPPED mode, put the machine in OPERATOR mode. You can select each of the drives to manually move or jog. Test the Start/Stop mode, speed, and direction of each device.

Open one of the device faceplates. While in OPERATOR mode, manually jog or move the drive.

Refer to <u>Chapter 7</u> on <u>page 183</u> for more information on how device control buttons function.



### **Program (automatic) Control**

With the faults cleared and the machine state in STOPPED mode, you can put the machine in PROGRAM mode. By pressing the Start push button on the machine faceplate, the controller runs the machine according to the application program.

Machine Status Indicators	Machine Control Buttons				
Machine Status	Machine Control				
OK Ready	Program Start Clear Faults				
Safe Speed State: STOPPED	Stop				

## Notes:

# **System Application Guide**

This chapter guides you through the pre-configured FactoryTalk View Machine Edition application faceplates providing you with an understanding of the status, control, and diagnostic operation of the faceplate displays.

## **Before You Begin**

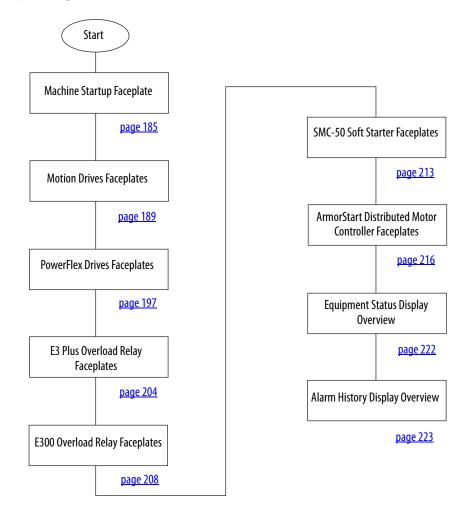
- Complete your logic configuration (refer to <u>Chapter 4</u>).
- Complete your FactoryTalk View Machine Edition configuration (refer to <u>Chapter 5</u>).
- Complete your Logix5000 and PanelView Plus application downloads (refer to Chapter 6).

## What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative.
- Hardware installation and wiring complete with power applied.
- Logix Designer project file downloaded to the Logix5000 controller and controller set to run.
- FactoryTalk View ME runtime application file downloaded to the PanelView Plus terminal. Run Application activated on terminal.

## **Follow These Steps**

Complete these display overview steps to run the preconfigured application and gain an understanding of the drives and motion system operation.



## **Machine Startup Faceplate**

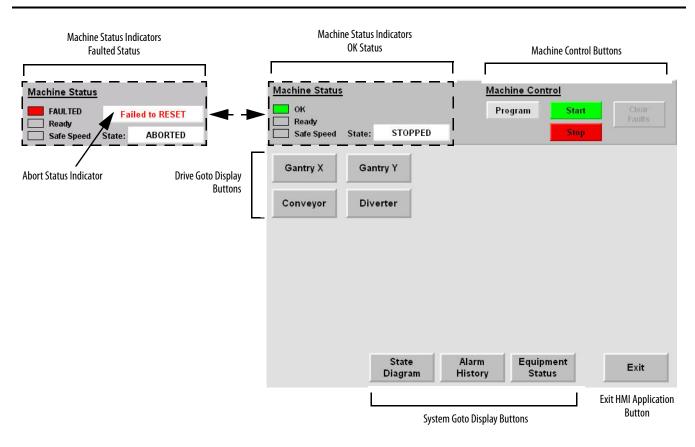
The Machine Startup faceplate display provides general machine status and control. It is also configured as the main navigation display for access to the other devices, the Alarm History faceplate display, and the Equipment Status faceplate display.

### **Machine Status**

The Machine Status indicators (OK and Faulted) provide general machine status (refer to the figure below). The specific indicator functions are included in the Machine Status Indicators table on <u>page 186</u>.

In this example, there are seven Goto display buttons configured. There is one Goto display button for each of the four drives, the State Diagram, the Equipment Status display, and the Alarm History display. Pressing any of the Goto display buttons launch the associated display.

**IMPORTANT** If the Machine Startup display is not visible or errors are reported on either the Logix5000 controller or PanelView Plus terminal, refer to previous chapters to check system wiring and configuration settings.



#### **Machine Status Indicators**

Status Indicator	Color/Value	Description
ОК	Green	No machine faults detected.
Faulted	Red	Machine fault detected.
	Power Up	
	Module Not Ready	
	Module Fault	
Abort Status	Failed to RESET	Displays additional diagnostic information for machine ABORT condition.
	Failed to START	
	Failed to STOP	
	Failed to CLEAR	
Ready	Green	Machine is ready to run. By default, the machine will be in one of the following states: IDLE, STARTING or RUNNING
Neauy	Grey	Machine is not ready to run.
Safe Speed	Green	Safe speed condition is currently active in at least one device module.
sale speed	Grey	Safe speed condition is not currently active.
	ABORTING	
	ABORTED	
	CLEARING	
	RESETTING	
State	IDLE	Displays the current machine state.
	STARTING	
	RUNNING	
	STOPPING	
	STOPPED	

#### **Machine Control**

The Machine control buttons provide Operator Start, Stop, and Mode control.

	Machine Control Buttons
<u>Machine Status</u>	Machine Control
OK Ready	Program Start Clear Faults
Safe Speed State: STOPPED	Stop

### **Program/Operator Mode**

Follow these steps to start and stop the motion system in Program control mode.

1. Press the Operator control mode button so that Program is displayed.

Program is now the active mode.

2. Press Start.

The required axes and drives are enabled and homed. The machine state goes to IDLE.

3. Press Start (again).

The required axes enable and begin operating according to the Logix Designer application. When the system is running, Start appears dimmed. The machine state goes to RUNNING.

4. Press Stop.

The system stops.

**IMPORTANT** The machine must be in a stopped state to switch modes.

5. Press the Control mode button until Operator is displayed in the Control field.

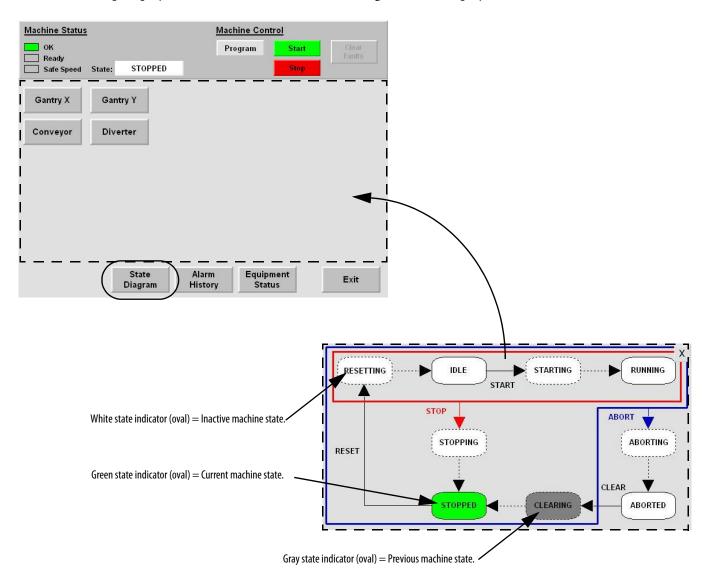
In Operator control, you can use one of the faceplate displays to manually control one of the drives.

#### **Machine Control Buttons**

Control Button	Button Function
Program/Operator	Toggles the control mode between Program and Operator. Operator mode permits manual control of the drives from the faceplate. Program mode operates the drive according to the Logix Designer application. The active control mode is displayed on the button. If control mode is switched from Program to Operator while the machine is RUNNING, the machine is STOPPED.
Start	When in Program control mode, pressing Start will RESET the machine and place it into IDLE. The Start button is disabled when in Operator control mode. Pressing START when the machine is in IDLE places it into RUNNING.
Stop	When in Program control mode, pressing Stop brings the machine to a controlled stop. The machine must be stopped before you can switch to the other mode.
Clear Faults	The Clear Faults button attempts to clear faults on all axes. The condition that caused the fault must be corrected, otherwise the machine will remain in ABORTED.
IMPORTANT	Start and Stop buttons on your PanelView Plus terminal do not replace a hardwired start/stop control circuit for safety purposes.
IMPURIANI	Your system should also include an emergency start/stop control circuit.

### State Diagram Faceplate Display

This display provides a graphical machine state status and is configured to fit within the middle section of the Machine Startup display when launched from the State Diagram Goto display button.



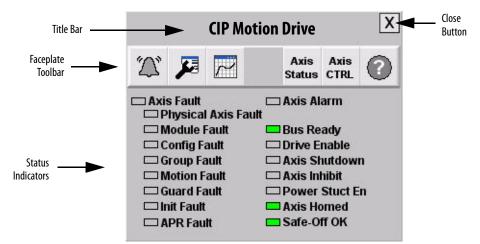
The State Diagram faceplate provides a quick reference for machine operators summarizing the relationship between machine states. Refer to Appendix A on <u>page 225</u> for more information on the individual states.

## **Motion Drives Faceplates**

The Motion drives faceplates are typically launched from the Machine Startup or Equipment Status faceplate's corresponding Goto display buttons.

**TIP** The Kinetix 300, sercos interface, and CIP Motion faceplates are similar in layout and the information they show, although differences do exist. The examples shown in this section are for CIP Motion drives.

### **Home View**



#### **Faceplate Toolbar Buttons**

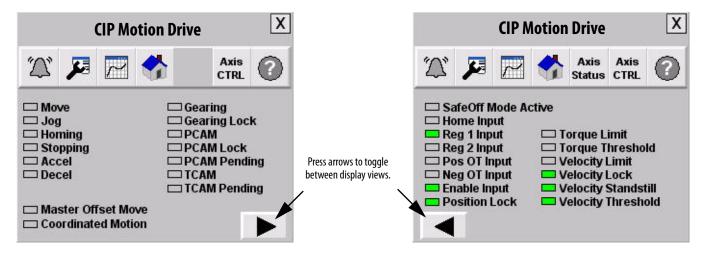
Function Button	lcons	Description	Function Button	lcons	Description
Alarm	Ĩ	The Alarm button indicates a drive fault condition and activates fault diagnostic views. A grey bell indicates normal status, with no faults. A yellow flashing bell indicates a fault condition.	Axis Control	Axis CTRL	From the Axis Control display you can home, enable, disable, reset an axis fault, and manually control the drive.
Configuration	F	The Configuration button lets you edit the faceplate name or name of the device.	Help	0	The Help button provides information for the existing view.
Trending		The Trending button shows you position, velocity, and current/torque trends.	Close	X	Click the Close button to close the faceplate.
Axis Status	Axis Status	From the Axis Status display you can view general motion, axis, and drive status.			•

#### **Axis Status Views**

The Axis Status views let you display general motion, axis, and drive status.

- Green = ON state
- Gray = OFF state

#### **CIP Motion Axis Status Views**



#### **Kinetix 300 Axis Status View**

Kinetix 300 Drive							
X 🎜	$\sim$		Axis CTRL	0			
□ Homing □ Indexing ■ Registrati	on Even	➡ Positi □ Veloci t ■ Veloci	ity Loc	:k			
UserDINT0	0	UserREAL	D	0.0			
UserDINT1	Ω	UserREAL	1	0.0			

The Kinetix 300 faceplate contains only one axis status view and is slightly different from the CIP Motion and sercos faceplates. The Kinetix 300 axis status view also displays the four Input Assembly Links that are transmitted from the drive to the controller.

### **Axis Control Views**

		CIP M	otion	Drive		X				CIP N	lotion	Drive		X
Ŕ	F	$\sim$		Axis Status		0		Ŕ	F	$\sim$		Axis Status		0
🗆 Axis 🗖 Bus	s Fault Ready	. 1	Opera	itor	Enabl	led	🗖 Axis Fault		Uperator		Enabled			
Enal Avis	bled s Home		CLR Fa	ults	Hom	e		Enabled			CLR Fa	ults	Ho	me
	s nome		Jog	-	Sto	p			s nome		- Mov	/e	St	ор
Positi	ion	0.32	uni	ts	Jog F	wd	Press Jog/Move to toggle between display views.	Move [	Dist	0.32	uni	its	Start	Move
Jog Sp	d 🗌	-0.00	uni	ts	Jog R	lev		Move S	Spd 🗌	0.00	uni	its		

#### **General Status/Control Buttons**

Button/Indicator	Description	Conditions Required for Each Manual Control Button			
Button/multator	Description	CIP Motion/ Sercos Drives	Kinetix 300 Drives		
Program/Operator	Toggles the control mode between Program and Operator mode. Operator mode permits manual control of the drive from the faceplate. Program mode operates the drive according to the Logix Designer application. The active control mode is displayed on the button.	Machine cannot be in the STARTING or RUNNING star			
Disabled/Enabled	Toggles the drive between the enabled and disabled states. The active state of the drive is displayed on the button.	Operator Mode			
CLR Faults	Clears any active drives faults. The button appears dimmed when no active faults are present in the drive.	<ul><li> Operator Mode</li><li> Active Drive Fault</li></ul>			
Home	CIP Motion and sercos drives: The reset sequence is initiated. By default, the reset sequence typically executes a motion axis home (MAH) instruction. Kinetix 300 drives: A start homing command is sent to the drive.	Operator Mode	<ul><li> Operator Mode</li><li> Drive Enabled</li></ul>		
Move/Jog	Toggles manual control between Move and Jog. Move mode, by default, performs an incremental position move based on the Move Position and Speed setpoints. Jog mode, by default, jogs the drive in the desired direction (forward/reverse) based on the Jog Speed.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> </ul>	<u>.</u>		

#### Move Status/Control Buttons

	Decription	Conditions Required for Each Manual Control Button			
Button/Indicator	Description	CIP Motion/ Sercos Drives	Kinetix 300 Drives		
Move Dist	Dual purpose control. Displays the actual position feedback of the drive. Also launches the numeric keypad to enter the desired Move Distance.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Move Selected</li> </ul>			
Move Spd	Dual purpose control. Displays the actual speed feedback of the drive. Also launches the numeric keypad to enter the desired Move Speed.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Move Selected</li> </ul>			
Start Move	Initiates or starts the manual move.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Move Selected</li> </ul>			

#### Jog Status/Control Buttons

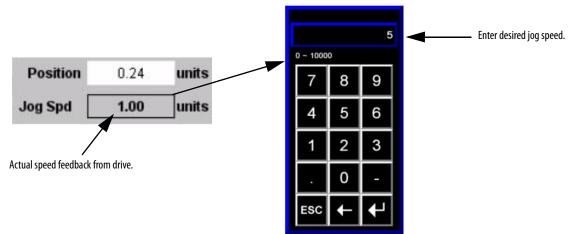
Dutton /In disaton	Description	Conditions Required for Each Manual Control Button			
Button/Indicator	Description	CIP Motion/ Sercos Drives	Kinetix 300 Drives <sup>(1)</sup>		
Position	Displays the actual position of the drive.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Jog Selected</li> </ul>	<ul><li> Operator Mode</li><li> Jog Selected</li></ul>		
Jog Spd	Dual purpose control. Displays the actual speed feedback of the drive. Also launches the numeric keypad to enter the desired Jog Speed.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Jog Selected</li> </ul>	<ul> <li>Operator Mode</li> <li>Jog Selected</li> </ul>		
Jog Fwd	Jogs the drive in the forward direction while the button is held. The drive stops immediately once the button is released.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Jog Selected</li> </ul>	<ul><li> Operator Mode</li><li> Jog Selected</li></ul>		
Jog Rev	Jogs the drive in the reverse direction while the button is held. The drive stops immediately once the button is released.	<ul> <li>Operator Mode</li> <li>Drive Enabled</li> <li>Jog Selected</li> </ul>	<ul><li> Operator Mode</li><li> Jog Selected</li></ul>		

(1) For the Kinetix 300 drive in Jog control mode, Drive Enable is not applicable.

#### Jog Speed, Move Distance, and Speed Controls

Jog Spd, Move Dist, and Move Spd are both indicators and keypad input buttons. For example, the Jog Spd indicator displays the actual speed feedback of the drive, not the desired jog speed. However, by clicking the indicator you launch the keypad input object where you can enter the desired jog speed.

#### **Dual Purpose Controls**



### **Fault Indication View**

The Alarm button indicates a Close **CIP Motion Drive** Button drive fault condition and activates the fault diagnostic views. **Flashing Fault** Axis Axis ×~ 10  $\sim$ Indicator Status CTRL Alarm Indicator Axis Fault 🗆 Axis Alarm 🚽 Physical Axis Fault Module Fault Bus Ready **Current Fault** Drive Enable Config Fault **General Status** Indicators Group Fault Axis Shutdown Indicators Motion Fault Axis Inhibit Guard Fault Power Stuct En 🗀 Init Fault Axis Homed Safe-Off OK APR Fault

#### **Fault Indication View**

Toolbar Button Color Indicator		Description	Action		
Alarm	Grey	Normal state	None		
Alarm	Flashing yellow	Fault	Follow fault action screen		

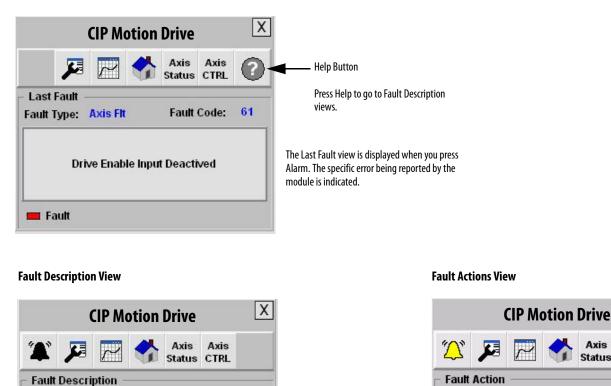
To access the detailed fault information and action displays, press the alarm button on the toolbar.

## **Fault Diagnostic Views**

The hardware enable input was deactivated

while the drive was enabled.

**Last Fault View** 



Press arrows to toggle between display views.

whenever the drive is enabled through software.

Disable the Drive Enable Input fault.

Verify that Drive Enable hardware input is active

X

Axis

Axis

Status CTRL

This diagnostic information is triggered by the reported module error code. The input and output error code information provided is in accordance with the fault descriptions and actions found in the drive specific user manual.

#### **Configuration View**

The configuration button  $\checkmark$  takes you to a display to edit the faceplate name or device descriptions.

You can enter display names and units as required for your application. Some of the labels are used on the Equipment Status faceplate.

Pressing any of the name or device descriptions launches an ASCII keypad for text entry. Pressing Enter on the keypad completes editing.

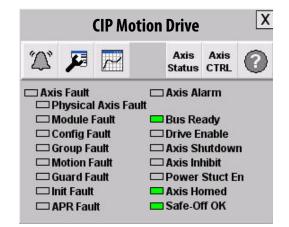
	Devi	ce N	lame		X	
Дĭ		<b>%</b>	Axis Status	Axis CTRL	0	
Dev	/ice Name	C	evice N	ame		
Equipm	ent Faceplat	e E	quip Na	me		
units			Position Units			
	units	v	elocity	Units		
Percent Rated			Current Units			
units			alue 4 L	Inits		

#### **Trend Views**

Follow these steps to discover the trend views.

1. Press the trend toolbar button 🖾 to access the trend faceplate views.

The trend views let you monitor the position, velocity and current values.

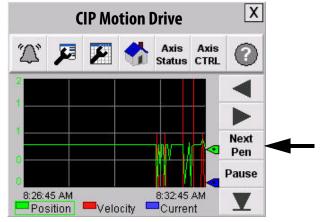


2. Press the Next Pen button to shift between the position, velocity, and current/torque trends.

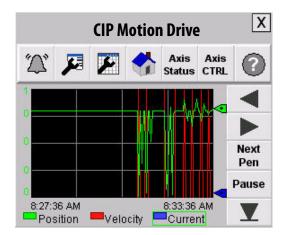
The Y-axis scale is automatically adjusted based on the trend pen you select.

In this example, the Position trend is selected.

The green box around position, velocity, and current/torque indicates the selected pen.



In this example, the Current trend is selected and the Y-axis scale is adjusted accordingly.



3. Press the trend configuration toolbar button I to set the minimum and maximum values of the trend Y-axis scale.

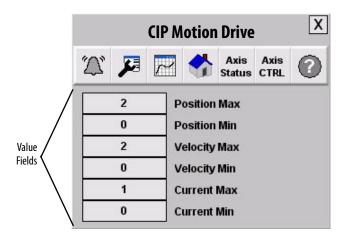
X **CIP Motion Drive** 1 🔎 Axis Axis 4 ? Status CTRL Next Pen Pause 8:26:45 AM 8:32:45 AM V Current Position Velocity

The trend scale configuration screen opens.

4. Press the value fields to modify.

A popup keyboard opens for value entry.

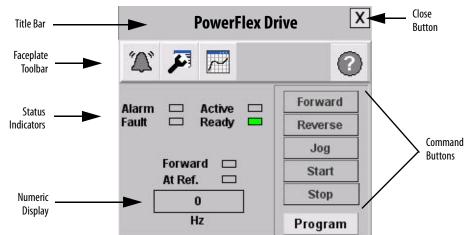
**5.** Press the Enter key on the keyboard, when entry is complete.



## **PowerFlex Drives Faceplates**

The PowerFlex drives faceplates are typically launched from the corresponding Machine Startup or Equipment Status faceplate's Goto display button.

#### **Home View**



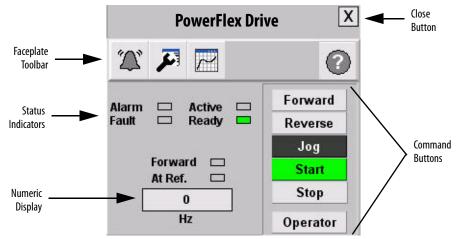
#### Faceplate Status/Control Buttons

Button	lcons	Description
Alarm <sup>(1)</sup>	Ц Ц	The Alarm button indicates a drive fault condition and activates fault diagnostic views. A grey bell indicates normal status, with no faults. A red flashing bell indicates a fault condition.
Configuration	F	The Configuration button lets you edit the PowerFlex faceplate name or name of the device.
Trending		The Trending button shows you voltage, current, and speed trends.
Help	?	The Help button provides information for the existing view.
Close	X	Click the Close button to close the faceplate.
Program/Operator	Program	Toggles the control mode between Program and Operator. Operator mode permits manual control of the drives from the faceplate. Program mode operates the drive according to the Logix Designer application. The active control mode is displayed on the button. If control mode is switched from Program to Operator while the machine
		is RUNNING, the machine is STOPPED.
Numeric Display		Click the Numeric Display button to access numeric entry keypad.

(1) There is no Alarm indication on the PowerFlex 525 drive faceplate because the PowerFlex 525 drive does not support alarms.

### **Control View**

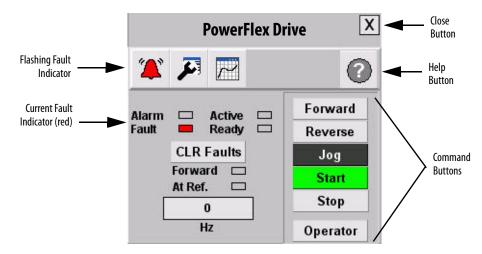
The overview faceplate places the logic program in control by default. For an operator to take control, press the Program button. The text on the button changes to Operator and the drive command buttons (Start and Stop, for example) are enabled.



Forward, Reverse, Jog, Start, and Stop command buttons let the operator perform the normal drive functions as the names suggest. You can also enter a speed reference by pressing the numeric display.

#### **Fault Indication View**

The Alarm button indicates a drive fault condition and activates the fault diagnostic views.



#### **Fault Indication View**

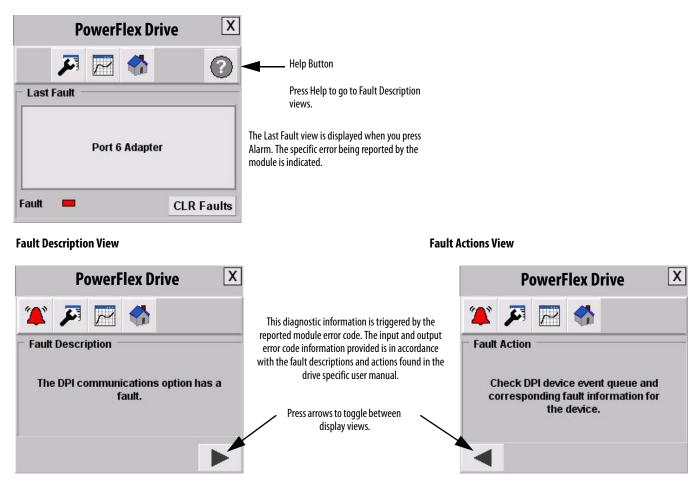
Toolbar Button	Color Indicator	Description	Action
Alarm <sup>(1)</sup>	Grey	Normal state	None
	Flashing red	Fault	Follow fault action screen

(1) There is no Alarm indication on the PowerFlex 525 drive faceplate because the PowerFlex 525 drive does not support alarms.

To access the detailed fault information and action displays, press the alarm button on the toolbar.

## **Fault Diagnostic Views**

**Last Fault View** 

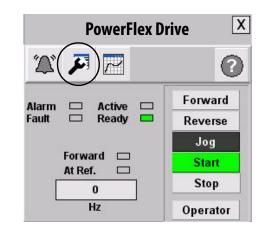


### **Configuration Views**

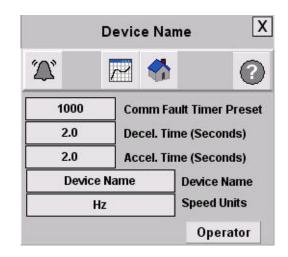
You can use the Configuration button to edit the faceplate name or device descriptions.

1. Press the Configuration button on the toolbar.

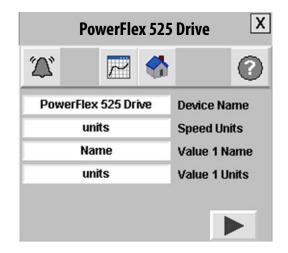
The Configuration button becomes highlighted.

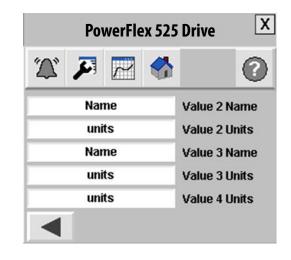


2. Press the title bar, drive name, or value fields that you need to modify.



These HMI faceplates apply to the PowerFlex 525 drives and are used for assigning the device name and units to the faceplate and the speed units and pens associated with them.





A popup keyboard opens.

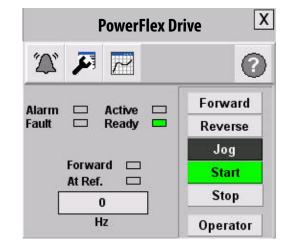
- 3. Type the desired text or values.
- 4. Press the Enter key.

Dev	/ice	e N	ame									
1	2	3	4	5	6	7	8	9	0	-	=	
q	w	е	r	t	у	u	i	o	р	I	]	
а	s	d	f	g	h	j	k	I	;	1	•	
z	x	с	v	b	n	m	•		/	١	41	Entar Kay
SHF	CAP	INS		SPACE		<<	>>	ESC	CLR	+		Enter Key

### **Trend Views**

1. Press the trend toolbar button *to* access the trending faceplate view.

The trend views let you monitor the voltage, current, and speed values.



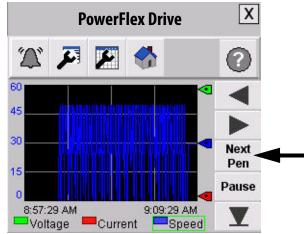
2. Press the Next Pen button to shift between the voltage, current, and speed trends.

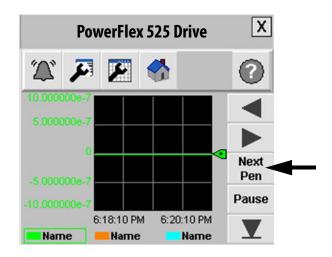
The Y axis scale is automatically adjusted based on the trend pen you select.

In this example, the Speed trend is selected.

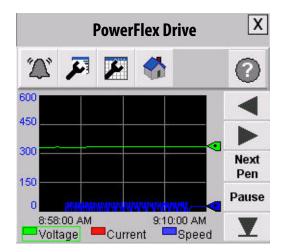
The green box around Voltage, Current, and Speed indicates the selected pen.

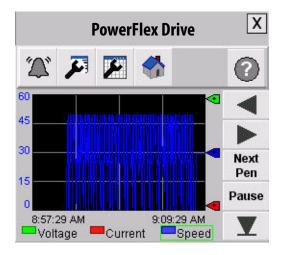
This HMI faceplate applies to the PowerFlex 525 drives.

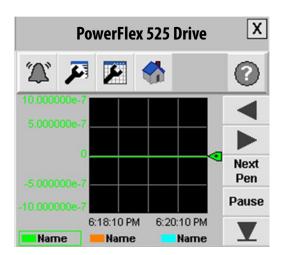




In this example, the Voltage trend is selected and the Y-axis scale is adjusted accordingly.





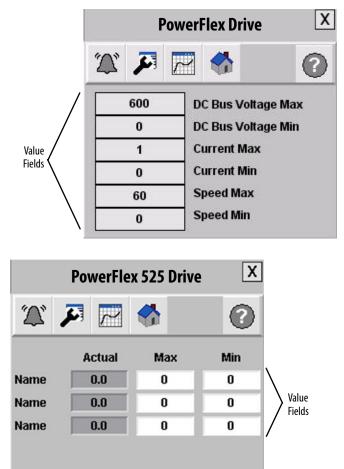


3. Press the trend configuration toolbar button it to set the minimum and maximum values of the trend scale.

This HMI faceplate applies to the PowerFlex 525 drives.

The trend scale configuration screen opens.

4. Press the value fields to modify.



This HMI faceplate applies to the PowerFlex 525 drives.

A popup keyboard opens for value entry.

**5.** Press the Enter key on the keyboard, when entry is complete.

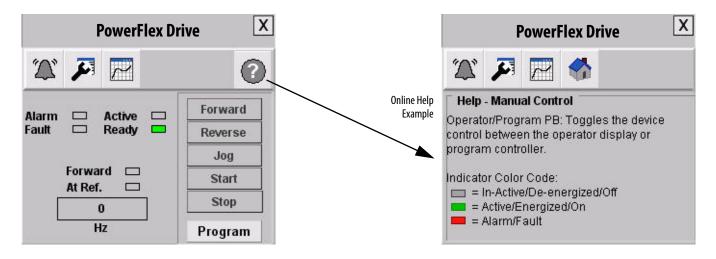
### **Energy Status Views**

If the PowerFlex Drive faceplate with the Energy Monitoring option is used, there will be also be an Energy tab available on the toolbar.

Press the energy toolbar button **E** to access the energy status faceplate view.

PowerFlex D	PowerFlex Drive X					rive	X
* 🕨 🖉 🤇	E	*	F	۶			0
Alarm Active D Faulty Ready D	Forward Reverse Jog	Resoure Capabili Consun	ities: ned (kV	Vh):	Me: 00	e(vical asured 10000000.	_
Forward C At Ref. C 0 SPEED	Start Stop Operator	Generat Total (k' Power (	Wh):	/h): [		10000000.1 100000000.1 C	

#### **Online Help Views**

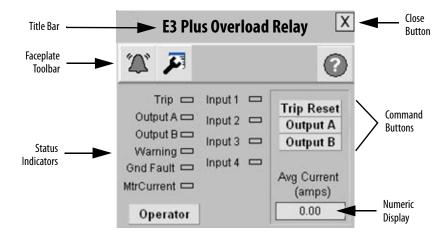


Press the Help button on any view to access the online help information.

## **E3 Plus Overload Relay Faceplates**

The E3 Plus overload relay faceplate is typically launched from the corresponding Machine Startup or Equipment Status faceplate's Goto display button.

#### **Home/Control View**

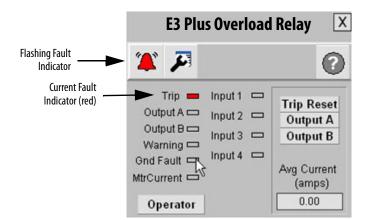


<b>Faceplate Status</b>	/Control Buttons
-------------------------	------------------

Button	lcons	Description
Alarm	Ц Ц	The Alarm button indicates a fault condition and activates fault diagnostic views. A grey bell indicates normal status, with no faults. A red flashing bell indicates a fault condition.
Configuration	F	The Configuration button lets you edit the E3 Plus overload relay faceplate name or name of the device.
Help	0	The Help button provides information for the current view.
Close	Х	Click the Close button to close the faceplate.
Status Indicators	Trip 📼	Grey = OK, normal, off Red = Tripped Yellow = Warning/Outputs commanded closed/user device inputs closed Green = Active load present
Program/Operator	Program	Toggles the control mode between Program and Operator. Operator mode permits manual control of the relay from the faceplate. Program mode operates the relay according to the Logix Designer application. The active control mode is displayed on the button.
Command Buttons	Trip Reset Output A Output B	The command buttons are enabled when in Operator mode. Trip Reset, Output A, and Output B let the operator perform the E3 Plus overload relay functions as the names suggest.

### **Fault Indication View**

The Alarm button indicates a drive fault condition and activates the fault diagnostic views.



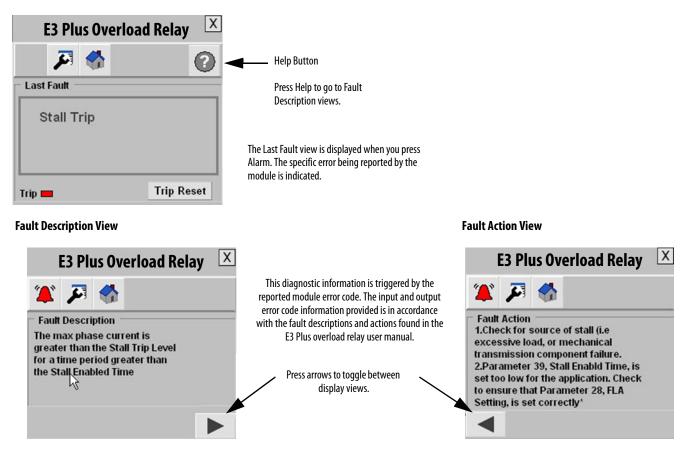
#### **Fault Indication View**

Toolbar Button	Color Indicator	Description	Action
Alarm	Grey	Normal state	None
	Flashing yellow	Warning	None
	Flashing red	Fault	Follow fault action screen

To access the detailed fault information and action displays, press the alarm button on the toolbar.

## **Fault Diagnostic Views**

#### **Last Fault View**

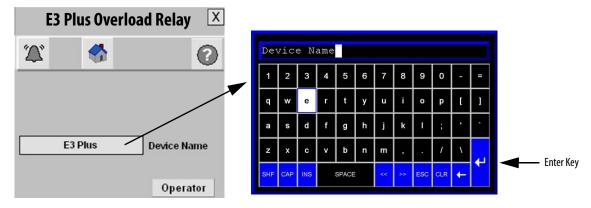


#### **Configuration View**

You can use the Configuration button to edit the faceplate name or device descriptions.

1. Press 🎾 on the faceplate toolbar to launch the Configuration view.

The only parameter that is configurable from the E3 Plus faceplate is the faceplate/device name.



- 2. Click the string entry box to launch the keyboard popup.
- 3. Type the desired text.
- 4. Press Enter.

### **Online Help Views**

Press 🕖 on the faceplate toolbar of any view to access the online help information.



#### **Energy Status Views**

If the E3 Plus overload relay faceplate with the Energy Monitoring option is used, the Energy tab also appears on the faceplate toolbar.

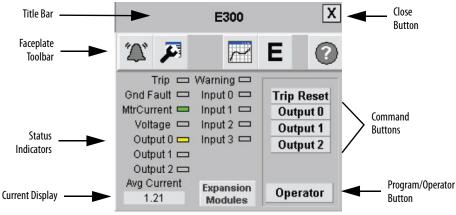
Press **E** on the Energy faceplate toolbar to access the energy status faceplate view.

E3 Plus Overloa	d Relay 🛛 🗙	E3 Plus Ov	E3 Plus Overload Relay 🛛 🗴				
🌋 🎜 🛛 E	)	X 🏹 🛠	0				
Trip Input 1 Input 2 Input 2 Input 2 Input 3 Input 3 Input 3 Input 4 I	Trip Reset Output A Output B	Resource Type: [ Capabilities: [ Consumed (kWh): [ Generated (kWh): [ Total (kWh): [ Power (kW):	Electrical Measured 009010011.012 000000000.000 009010011.012 6.00				

## E300 Overload Relay Faceplates

The E300 overload relay faceplate is typically launched from the corresponding Machine Startup or Equipment Status faceplate's Goto display button.

### **Home/Control View**



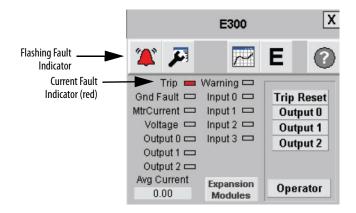
#### Faceplate Status/Control Buttons

Button	lcons	Description
Alarm	<u>ب</u>	The Alarm button indicates a fault condition and activates fault diagnostic views. A grey bell indicates normal status, with no faults. A red flashing bell indicates a fault condition.
Configuration	<b>F</b>	The Configuration button lets you edit the E3 Plus overload relay faceplate name or name of the device.
Trending		The Trending button displays a trend of the current and % TCU.
Energy	E	The Energy button displays a list of energy related data values.
Help	0	The Help button provides information for the current view.
Close	X	Click the Close button to close the faceplate.
Status Indicators <sup>(1)</sup>	Trip  Gnd Fault  MtrCurrent  Voltage  Output 0	Grey = Inactive/De-energized/OFF Green = ON Yellow = Energized/Warning Red = Alarm/Fault
Program/Operator	Program	Toggles the control mode between Program and Operator. Operator mode permits manual control of the relay from the faceplate. Program mode operates the drive according to the Logix Designer application. The active control mode is displayed on the button.
Command Buttons <sup>(1)</sup>	Trip Reset         Output 0         Output 1         Output 2         Output 2         Operator         Progcam         Local         Keyped Control         Press REMOTE         button on E300 for         Faceplate control	Command buttons are available for performing a trip reset and energizing outputs from the faceplate. The command buttons are enabled when the E300 relay is in Remote mode and Operator mode is selected by the operator. If the E300 relay is in Remote mode, but Program mode is selected, the buttons are disabled. If the E300 relay is not in Remote mode, the buttons are not visible and the faceplate indicates that the device is currently under Local Keypad Control.
Expansion Modules	Expansion Modules	The Expansion Modules button is available when there are expansion modules configured. Clicking this button displays the status of inputs and outputs on the expansion modules. The number of expansion modules shown updates dynamically, based on the module properties defined in the controller.

(1) The number of inputs and outputs displayed, changes dynamically based on the module properties defined in the controller.

#### **Fault Indication View**

The Alarm button indicates a drive fault condition and activates the fault diagnostic views.

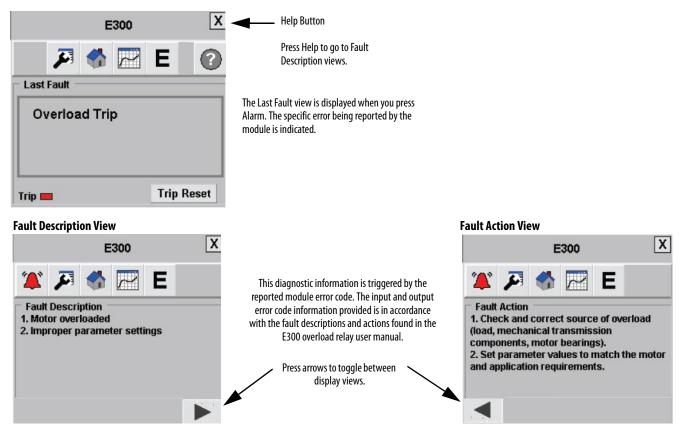


Alarm Fault Indications				
Color Indicator	Description	Action		
Grey	Normal state	None		
Flashing yellow	Warning	Follow fault action screen		
Flashing red	Fault	Follow fault action screen		

To access the detailed fault information and action displays, press the alarm button on the toolbar.

#### **Fault Diagnostic Views**

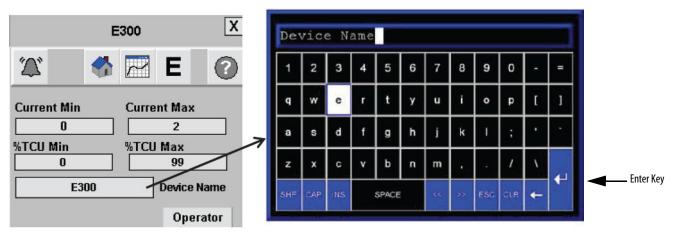
#### **Last Fault View**



#### **Configuration View**

You can use the Configuration button to edit the faceplate name or device descriptions.

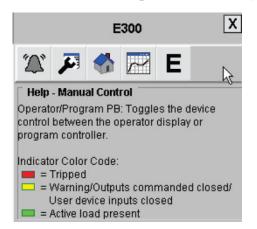
1. Press 🏓 on the faceplate toolbar to launch the Configuration view.



- 2. Click the string entry box to launch the keyboard popup.
- **3.** Type the desired text.
- **4.** Press Enter.

### **Online Help Views**

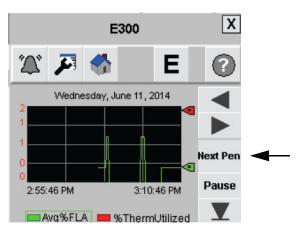
Press ② on the faceplate toolbar of any view to access the online help information.



#### **Trend View**

The Trend view displays a trend of either the average current or the % Thermal Capacity Utilized (TCU).

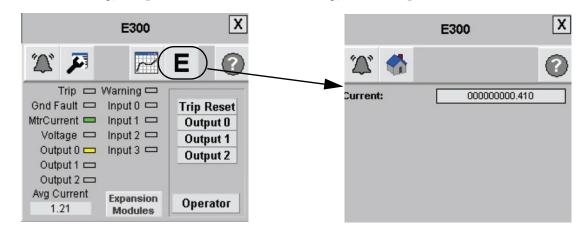
1. Press an the toolbar to access the trending faceplate view.



- 2. Press the Next Pen button to toggle between trend views.
- 3. Press 🎾 on the configuration toolbar to set the minimum and maximum display range.

#### **Energy Status View**

If the E300 overload relay faceplate with the Energy Monitoring option is used, the Energy tab also appears on the faceplate toolbar.



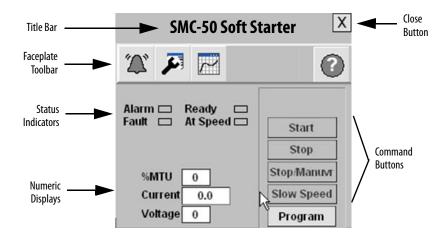
Press E on the Energy faceplate toolbar to access the energy status faceplate view.

The energy data displayed is dependent on the module definition configured in the controller. If you do not have a voltage-sensing module configured, only the current is displayed on the energy tab.

## SMC-50 Soft Starter Faceplates

The SMC-50 soft starter faceplate is typically launched from the corresponding Machine Startup or Equipment Status faceplate's Goto display button.

### **Home/Control View**



#### Faceplate Status/Control Buttons

Button	lcons	Description
Alarm	X	The Alarm button indicates a fault condition and activates fault diagnostic views. A grey bell indicates normal status, with no faults. A red flashing bell indicates a fault condition.
Configuration	<b>F</b>	The Configuration button lets you edit the SMC-50 communication fault timer, slow speed percent, and faceplate/device name.
Trend	2	The Trending button shows you voltage, current, and MTU trends.
Help	0	The Help button provides information for the current view.
Close	X	Click the Close button to close the faceplate.
Status Indicators	Alarm 🗖 Fault 🗖	Grey = Inactive/De-energized/Off Green = Active/Energized/On Red = Alarm/Fault
Program/Operator	Program	Toggles the control mode between Program and Operator. Operator mode permits manual control of the SMC-50 soft starter from the faceplate. Program mode operates the drive according to the Logix Designer application. The active control mode is displayed on the button.
Command Buttons	Stop Manuvr Stop Manuvr Slow Speed	The command buttons are enabled when in Operator mode. Start, Stop, Stop Maneuver, and Slow Speed buttons let you perform the SMC-50 soft starter functions as the names suggest.

#### **Fault Indication View**

The Alarm button indicates a drive fault condition and activates the fault diagnostic views.

		SMC-50 Soft Starter 🛛 🗙				
Flashing Fault Indicator		<b>X</b> F	$\sim$			0
Current Fault Indicator (red)	0.0		Ready At Spee	d	CLR Faults Start Stop	
		%MTU Current Voltage	0 0.0 0		Stop/Manuvr Slow Speed Program	

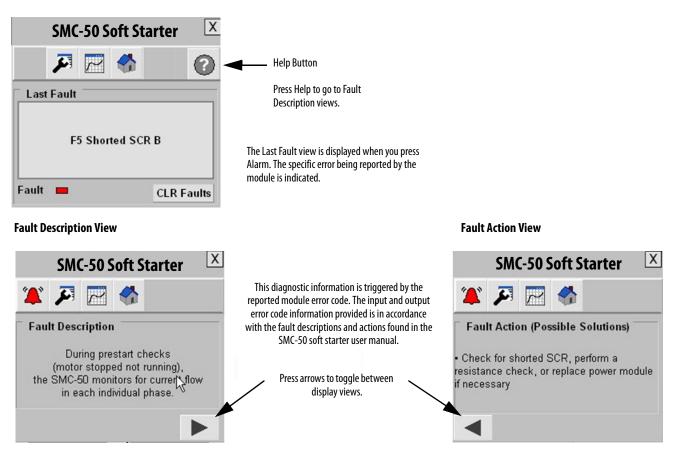
Color Indicator	Description	Action		
Grey	Normal state	None		
Flashing red	Fault	Follow fault action screen		

**Alarm Fault Indications** 

To access the detailed fault information and action displays, press the alarm button on the toolbar.

### **Fault Diagnostic Views**

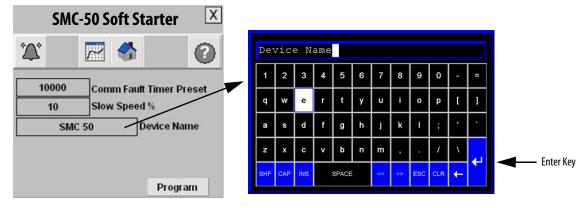
Last Fault View



#### **Configuration View**

You can use the Configuration button to edit the faceplate name or device descriptions.

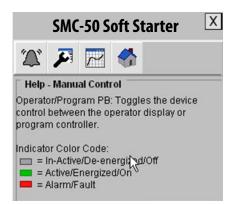
1. Press 🎾 on the faceplate toolbar to launch the Configuration view.



- 2. Click the string entry box to launch the keyboard popup.
- **3.** Type the desired text.
- 4. Press Enter.

#### **Online Help Views**

Press 🕖 on the faceplate toolbar of any view to access the online help information.



### **Energy Status Views**

If the SMC-50 soft starter faceplate with the Energy Monitoring option is used, the Energy tab also appears on the faceplate toolbar.

SMC-50 Soft Starter X Х SMC-50 Soft Starter  $\sim$ Ε N° N ? Electrical Resource Type: Ready Alarm 🗖 Fault 🗖 At Speed Measured Capabilities: Start 000123456.000 Consumed (kWh): Stop 000000000.000 Generated (kWh): Stop/Manuvr %MTU 0 000123456.000 Total (kWh): Current 0.0 Slow Speed 2.00 Power (kW): Voltage 0 Program

Press E on the Energy faceplate toolbar to access the energy status faceplate view.

## **ArmorStart Distributed Motor Controller Faceplates**

The ArmorStart faceplates are typically launched from the corresponding Machine Startup or Equipment Status faceplate's Goto display button.

**IMPORTANT** This faceplate is only for the ArmorStart Bulletin 294E. Each ArmorStart device has its own faceplate with similar functions.

#### Close х Title Bar ArmorStart 294E Button Faceplate Help N N ? Toolbar Button 🗆 I/O PTO Тгір RunFwd Warning 🗆 I/0 PT1 RunRev DiscClosed 🛄 I/O PT2 Status Command Indicators JogFwd I/O PT3 Ready Buttons RunFwd 🗆 I/O PT4 10000 JogRev RunRev 💻 I/O PT5 Stop AtRef 6 - Input/Output Program

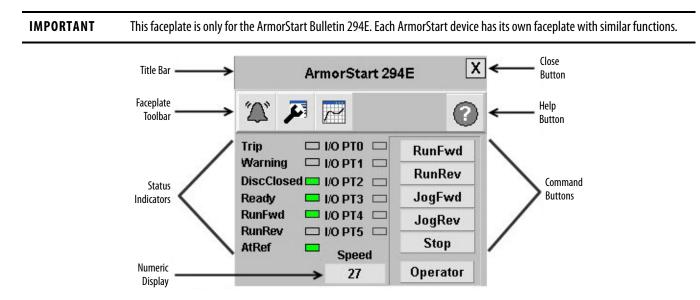
#### **Home View**

#### **Faceplate Status/Control Buttons**

Button	lcons	Description
Alarm	Ц Ц	The Alarm button indicates a fault condition and activates fault diagnostic views. A grey bell indicates normal status, with no faults. A red flashing bell indicates a fault condition.
Configuration	F	The Configuration button lets you edit the ArmorStart faceplate name or name of the device.
Help	0	The Help button provides information for the current view.
Trending	2	The Trending button shows you voltage, current, and speed trends.
Close	X	Click the Close button to close the faceplate.
Status Indicators	Trip 📼	Grey = OK, normal, off Red = Tripped Yellow = Warning/Outputs commanded closed/user device inputs closed Green = Active load present
Program/Operator	Program	Toggles the control mode between Program and Operator. Operator mode permits manual control of the relay from the faceplate. Program mode operates the relay according to the Logix Designer application. The active control mode is displayed on the button.

### **Control View**

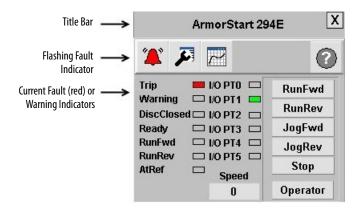
The overview faceplate places the logic program in control by default. For an operator to take control, press the Program button. The text on the button changes to Operator and the drive command buttons (Run and Jog, for example) are enabled.



RunFwd, RunRev, JogFwd, JogRev, and Stop command buttons let the operator perform the normal functions as the names suggest. You can also enter a speed reference by pressing the numeric display.

### **Fault Indication View**

The Alarm button indicates an ArmorStart fault condition and activates the fault diagnostic views.



Color Indicator	Description	Action
Grey	Normal state	None
Flashing red	Fault	Follow fault action screen

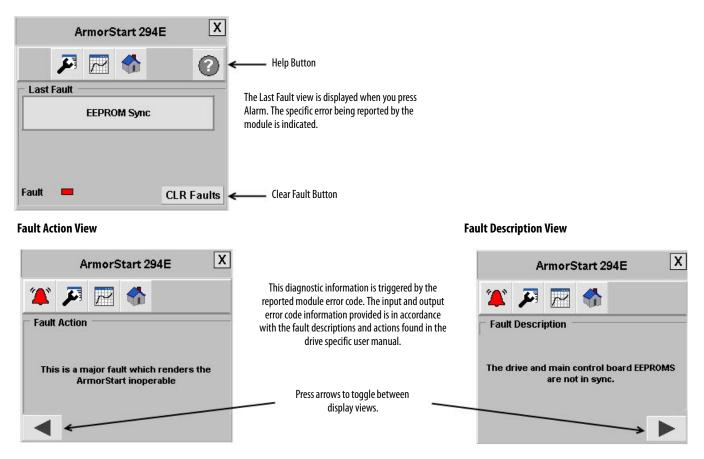
**Alarm Fault Indications** 

To access the detailed fault information and action displays, press the alarm button on the toolbar.

**IMPORTANT** These faceplates are only for the ArmorStart Bulletin 294E. Each ArmorStart device has its own faceplate with similar functions.

### **Fault Diagnostic Views**

#### Last Fault View

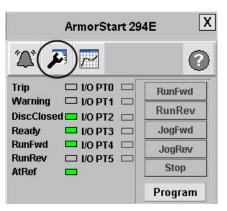


### **Configuration Views**

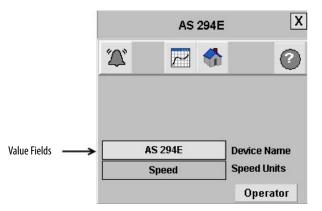
You can use the Configuration button to edit the faceplate name or device descriptions.

**IMPORTANT** This faceplate is only for the ArmorStart Bulletin 294E. Each ArmorStart device has its own faceplate with similar functions.

1. Press 🔎 on the faceplate toolbar to launch the Configuration view.



2. Press the title bar, drive name, or value fields that you need to modify.



3. Type the desired text and press the Enter key.

This faceplate is for assigning the device name and units of the faceplate.

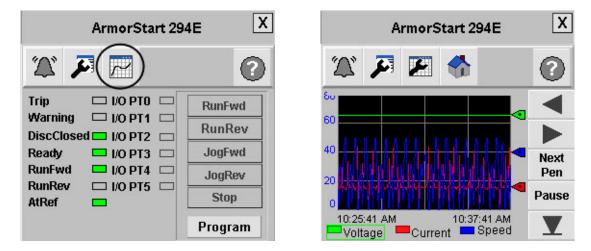
AS 294E	×											
AS 294E Dr Speed Sc	Arı	nor	Sta.	rt	294	Е						
	1	2	3	4	5	6	7	8	9	0	-	=
	q	w	е	r	t	у	u	i	o	р	I	1
	а	s	d	f	g	h	j	k	I.	Ģ	·	•
	z	x	с	v	b	n	m	•		7	١	_
	SHF	CAP	INS		SPACE		~~	>>	ESC	CLR	+	

### **Trend Views**

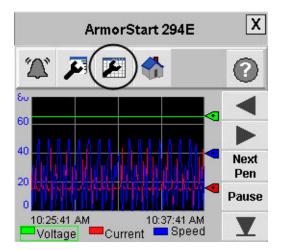
**IMPORTANT** This faceplate is only for the ArmorStart Bulletin 294E. Each ArmorStart device has its own faceplate with similar functions.

1. Press on the toolbar to access the trending faceplate view.

The trend views let you monitor the voltage, current, and speed values.



2. Press on the toolbar to set the minimum and maximum values of the trend scale.



**3.** Press the value fields to modify.

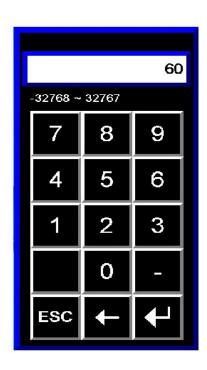
A popup keyboard opens for value entry.

**4.** Press the value fields to modify.

A popup keyboard opens for value entry.

5. Press the Enter key on the keyboard, when entry is complete.

× 🕨	2 💠 🕜			
0	DC Bus Voltage Max			
0	DC Bus Voltage Min			
0	Current Max			
0	Current Min			
60	Speed Max			
0	Speed Min			
↑ Value Fields				



## **Online Help Views**

**IMPORTANT** This faceplate is only for the ArmorStart Bulletin 294E. Each ArmorStart device has its own faceplate with similar functions.

Press 🕐 on the faceplate toolbar of any view to access the online help information.

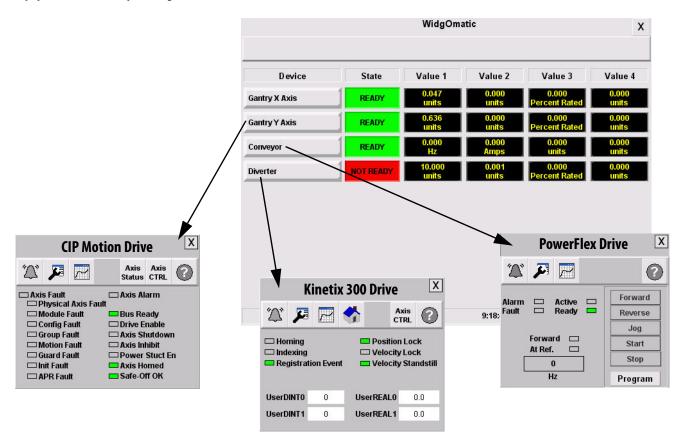
ArmorStart 2	94E X		ArmorStart 294E X
X 🕨 🗷	0	Online Help Example	X 🗾 🔁 🍫
TripI/O PT0WarningI/O PT1DiscClosedI/O PT2ReadyI/O PT3RunFwdI/O PT4RunRevI/O PT5AtRef	RunFwd RunRev JogFwd JogRev Stop Program		Help - Manual Control Operator/Program PB: Toggles the device control between the operator display or program controller. Indicator Color Code:

## **Equipment Status Display Overview**

The Equipment Status faceplate files let you quickly load and configure a summary display of preconfigured status and diagnostic displays or faceplates for FactoryTalk View Machine Edition. The Equipment Status faceplate works in conjunction with individual device faceplates and provides a single summary display of all of the faceplates that may be configured for an application. You can configure up to nine device faceplates to run with the Equipment Status faceplate and you can launch each device faceplate directly from it.

In this example, the drives from the Widg-O-matic example were added to the Equipment Status display. Click the device buttons to open the associated device faceplates.

#### Equipment Status Example - Widg-O-matic Drives Added



### **Equipment Status Display for Energy Overview**

The Equipment Status Display for Energy provides a summary of the energy status for all of the devices configured for an application. It also provides a central place for launching the device faceplates. You can configure up to nine devices to run with the Equipment Status Display for Energy faceplate.

	Ed	luipment Ene	rgy Status		Х
Device	State	Value 1	Value 2	Value 3	Value 4
PF 753	DISABLED	0.000 kW	0.000	0.000	0.000
PF755	DISABLED	0.000 kW	0.000	0.000	0.000
E3 Plus A	DISABLED	6.000 kW	0.000	0.000	0.000
SMC 50	ACTIVE	2.000 kW	0.000	0.000	0.000
PF70EC	DISABLED	0.000 kW	0.000	0.000	0.000

## **Alarm History Display Overview**

The Alarm History display provides time and date stamped machine and device faults, and alarms when launched from the Alarm History Goto display button on the Machine Startup faceplate display.

#### Alarm History Faceplate Display Example

Alarm time	A	cknowledg	e time	Messa	ae		
10/13/2010 9:25		Sittle Houg				Excessive	Velocity Error
10/13/2010 9:25					X Axis Drive		
10/13/2010 9:24	40 AM			Gantry	X Axis Drive	Drive Enab	le Input Deact
10/13/2010 9:24	40 AM			Gantry	X Axis Drive	Drive Fault	
Ack	Silonge				1	Alarm	
Ack	Silence	T	<b>★</b>		Print	Alarm	
Ack Alarm Ack	Silence Alarms Clear	T	<b>1</b>		Print History	Alarm Status Sort	Close

In this example, a number of faults are displayed from a CIP Motion drive named Gantry X Axis.

Refer to FactoryTalk View Machine Edition User Manual Volume 1, publication <u>VIEWME-UM004</u> for Alarm History alarm button operation and configuration.

## Notes:

# **Logic Program Overview**

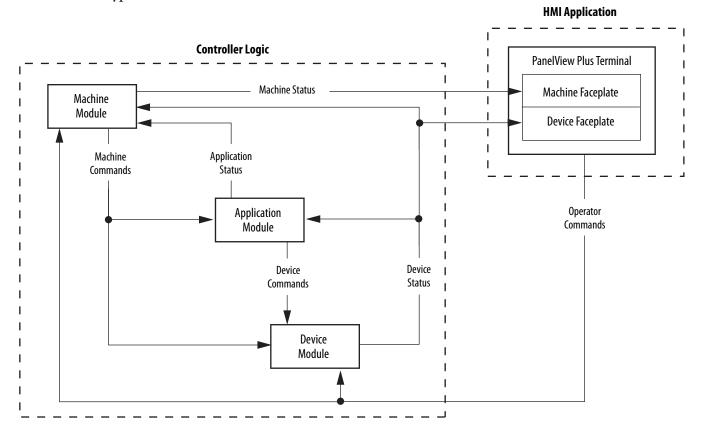
The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>, was developed around a modular concept. Modularity lets you decide which components to incorporate into your machine, providing greater flexibility and a custom fit. The preconfigured logic is specifically designed around this modular concept and consists of three main logic modules.

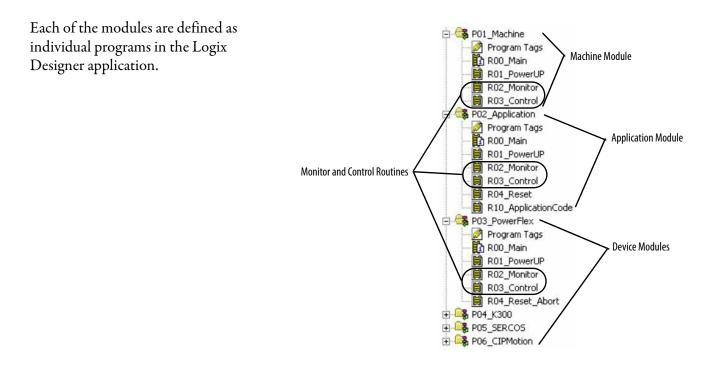
#### **Logic Module Overview**

Logic Module Type	Function
Machine	The machine module contains the high level control for the entire machine. The machine module was built around a simple state machine that you can customize to fit most applications. The machine module broadcasts out commands and receives feedback information from each of the application and device modules. Based on the feedback information, the machine will react accordingly.
	In addition, the machine module provides a high level interface with the HMI, accepting commands like Start, Stop, and Clear Faults. It provides status info to the HMI terminal like current state of the machine (for example, RUNNING versus STOPPED).
Application	The application modules contain all of the application specific code. This is where a majority of the customizing is expected to occur and is essentially a programming space where you spend a significant portion of your efforts to develop proprietary logic specific to your application.
Device	Device modules contain all of the logic to control the essential functions required by the device. For example, an Integrated Motion servo drive like the Kinetix 6500 requires logic (MSO and MSF instructions) to enable and/or disable the servo drive. This logic reduces the programming effort required by most applications providing more time for the proprietary logic needed for the application.
	Typically, the device module consists of a physical drive, but could also consist of a virtual or feedback-only axis. Device modules can also consist of multiple devices (for example, a drive) and perhaps a feedback device (for example, a sensor).

## Machine/Application/Device Module Relationship

The machine module monitors the current state of the overall machine and based on the state and/or requests from the HMI terminal, broadcasts out commands to both the application and device modules. The individual modules perform a predefined task based on the command. Some of the commands may be ignored depending on the module type.



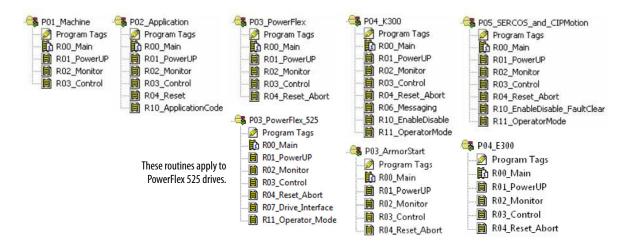


Each program contains all of the necessary logic to interact with the other configured modules. This interface between each of the modules is accomplished via the Monitor and Control routines located in each of the programs. The machine commands and corresponding module status is routed through the Monitor and Control routines. This lets the modules operate independently in a modular structure.

## **Module Routine Overview**

Each module is broken down into routines that contain logic for a specific function. Each module contains a monitor and control routine that provides a common interface between the machine and the application / device modules. Each of the routines main functions are listed below:

#### **Module Routine Listing Examples**



#### **Module Routine Overview**

Logic Module Type	Routine	Function
	R00_Main	Dispatch routine, calls all of the other routines in the program.
	R01_PowerUp	Initializes parameters following power up or controller first scan.
Machine	R02_Monitor	<ul> <li>Summarizes the status from all of the dependent modules (for example, application and device modules).</li> <li>Detects Abort and/or Stop conditions.</li> <li>Provides machine status information to HMI terminal.</li> </ul>
	R03_Control	<ul> <li>Provides main interface with HMI terminal requests (for example, Start/Stop/Clear Faults pushbuttons).</li> <li>Contains the state machine logic.</li> </ul>
	R00_Main	Dispatch routine, calls all of the other routines in the program.
	R01_PowerUp	Initializes parameters following power up or controller first scan.
	R02_Monitor	<ul> <li>Summarizes the status for the application module (for example, OK, Ready, Running, Stopped).</li> <li>Detects module faults (for example, Failed to RESET, Failed to RUN).</li> </ul>
Application	R03_Control	Receives machine commands and initiates the corresponding sequences (for example, RESET, RUN and STOP sequences).
	R04_Reset	Contains the RESET sequence logic, used to prepare the application to run.
	R10_ApplicationCode	<ul><li>Typical location for the application specific logic.</li><li>Contains the RUN and STOP sequences.</li></ul>
	R00_Main	Dispatch routine, calls all of the other routines in the program.
	R01_PowerUP	Initializes parameters following power up or controller first scan.
	R02_Monitor	<ul> <li>Summarizes the status for the device module (for example, OK, Ready, Reset).</li> <li>Detects module faults (for example, Failed to RESET, Failed to CLEAR, Module Not Ready).</li> <li>Contains the faceplate add-on instruction (AOI) for the HMI terminal faceplate.</li> </ul>
PowerFlex	R03_Control	Receives machine commands and initiates the corresponding sequences (for example, RESET and ABORT sequences)
SMC-50 E3 Plus E300 ArmorStart	R04_Reset_Abort	<ul> <li>Contains place holder for application specific reset logic if required.</li> <li>Contains the ABORT sequence which makes sure that the drives contained within the module are stopped and disabled. The ABORT sequence also makes sure that other devices are placed into a desired state.</li> </ul>
	R05_Energy (applies only if the device module with energy monitoring is used)	<ul> <li>Gets the energy data from the device using explicit messaging.</li> <li>Monitors the communication status and sets alarm and status bits related to energy.</li> </ul>
	R07_Drive_Interface (applies to PowerFlex 525 drives only)	<ul> <li>Contains the drive status, command, and communication logic for PowerFlex 525 drives.</li> <li>Contains place holder for drive specific datalink logic if required.</li> </ul>
	R11_OperatorMode (applies to PowerFlex 525 drives only)	Contains the Operator or Manual mode logic for the PowerFlex 525 drives. This logic is initiated via requests made from drive faceplate located on the HMI terminal.

#### Module Routine Overview (continued)

Logic Module Type	Routine	Function
	R00_Main	Dispatch routine, calls all of the other routines in the program.
	R01_PowerUP	Initializes parameters following power up or controller first scan.
	R02_Monitor	<ul> <li>Summarizes the status for the device module (for example, OK, Ready, Reset).</li> <li>Detects module faults (for example, Failed to RESET, Failed to CLEAR, Module Not Ready).</li> <li>Contains the faceplate add-on instruction (AOI) for the HMI terminal faceplate.</li> </ul>
	R03_Control	Receives machine commands and initiates the corresponding sequences (for example, RESET and ABORT sequences)
Kinetix 300	R04_Reset_Abort	<ul> <li>Contains the RESET sequence logic, used to prepare the application to run.</li> <li>Contains the ABORT sequence which makes sure that the drives contained within the module are stopped and disabled. The ABORT sequence also makes sure that other devices are placed into a desired state.</li> </ul>
	R06_Messaging	Contains all of the explicit messaging logic required for the Kinetix 300 drive.
	R10_EnableDisable	Contains the enable, disable, clear faults logic for the Kinetix 300 drive.
	R11_OperatorMode	Contains the Operator or manual mode logic for the Kinetix 300 drive. This logic is initiated via requests made from drive faceplate located on the HMI terminal.
	R00_Main	Dispatch routine, calls all of the other routines in the program.
	R01_PowerUP	Initializes parameters following power up or controller first scan.
	R02_Monitor	<ul> <li>Summarizes the status for the device module (for example, OK, Ready, Reset).</li> <li>Detects module faults (for example, Failed to RESET, Failed to CLEAR, Module Not Ready).</li> <li>Contains the faceplate add-on instruction (AOI) for the HMI terminal faceplate.</li> </ul>
Sercos or	R03_Control	Receives machine commands and initiates the corresponding sequences (for example, RESET and ABORT sequences)
or CIP Motion	R04_Reset_Abort	<ul> <li>Contains the RESET sequence logic, used to prepare the application to run.</li> <li>Contains the ABORT sequence which ensures that the drives contained within the module are stopped and disabled. The ABORT sequence can also make sure that other devices are placed into a desired state.</li> </ul>
	R10_EnableDisable	Contains the enable, disable, clear faults logic for the drives.
	R11_OperatorMode	Contains the Operator or Manual mode logic for the drive. This logic is initiated via requests made from drive faceplate located on the HMI terminal.

## **Machine Module**

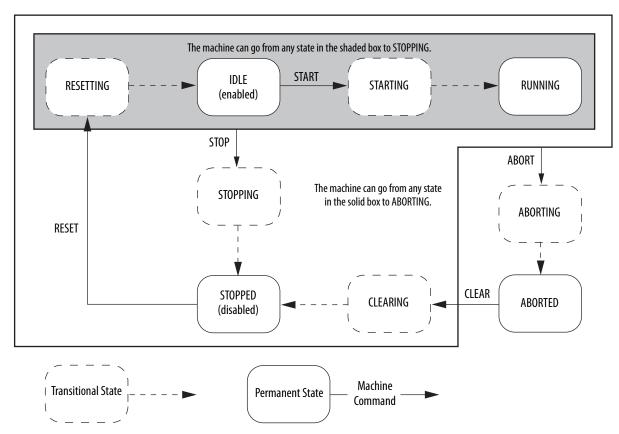
The machine module contains the high level control for the entire machine. The machine module was built around a simple state machine that you can customize to fit most applications. The machine module broadcasts out commands and receives feedback information from each of the application and device modules. Based on the feedback information, the machine will react accordingly.

In addition, the machine module provides a high level interface with the HMI, accepting commands like Start, Stop, and Clear Faults. It provides status info to the HMI terminal like current state of the machine (for example, RUNNING versus STOPPED).

### **Machine States**

By default, the machine program module operates based on this overall state diagram.

#### Machine State Diagram



The machine module uses the Transitional States to move between Permanent States. Typically, the machine only remains on a Transitional State for brief period of time. If the machine module detects an error during a Transitional State or if the application or device modules fail to transition within an allotted time (10 seconds by default), the machine module issues an ABORT command. The fail safe transition timer makes sure the overall machine does not become stuck in a Transitional State. It also helps to provide diagnostic information to determine which module is not transitioning properly.

You can fully customize the state machine, letting you change the relationship between states and the state names, and add or remove states if needed. Refer to Appendix B on <u>page 241</u> for information on how to customize the state machine.

#### **Default Machine States**

Machine State	State Type	Description
ABORTING	Transitional	Broadcasts the ABORT command until confirmation that all of the application and device modules are aborted. The ABORTING state is triggered based on feedback from the modules.         Default ABORT conditions that place the machine in the ABORTING state include:         • Power-up detected (for example, controller first scan)         • Modules not ready while the machine is in STARTING and/or RUNNING states         • Modules not ready while the machine is in STARTING and/or RUNNING states         • Modules failed to RESET         • Modules failed to START         • Modules failed to STOP         • Modules failed to CLEAR
ABORTED	Permanent	All application and device modules are aborted (for example, stopped and disabled). Typically, this state indicates a fault condition.
CLEARING	Transitional	Broadcasts the CLEAR command until confirmation that all of the application and device modules are ok (for example, all active drive and/or modules have been cleared) within the allotted time. Otherwise, an ABORT condition is generated. Once all of the modules are ok, the machine is placed into the STOPPED state.
RESETTING	Transitional	Broadcasts the RESET command until confirmation that all of the application and device modules are reset within the allotted time. Otherwise, an ABORT condition is generated.
IDLE	Permanent	All application and device modules are reset or ready to run (for example, enabled or homed). Typically, this state that the machine is ready to run and awaits a START command.
STARTING	Transitional	Broadcasts the RESET command until confirmation that all of the application modules are running within the allotted time. Otherwise, an ABORT condition is generated.
RUNNING	Permanent	All application modules are running.
STOPPING	Transitional	Broadcasts the STOP command until confirmation that all of the application modules are stopped within the allotted time. Otherwise, an ABORT condition is generated.
STOPPED	Permanent	All application modules are stopped and all modules (application and/or device) are ready.

#### **Default Machine Commands**

Machine Command	Application Module Response	Device Module Response
ABORT	Halts the application RUN sequence (if active) and initiates the STOP sequence. The STOP sequence attempts to stop and disable all active drives.	Halts the device module RESET sequence (if active) and initiates the device module ABORT sequence. The ABORT sequence makes sure the drives contained within the module are stopped and disabled. The ABORT sequence can also be used to make sure other devices are placed into a desired state.
CLEAR	Attempts to clear any active faults that exist in the modules.	Attempts to clear any active faults that exist in either the module and/or drive.
RESET	Initiates the application RESET sequence, which prepares the application and/or devices to run. Use this for the coordinated reset of multiple modules.	Initiates the device module RESET sequence, which prepares the device module to run.
START	Initiates the application RUN sequence. Customize the RUN sequence to fit the needs of your application.	Ignored <sup>(1)</sup>
STOP	Halts the application RUN sequence (if active) and initiates the STOP sequence. The STOP sequence attempts to stop and disable all active drives.	Halts the device module RESET sequence.

(1) By default, these commands are ignored by the module. However, you can change the relationship of each module to best fit the needs of the application.

## **Machine Control Module Tags**

The machine control data type, UDT\_MachCtrl, comprises the overall machine control and status, including the state machine. The user-defined data type consists of these components.

1	Name	Data Type	Style	Description		
	- Mode	UDT_MachMode		Machine Mode	$\sum$	
	-OPERATOR	BOOL	Decimal	Operator (MANUAL) Mode	Machine Mode	
	PROGRAM	BOOL	Decimal	Program (AUTO) Mode	/	
	∃ <sub>1</sub> Cmd	UDT_MachCmd		Machine Commands	1	
	-ABORT	BOOL	Decimal		Machine Commands	
	-CLEAR	BOOL	Decimal			
	-RESET	BOOL	Decimal			
	-START	BOOL	Decimal		/	
	STOP	BOOL	Decimal		/	
	- State	UDT_MachState		Indicates Current Machine State	ί.	
	ABORTED	BOOL	Decimal		Current Machine State	
	ABORTING	BOOL	Decimal			
	CLEARING	BOOL	Decimal		1	
	-IDLE	BOOL	Decimal			
	RESETTING	BOOL	Decimal		1	
	RUNNING	BOOL	Decimal			
	-STARTING	BOOL	Decimal		1	
	-STOPPED	BOOL	Decimal		1	
	STOPPING	BOOL	Decimal		1	
	PreState	UDT_MachState		Indicates Previous or Last Machine State	Previous Machine State	
	E StateDisplay	STRING		Displays Current State	-	— Machine State Display
	AbortStatus	DINT	Decimal	Displays ABORT Status	$\mathbf{N}$	machine state bisplay
	OK	BOOL	Decimal	Machine OK (NOT Faulted)	Machine Status	
	Ready	BOOL	Decimal	Machine Ready for Use	Widelinine Status	
	SLSStatus	BOOL	Decimal	Machine in Safe Limited Speed		

#### **Machine Tags**

Tag Group	Function
Machine mode	<ul> <li>Additional modes can be added to the machine. By default, the modes included are:</li> <li>OPERATOR or manual mode</li> <li>PROGRAM or auto mode</li> </ul>
Machine commands	Broadcast machine commands that direct all of the dependent modules (for example, application and device modules).
Current machine state	Indicates the current state of the overall machine. Only one state can set at even given time.
Previous machine state	Indicates the previous machine state. Used primarily by the application and device modules to determine Transitional State faults.
Machine state display	String tag that can be used to indicate the current machine state.
Machine status	Indicates miscellaneous machine status information.

### **Device and Application Status Rung Tags and Logic**

The device and application status rungs provide feedback information to the machine module and consists of these components.

#### **Device Module Status**

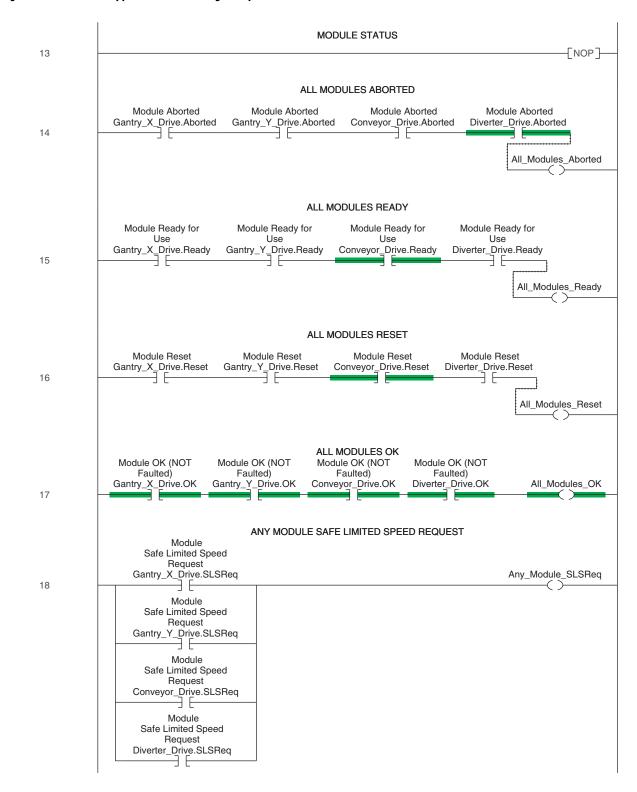
Name	Data Type	Style	Description
Aborted	BOOL	Decimal	Module Aborted
Active	BOOL	Decimal	Module Active (Enabled / Running)
Reset	BOOL	Decimal	Module Reset
OK	BOOL	Decimal	Module OK (NOT Faulted)
Ready	BOOL	Decimal	Module Ready for Use
SLSReq	BOOL	Decimal	Module Safe Limited Speed Request
+ Name	STRING		Module Name

#### **Application Module Status**

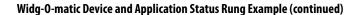
1	Name	Data Type	Style	Description
	OK	BOOL	Decimal	Application OK (NOT Faulted)
	Ready	BOOL	Decimal	Application Ready for Use
	Reset	BOOL	Decimal	Application Initialized
	Running	BOOL	Decimal	Application Running
	Stopped	BOOL	Decimal	Application Stopped
1	+ Name	STRING		Application Name

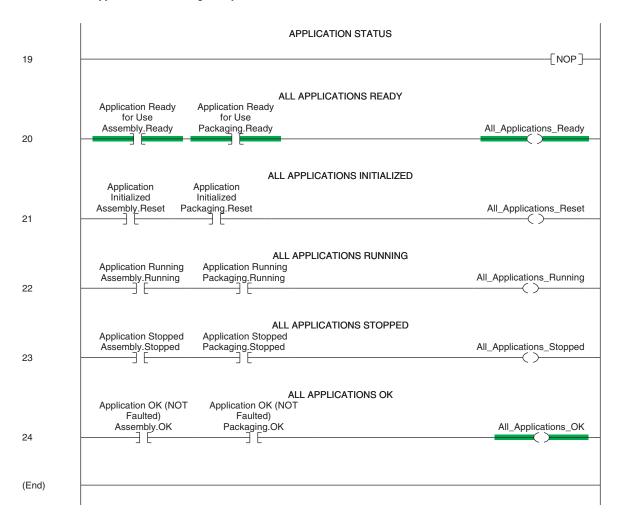
The status bits are set in the Monitor routine of the corresponding modules. These status bits are vital to the machine module, as they are used to determine the overall status of the machine. They help the machine transition between states or detect a fault and respond accordingly. All of the module status information is summarized in the Monitor routine of the machine module.

For these Widg-O-matic application examples, the rungs are found in the R02\_Monitor routine of the P01\_WidgOmatic machine program.



#### Widg-O-matic Device and Application Status Rung Example





# **Application Modules**

The application modules contain all of the application specific code. This is where a majority of the customizing is expected to occur and is essentially a programming space where you spend a significant portion of your efforts to develop proprietary logic specific to your application.

In this example, application code is shown for the Widg-O-matic machine's assembly application.

=====	
	SERCOS / CIP MOTION SIMPLE INCREMENTAL MOVE
	emonstrates how to control a SERCOS / CIP MOTION drive using sequencers & Motion Instructions. is STARTING / RUNNING, the drive will be operated as follows:
3 4) 5) 6 7)	<ul> <li>Lower Y-Axis - Incremental Distance -2.0 revs</li> <li>2) DWELL - Time 1 sec</li> <li>Paise Y-Axis - Incremental Distance 2.0 revs</li> <li>Extend X-Axis - Incremental Distance 3.0 revs</li> <li>Lower Y-Axis - Incremental Distance -2.0 revs</li> <li>5) DWELL - Time 1 sec</li> <li>Paise Y-Axis - Incremental Distance 2.0 revs</li> <li>Retract X-Axis - Incremental Distance -3.0 revs</li> <li>8) Repeat</li> </ul>
	command.
	RUN SEQUENCE
=====	
	[NOP]
	NOP ]
	INCREMENTAL MOVE
EOU	INCREMENTAL MOVE Lower Y-Axis Incremental Distance -2.0 revs Motion Axis Move
Equal Source A RunSEQ[0] 0	INCREMENTAL MOVE Lower Y-Axis Incremental Distance -2.0 revs Motion Axis Move MAM Motion Axis Move Axis Motion Control Gantry_Y_Axis
Equal Source A RunSEQ[0]	INCREMENTAL MOVE Lower Y-Axis Incremental Distance -2.0 revs Motion Axis Move MAM Motion Axis Move Axis Gantry_Y_Axis
Equal Source A RunSEQ[0] 0	INCREMENTAL MOVE Lower Y-Axis Incremental Distance -2.0 revs Motion Axis Move MAM Motion Axis Move Axis Gantry_Y_Axis Motion Control Gantry_Y_Axis_Ctrl.MI.MAM[1] Move Type 1 (ER)

## **Device Modules**

Device modules contain all of the logic to control the essential functions required by the device. For example, an Integrated Motion servo drive like the Kinetix 6500 requires logic (MSO and MSF instructions) to enable and/ or disable the servo drive. This logic reduces the programming effort required by most applications providing more time for the proprietary logic needed for the application.

Typically, the device module consists of a physical drive, but could also consist of a virtual or feedback-only axis. Device modules can also consist of multiple devices (for example, a drive) and perhaps a feedback device (for example, a sensor).

## **Device Module Tags**

The application and individual device modules interact with each other via device specific control tags that include both command and status information. The control tags consist of these data types.

#### **Device Tags**

Device Classifications	Covered Products	Data Type
PowerFlex drives	<ul> <li>PowerFlex 4-class drives, for example, 4, 40, 40P</li> <li>PowerFlex 7-class drives, for example, 70EC, 700VC</li> <li>PowerFlex 750-Series drives for example, 753, 755</li> <li>PowerFlex 520-Series drives for example, 525</li> </ul>	Product specific add-on defined (AOI) data type: PFlex_XXX_AOI Where XXX refers to the specific PowerFlex drive
Kinetix 300 drives	Kinetix 300	User-defined type: UDT_K300_Ctrl
Sercos physical axis	<ul> <li>Kinetix 2000</li> <li>Kinetix 6000</li> <li>Kinetix 6000M</li> <li>Kinetix 6200</li> <li>Kinetix 7000</li> </ul>	User-defined type: UDT_ServoCtrl
Sercos feedback-only axis	Applicable sercos drives	User-defined type: UDT_ServoCtrl
CIP Motion physical axis	Kinetix 6500     PowerFlex 755	User-defined type: UDT_ServoCtrl
CIP Motion frequency control	PowerFlex 755, PowerFlex 527, and Kinetix 5500	User-defined type: UDT_FreqCtrl
CIP Motion feedback-only axis	Applicable CIP motion drives	User-defined type: UDT_ServoCtrl
Virtual axis	N/A	User-defined type: UDT_ServoCtrl
SMC-50 solid-state soft starters	SMC-50 solid-state soft starters	Add-on defined (AOI) data type: SMC_50_AOI
E3 Plus overload relay with communications auxiliary (193-DNENCAT) device	E3 Plus overload relay with 193-DNENCAT module	Add-on defined (AOI) data type: E3_CommsAux_rev6_AOI
PowerFlex drives, SMC-50 soft starters, and E3 Plus overload relays with energy monitoring	<ul> <li>PowerFlex 7-class drives, for example, 70EC, 700VC</li> <li>PowerFlex 750-Series drives, for example, 753, 755</li> <li>SMC-50 solid-state soft starters</li> <li>E3 Plus overload relay with 193-DNENCAT module</li> </ul>	In addition to the device AOI tags, a user defined data type is used to provide energy monitoring: UDT_BEO
ArmorStart distributed motor controllers	<ul> <li>ArmorStart LT 290E, 291E, and 294E</li> <li>ArmorStart 280E, 281E, and 284E</li> </ul>	ArmorStart product specific add-on defined (AOI) data type: AS_2xxE_AOI ArmorStart ST product specific add-on defined (AOI) data type: <sup>(1)</sup> AS_2xxE_AOI_wIPS or AS_2xxE_AOI_wOIPS Where xx refers to the specific ArmorStart motor control

(1) With or without internal power supply (IPS).

All of the data types listed above can be modified to fit specific needs of your application. However, modifications to the data types could have an impact on the device module and/or other preprogrammed logic, especially during import of additional device modules.

For example, the UDT\_ServoCtrl data type that is used by the integrated motion drives (CIP Motion and sercos interface based drives) consists of these tags.

Na	ame	Data Type	Style	Description
Ξ	Cmd	UDT_ServoCmd		Servo Commands
1	-Enable	BOOL	Decimal	Enable Servo Commands
	-Disable	BOOL	Decimal	Disable Servo
1		BOOL	Decimal	Clear Faults
B	Status	UDT_ServoStatus		Servo Status
1	-ConfigComplete	BOOL	Decimal	Configuration Complete
1	-ConfigState	DINT	Decimal	Axis Configuration State Status
1	-Homed	BOOL	Decimal	Servo Homed Status
1	—ОК	BOOL	Decimal	Servo DK (NOT Faulted)
1	-ON	BOOL	Decimal	Power Structure Active and Servo Control Enabled
1	-Operator	BOOL	Decimal	Servo in Operator (Manual) Mode
1	-Program	BOOL	Decimal	Servo in Program (Auto) Mode
1	-Ready	BOOL	Decimal	Servo Ready for Use
İ	—SafetyDK	BOOL	Decimal	SafeDff Status Indicator
1	-Stopped	BOOL	Decimal	Servo Stationary (Stopped)
1	-SLSReq	BOOL	Decimal	Servo Safe Limited Speed Request
	<sub>1</sub> МІ	UDT_MotionInstructions	1	Motion Instructions
1	MASR	MOTION_INSTRUCTION		Motion Axis Shutdown Reset Motion Instructions
	MAFR	MOTION_INSTRUCTION		Motion Axis Fault Reset
~	MDR	๚ฏฃ๛๛๛๛๛ฃ๛๚ๅ ๚๛๚๛๚ๅ๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛๛	y in	Motion Disam Registration
	Data	UDT_ServoData		Servo Data
	-Direction	DINT[8]	Decimal	Direction Placeholder
	-GearRatio	REAL[4]	Float	Gear Ratio Placeholder Miscellaneous Data Placeho
	-JogAccel	REAL[8]	Float	Jog Accel Placeholder
	—JogDecel	REAL[8]	Float	Jog Decel Placeholder
	—JogDir	DINT[8]	Decimal	Jog Direction Placeholder
	—JogSpd	REAL[8]	Float	Jog Speed Placeholder
	-MoveAccel	REAL[8]	Float	MAM Accel Placeholder
	-MoveDecel	REAL[8]	Float	MAM Decel Placeholder
	-MoveDir	DINT[8]	Decimal	MAM Direction Placeholder
	-MoveSpd	REAL[8]	Float	MAM Speed Placeholder

#### CIP Motion UDT\_ServoCtrl Tag Listing

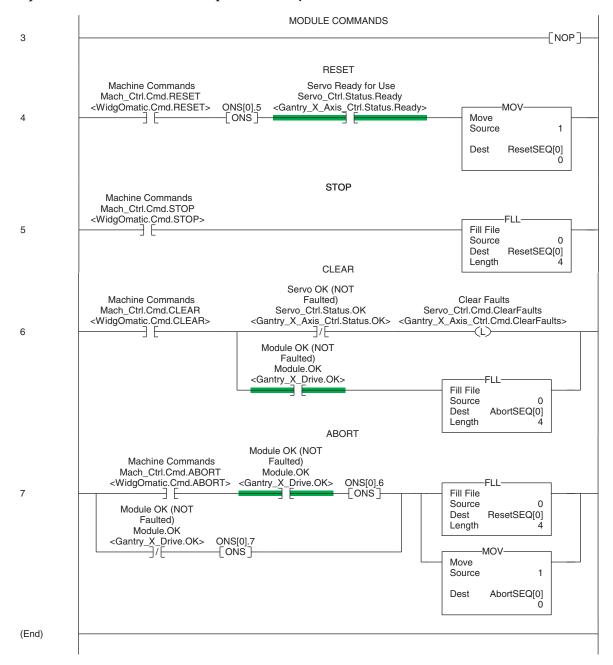
#### UDT\_ServoCtrl Tags

Tag Group	Function
Commands	The command tags initiate preprogrammed logic in the device module. The command tags can be set (latch - OTL) in either the device and/or application module, and the device module will perform the requested action. The device module also clears the command bit (unlatch – OTU). For example, if the Enable bit is latched, the corresponding device module executes a Motion Servo On (MSO) instruction and unlatches the Enable bit.
Status	The Status tags are updated by the device module and contain commonly used information that can be referenced by both the device and application modules. For example, if the ON status bit is set, the application or device module knows that the drive is fully enabled.
Motion instructions	Placeholders for Motion Instructions. This provides one central group of Motion Instructions that can be used by both the application and device module.
Miscellaneous data placeholders	Placeholders for commonly used data for the application and device modules. The data placeholder tags are set by default in the PowerUP routine located in the device module.

The user-defined type for the Kinetix 300 drives and the add-on defined data type for the PowerFlex drives serve similar function as the UDT\_ServoCtrl data type, however their layouts differ. Refer to the specific data types for more information.

### **Device Module Control Logic Example**

In this example, the R03\_Control routine for a CIP motion device module initiates and/or clears the Reset and Abort sequences. The routine also attempts to clear any active faults.



Refer to the toolkit directory C:\Program Files\RA\_Simplification\DMAT\B-Files\6-Project Examples\ WidgOmatic folder for a complete example of a logic program.

## Notes:

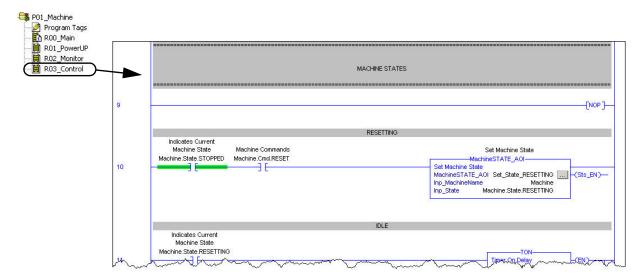
# **Logic Module Customization**

The toolkit logic modules are designed with a basic set of machine states, faults, alarms, and reset logic common to most applications. Knowing that specific application requirements dictate exceptions and additions, the ability to customize is also included in the logic module design.

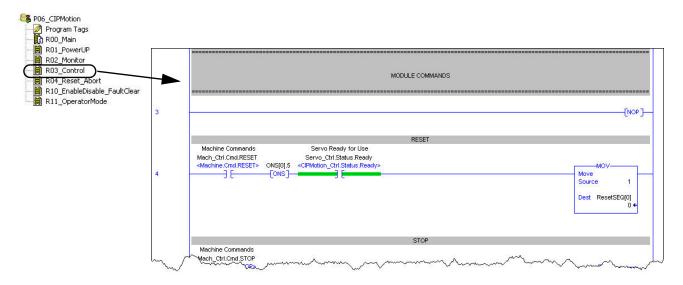
This appendix includes common modification recommendations for the customization of machine states, faults, alarms, and reset logic.

## **Machine State Customization**

You may wish to modify state names, add or remove states, or even change the relationship between states to fit your application. The state machine logic resides in the R02\_Monitor and R03\_Control routines located in the machine module.



The application and device modules interact with the state machine via their R02\_Monitor and R03\_Control routines.



For example, the device modules accept commands and react accordingly. Therefore, changes to the state machine can impact the individual application and device modules. Refer to Appendix A, Logic Program Overview, on <u>page 225</u>, for more information on the state machine and how it interacts with the application and device modules.

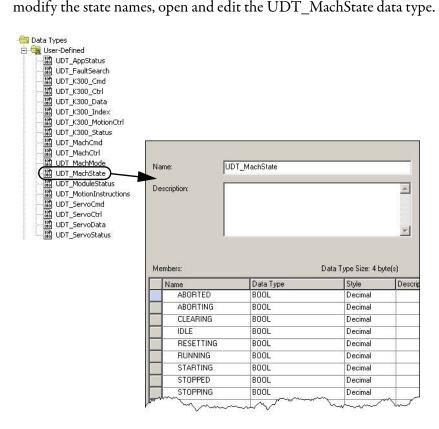
The core for the state machine is built around the UDT\_MachCtrl data type.

The UDT\_MachCtrl data type consists of three sub data-types that directly impact the state machine.

- Mode = UDT\_MachMode
- Command = UDT\_MachCmd
- State = UDT\_MachState

Name: UDT_MachCtrl				
escription:			×	
embers:	D	ata Type Size: 112	byte(s)	
Name	Data Type	Style	Description	
	UDT_MachMode		Machine Mode	
-OPERATOR	BOOL	Decimal	Operator (MANUAL) Mode	
PROGRAM	BOOL	Decimal	Program (AUTO) Mode	
En Cmd	UDT_MachCmd		Machine Commands	
ABORT	BOOL	Decimal		
CLEAR	BOOL	Decimal		
RESET	BOOL	Decimal		
-START	BOOL	Decimal		
STOP	BOOL	Decimal		
E State	UDT_MachState		Indicates Current Machine Sta	
-ABORTED	BOOL	Decimal		
ABORTING	BOOL	Decimal		
CLEARING	BOOL	Decimal		
-IDLE	BOOL	Decimal		
-RESETTING	BOOL	Decimal		
RUNNING	BOOL	Decimal		
STARTING	BOOL	Decimal		
STOPPED	BOOL	Decimal		
STOPPING	BOOL	Decimal		
F PreState	UDT MachState		Indicates Previous or Last Mar	

Modifications to the state, command, or mode need to be made to the corresponding data types. For example, to modify the state names, open and edit the UDT\_MachState data type.



## **Tag and Logic Modification Recommendations**

This table contains some of the common modifications to consider for the state machine. The modifications and corresponding recommended actions are meant to highlight the more significant updates that are needed. Additional updates could also be necessary.

Modification	Description	Recommended Actions
State Names	Simple change to the state name. The number of states and relationship between states remain unaltered. Example: Change RUNNING state to PRODUCING.	<ul> <li>Modify the UDT_MachState data type.</li> <li>Update the corresponding MachineSTATE_AOI embedded state name. <sup>(1)</sup></li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>
Command Names	Simple change to the command name. Their intended function remains unaltered. Example: Change RESET command to INITIALIZE.	<ul> <li>Modify the UDT_MachCmd data type.</li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>
Mode Names	Simple change to the mode name. The number of modes and their intended function remain unaltered. Example: Change OPERATOR mode to MANUAL.	<ul> <li>Modify the UDT_MachMode data type.</li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>
Add/Remove States	Adding additional states or removing states. The operation of the state machine will change to accommodate an increase or decrease in states. Example: Add a new state called PAUSED.	<ul> <li>Modify the UDT_MachState data type.</li> <li>Modify the machine module monitor and control routines as needed.</li> <li>If necessary, add/remove commands to support the changes in the states. Refer to <u>Add/Remove Commands</u> modification.</li> <li>If new states were added, then update the corresponding MachineSTATE_AOI embedded state name.</li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>
Add/Remove Commands	Adding additional commands or removing commands. Typically, increases or decreases in commands are required to support corresponding changes (+/-) with states. Example: Add a new command called PAUSE to support a new state called PAUSED.	<ul> <li>Modify the UDT_MachCmd data type.</li> <li>Modify the machine module monitor and control routines as needed.</li> <li>Modify the application and device modules monitor and control routines as needed. Typically, changes in commands require changes in the module status (UDT_AppStatus and UDT_ModuleStatus). For example, if you add a new command called PAUSE, then you should add a new status response from the modules called Paused.</li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>
Add/Remove Modes	Adding additional modes or removing modes. Example: Add a new mode called THREAD.	<ul> <li>Modify the UDT_MachMode data type.</li> <li>Modify the machine module monitor and control routines as needed.</li> <li>Modify the application and device modules monitor and control routines as needed.</li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>
State-to-State Relationships	Changing the conditions that enable transitions between states. Example: Update logic to transition from STOPPED directly to STARTING, bypassing IDLE.	<ul> <li>Modify the machine module monitor and control routines as needed.</li> <li>Modify the application and device modules monitor and control routines as needed.</li> <li>Update the HMI file as needed. <sup>(2)</sup></li> </ul>

(1) Refer to State Display Tag Modifications, on page 245, for more information.

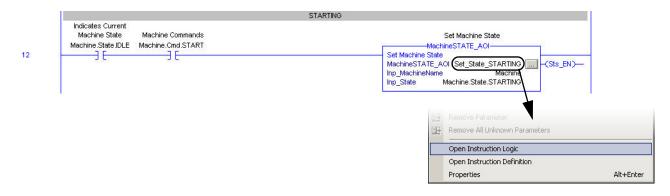
(2) Refer to Chapter 5, on page 101, for more information on the HMI terminal layout and function.

### **State Display Tag Modifications**

Each instance of any MachineSTATE\_AOI instruction contains an embedded string tag that sets the Machine.StateDisplay tag following a state change. The Machine.StateDisplay tag is referenced by the HMI to display the current or active machine state.

Follow these steps to modify the embedded string tag.

1. Right-click the AOI tag name and choose Open Instruction Logic.



2. Navigate to rung 5, right-click State\_Name, and choose Monitor "State\_Name".



**3.** Use the String Browser to modify or set the State\_Name.

The new state name should match the updated state set by the MachineSTATE\_AOI instruction. For example, if the MachineSTATE\_AOI instruction places the machine into the Machine.State.PRODUCING state, then the corresponding State\_Name tag should be set to PRODUCING.

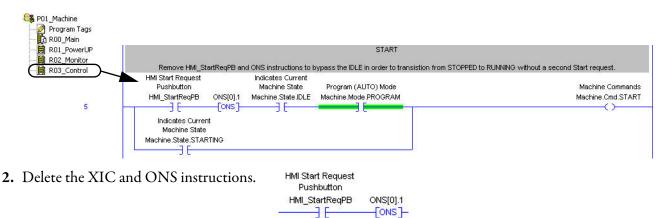
Each instance of any MachineSTATE\_AOI needs to be set or updated based on changes to the machine states.

Name === 🛆	Usage	Value 🗧	Force Mask 🛛 🗧 🗲	Style
EnableIn	Input	0	l.	Decimal
EnableOut	Output	0		Decimal
⊞-Inp_MachineName	e InOut	{}	{}	
Inp_State	InOut	0		Decimal
⊞-State_Name	Local	STARTING'	{}	
Sts_EN	Output	0	j į	Decimal
±-Zero	Local	{}	{}	
String Browser - Stat	e_Name*	-	× \$\$ \$'	
	e_Name*	×	\$\$	
			\$\$ \$' \$L \$N \$P	

### **Bypass Idle State Modifications**

By default, the state machine transitions from STOPPED to IDLE when Start is pressed on the HMI terminal. While in IDLE, typically all of the modules are reset and ready to run. Sercos and CIP Motion axes, for example, are enabled and holding position at this point. When Start is pressed a second time, the machine transitions from IDLE to RUNNING and motion begins. If your machine is not required to dwell on the IDLE state, but instead transitions to the RUNNING state, then make this edit:

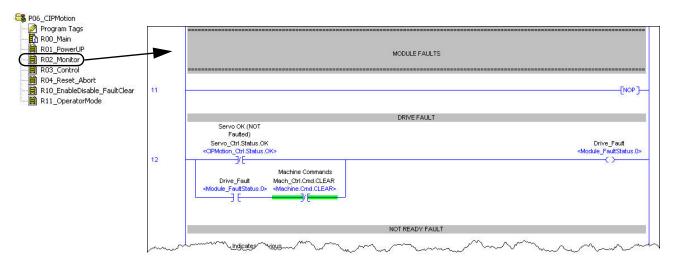
1. Navigate to rung 5 in the R03\_Control routine for the machine module.



The IDLE state was not removed. Instead, the state machine transitions instantly from IDLE into STARTING without requiring a second start request. To you, the operator, it will appear as if the IDLE state was removed or bypassed altogether.

## **Module Fault Customization**

The application and device module R02\_Monitor routines contain module fault logic.



Module faults are intended to act as a diagnostic tool to cover not only a drive or device fault, but also module specific faults. You can add custom module fault logic to provide additional diagnostic information based on your application. The default module specific faults are listed below.

#### **Module Faults**

Fault Description	Module Usage	Alarm History Fault Code
Drive Fault	Device Module	1
Not Ready	Application Module     Device Module	2
Failed to Clear	Application Module     Device Module	3
Failed to Reset	Application Module     Device Module	4
Failed to Start	Application Module	5
Failed to Stop	Application Module	6
Safety Fault	Device Module	7
User Alarm	Reserved	819 <sup>(1)</sup>
Instruction Error	Application Module     Device Module	20

(1) Alarm History fault codes 8...19 are placeholders. You can use them to quickly add custom user-defined module faults. Refer to Chapter 5, FactoryTalk View ME Configuration, on page 101, for more information on the Alarm History faceplate and its function.

All of the device modules also contain a general drive fault. The Drive Fault is in addition to the drive specific faults. For example, when a CIP Motion drive faults for an Excessive Position Error, both the drive specific fault (Excessive Position Error) and general fault (Drive Fault) are displayed on the HMI Alarm History faceplate. This general Drive Fault is also triggered when a drive faults, but does not provide specific fault information, for example, PowerFlex 4-class drives.

To add new module faults to the Alarm History faceplate, navigate to the fault trigger rungs and add the logic for your new fault with the appropriate fault code number.

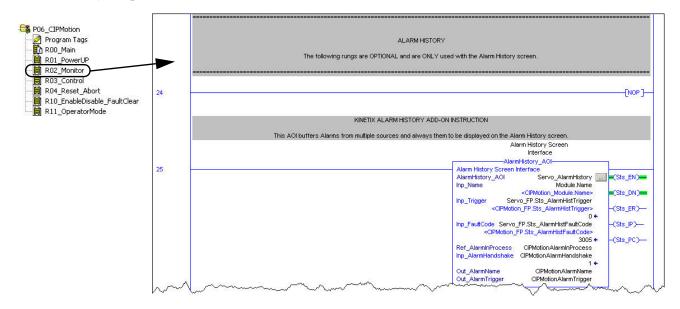
R01_PowerUP		DRIVE FAULT TRIGO	3GER		
R02_Monitor R03_Control R04_Reset_Abort	26	Drive_Fault <module_faultstatus.0> Module_FaultTrigger</module_faultstatus.0>	Module_FaultTrigger		
R03_Control   R04_Reset_Abort   R10_EnableDisable_FaultClear   R11_OperatorMode			Move Source 1		
			Dest Module_FaultCode 1 ←		
		NOT READY FAULT TR	GGER		
	27	NotReady_Fault <module_faultstatus.1> Module_FaultTrigger</module_faultstatus.1>	GGER Module_FaultTrigger		
	27	NotReady_Fault	Module_FaultTrigger (L)		
	27	NotReady_Fault <module_faultstatus.1> Module_FaultTrigger</module_faultstatus.1>	Module_FaultTrigger		

In addition to adding the logic for the new module faults, the alarm message within the HMI application needs to be entered for the associated trigger value.

actoryTalk View Studio - Machine Edition - [Alarm	Setup - /P¥P100	0_Application/]				
File Edit View Application Tools Window Help						Ð
1 🖶 🎒   🗅 🚅 🚿 🔃 🚔						
lorer - P¥P1000_Application	<u> </u>		1			
nter (USMEQKEMATHSO1)	Triggers	Messages Advanced	1			
E- 📴 PVP1000_Application	10-10-10-10-10-10-10-10-10-10-10-10-10-1					
E 🐘 PVP1000_Application	Irige	ger filter: <none></none>		✓ Sort by: <none></none>		
🖻 🔄 System	Alayes a					
Project Settings	Marini	iessages:			- I	
🛛 🖙 Runtime Security		Trigger	Trigger value	Message	Display	<b>.</b>
- 👸 Diagnostics List Setup	2	ModuleAlarmTrigger		/*5:0 ModuleAlarmName*/ Not Ready		-
- 😽 Global Connections	3	ModuleAlarmTrigger	3	/*S:0 ModuleAlarmName*/ Failed to Clear		
Startup	4	ModuleAlarmTrigger	4	/*5:0 ModuleAlarmName*/ Failed to Reset	<u> </u>	-
	5		5	/*S:0 ModuleAlarmName*/ Failed to Start	<u> </u>	-8
	6	ModuleAlarmTrigger ModuleAlarmTrigger	6	/*S:0 ModuleAlarmName*/ Failed to Stop /*S:0 ModuleAlarmName*/ Safety Fault	য	-8
		ModuleAlarmTrigger		/*5:0 ModuleAlarmName*/ Jserety Fault /*5:0 ModuleAlarmName*/ User Alarm	<u>v</u>	-
		ModuleAlarmTrigger		/*S:0 ModuleAlarmName*/ User Alarm	- V	•
🕀 🌌 Displays	10	ModuleAlarmTrigger		/*S:0 ModuleAlarmName*/ User Alarm		-
	10	ModuleAlarmTrigger	10	/*S:0 ModuleAlarmName*/ User Alarm	V	-
🕀 📝 Libraries	12			/*S:0 ModuleAlarmName*/ User Alarm	V .	1
庄 🚾 Images				/*S:0 ModuleAlarmName*/ User Alarm	<b>V</b>	
🕀 🗭 Parameters	4		1		•	ſ
Local Messages	Paralan					1
🖻 🔄 Alarms						-
Alarm Setup				OK Cancel	Help	
					<u> </u>	ł.
Information Setup						
Information Messages						
Macros						
📄 🔄 Data Log						
🛛 🖾 🔗 Data Log Models						
🖻 🔄 RecipePlus						
📲 👬 RecipePlus Setup						
RecipePlus Editor						
E RSLinx Enterprise						
System						
Jystem						
ication Communications	-11					
CIP connection (0) open rejected (Error 2040101) on ro	ute Coptroll origin	dot 0 of the chassis at 1	92 168 1 101		Clear Cle	
cue connection (o) open rejected (pror 2040101) on ro	ate controllogix in	SIOCO OF THE CHASSIS AC I	.72,100,1,1UL,			Bel
					NUM	

## **Alarm History Faceplate Logic Modification**

The alarm history rungs, located in the application and device module R02\_Monitor routines, support the HMI Alarm History faceplate.



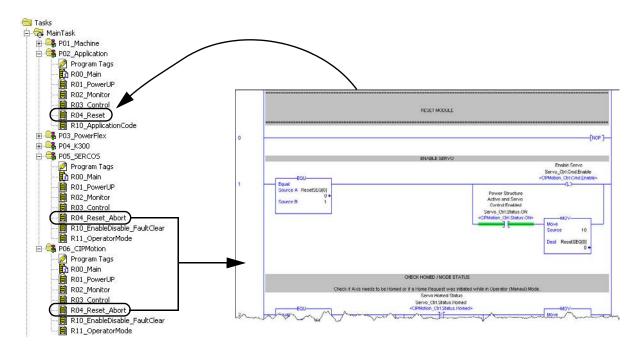
If your HMI application does not include the Alarm History faceplate, then you can remove this logic from the monitor routine for each module. You can locate the Alarm History faceplate logic rungs just below the Alarm History header, in the rung comments.

To remove logic, select Alarm History rungs in each R02\_Monitor routine of each application and device module and press the delete key or menu item.

## **Coordinated Reset Customization**

By default, each device module is pre-programmed with reset logic that is designed to prepare the module and the devices it contains (drives, for example) to run. For a sercos or CIP Motion axis, this might mean the reset logic will home the axis. This approach is well suited for applications where the individual device modules reset independently. However, some applications require multiple device modules to reset in a coordinated manner. For example, when two or more sercos and/or CIP Motion axes are homed in sequential order to avoid mechanical interference.

The recommended method to achieve a coordinated reset is to remove the reset-sequence logic from each of corresponding device module R04\_Reset\_Abort routines and insert it into the application R04\_Reset routine.



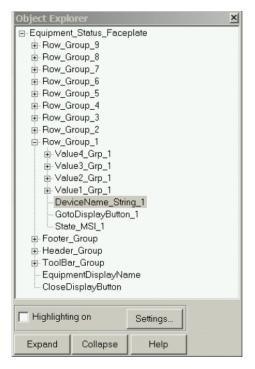
The reset logic from each device module can be blended together into a single reset sequence in the application module. Also, your application may contain device modules that can be reset independently while others may need a coordinated reset. In these cases, you only need to relocate the reset logic for the device modules that require the coordinated reset.

# Add Other Devices to the Equipment Status Faceplate

In this appendix you add devices that do not have pre-configured faceplates, such as a discrete device (solenoid or valve).

## Add Devices to the Equipment Status Faceplate

- 1. Go to the Object Explorer dialog box and select which Row\_Group you wish to display the Nonpreconfigured Device in.
- **2.** Find the DeviceName\_String\_*x* object for that row.



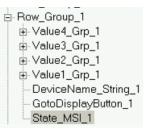
3. Double-click DeviceName\_String\_x object to open the String Display Properties and go to the Connections tab.

General C	ommo	1 Connections		
Name		Tag / Expression	Tag	Expr
Value	+	{#1.Set_DeviceNameOper}		

4. Assign a new controller tag by clicking the Tag browser and search for a controller tag containing the string name you want to display or you can type a static name in the tag field by enclosing in quotes, for example, "Furnace 1".



5. Go to the State\_MSI object and double-click to open its properties.



6. Click the States tab.

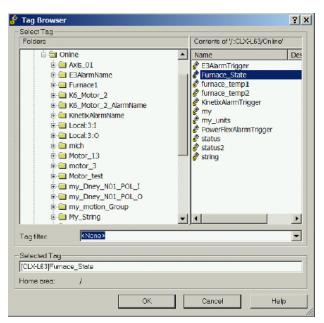
numerate indicator p	roperues		
General States Com	nmon Connections		
Select state: State0 State1 State2 State3 State4	General Value: 0	Back color Border color Blink	Pattern style: None
State4 State5 State6 State7 State8 State9 State9 State10 State11	Caption		×
State12 State13 State14 State15	Font Arial	Size:	Insert Variable

This Multistate Indicator has been pre-configured with 18 device states. When the tag assigned to the MSI becomes a certain value, the MSI displays the appropriate caption.

7. You can use the pre-existing captions and create logic in your controller to move the appropriate value to your device tag or edit the captions and values to meet your needs.

- **8.** Click the Connections tab and assign a device tag to the MSI by clicking the Tag browser.
- **9.** For your specific application, you may need to consider deleting any states you are not using to avoid any unwanted captions being displayed.

Lastly, there are four Value groups for each row that contain a numeric display and a string object to display units that you can configure.



**10.** Expand the Value1\_Grp group.

- Row\_Group\_1
   Value4\_Grp\_1
   Value3\_Grp\_1
   Value2\_Grp\_1
   Value1\_Grp\_1
   Value1\_Grp\_1
   Value1\_Str
   Value1\_Str
   Value\_Panel1
   DeviceName\_String\_1
- 11. Double-click the Value1\_Str object to open its properties. Click the Connections tab and assign a tag to the Numeric Display object.

lumeric Di	splay P	roperties		
General	Commo	n Connections		
Name		Tag / Expression	Tag	Exprn
Value	+	{[CLX-L63]furnace_temp1}		
Polarity	+			

12. Double-click the Units1\_Str object to open its properties. Click the Connections tab and assign a tag in the controller that contains a String for the units, or simply type in a static sting by enclosing in quotes. In this example, "degrees" is the tag name.

mon	Connections		
	Tag / Expression	Tag	Exprn
+ [	"degrees"		
			Tag/Expression Tag

13. Repeat <u>step 11</u> and <u>step 12</u> for each Value*x*\_Grp group in your row.

## **Add Optional Faceplate Views**

This example shows two additional faceplate toolbar buttons added to the Equipment Status faceplate that toggle between the existing main Equipment\_Status\_Faceplate Group (Home Button) and a new Help Object Group (Help Button).

Equipment_Status_Faceplate_a - /equip_faceplate// (Display)										
	5555	555555555555555555555555555555555555555	5555555555		x					
Device	State	Value 1	Value 2	Value 3	Value 4					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					
\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$\$	NOT READY	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS	NNNNNN.NNN SSSSSSSSS					

- 1. Create a new object group, for example, HelpManual\_Group, to be launched and add the objects within that group you wish to display when Help toolbar button is pressed.
  - HelpManual\_Group
    Text9
    Text8
    Text7
    Text6
    Text1
    Polygon2
    Polygon10
- 2. Right-click the new group and choose Animation>Visibility.
- **3.** Set the Visibility animation to be true when the Set\_EquipFaceplateAnimation tag in the AOI becomes a certain value, for example, 1.

Ani	mation			>
	Horizontal Position	Vertical Position	Horizontal Slider	Vertical Slider
ſ	<u>F</u> ill	Touch	<u>C</u> olor	OLE Verb
ſ	✓ Visibility	<u>R</u> otation	<u>₩</u> idth	Height
	Expression {#1.Set_EquipFaceplateAnim	nation} == 1		Tags Expression

- 4. Create an Interlocked Pushbutton on toolbar (see example) that will activate visibility of the new Object Group.
- 5. Set the Connection or tag tied to this button to {#1.Set\_EquipFaceplateAnimation}.

nterlocked Push Button Properties								
General St	tates	Common	Connections	]				
Name			Ta	g/Expression			Tag	Expm
Value	↔	{#1.Set_B	quipFaceplat	eAnimation}				

6. Set the button value to the number assigned in the group animation in step 3.

opearance		
Border style:	Borderwidth:	
Raised	▼ 4	Border uses back color
Back style:		Highlight color
Solid	•	
Shape:		
Rectangle	•	
-		
-		
puch margins Horizontal margin:		
puch margins Horizontal margin:	Vertical margin:	
ouch margins Horizontal margin: 0		
Horizontal margins Horizontal margin: 0 ther 4 Audio		
ouch margins Horizontal margin: 0		

7. Create another Interlocked Pushbutton on the toolbar (Home button in this example) that will activate visibility of the existing Equipment\_Status\_Faceplate Group.

The pre-configured visibility value for this group is 0.

8. Repeat <u>step 1</u> through <u>step 7</u> for additional faceplate object groups you wish to visually activate by faceplate toolbar buttons.

### Notes:

# Logix Designer Communication and Controller Configuration

In this appendix you configure your personal computer and controller communication, configure your controller, and create a new project using the Logix Designer application.

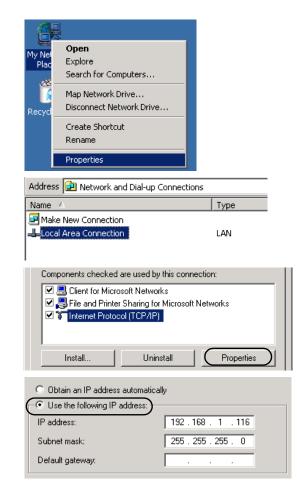
## **Configure Personal Computer Communication Properties**

In this section you set and verify the IP address of the personal computer running your program.

### Set the IP Address

1. On your desktop, right-click My Network Places and select Properties.

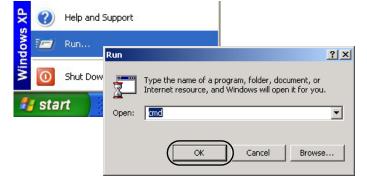
- 2. Double-click Local Area Connection.
- 3. On the General tab, select Properties.
- **4.** Verify Internet Protocol (TCP/IP) is checked and selected.
- 5. Click Properties.
- 6. Select Use the following IP address.
- 7. Enter the IP address and Subnet mask as shown or enter your address.
- 8. Click OK.
- 9. Close all network windows.



### Verify Your IP Address

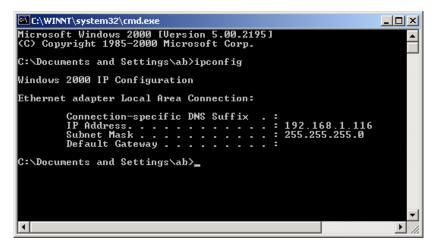
1. From the Start menu, select Run.

The Run dialog box opens.



- 2. Enter cmd.
- 3. Click OK.

The Windows IP Configuration dialog box opens.



- **4.** Enter ipconfig at the prompt.
- 5. Press Enter.
- 6. Verify that the IP address and Subnet Mask match what you entered.

If these numbers do not match what you entered, contact your network administrator.

7. Close the cmd.exe window.

### **Configure the EtherNet/IP Driver**

- 1. Click the RSLinx icon in the system tool tray to start the RSLinx Classic software.
- 2. From the Communications menu, choose Configure Drivers.

The Configure Drivers dialog box opens.

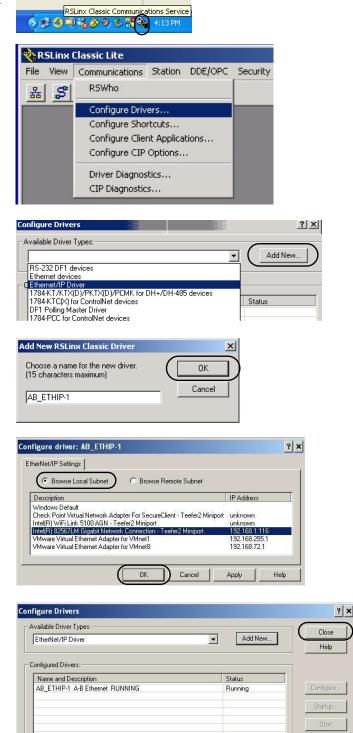
- **3.** From the Available Driver Types pull-down menu, choose EtherNet/IP Driver.
- 4. Click Add New.
- 5. Click OK to accept the default name.

The Configure Driver dialog box opens.

- 6. Select Browse Local Subnet and associated personal computer EtherNet/IP port.
- 7. Click OK.

The EtherNet/IP driver is added to the Configured Drivers list.

- 8. Verify that the status of the driver indicates Running.
- 9. Click Close.



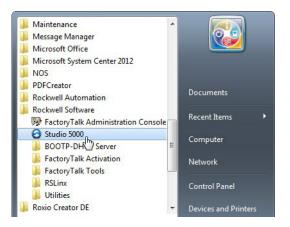
Stop

# **Configure the Logix5000 Controller**

### Check the Web for Firmware Updates

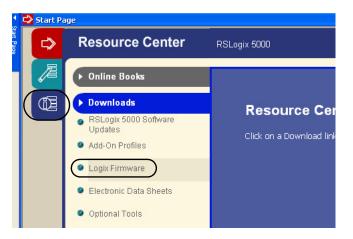
Follow these steps to check for ControlFLASH firmware updates.

1. From the Start menu, launch the Studio 5000 Logix Designer application.



The Start Page opens.

- 2. Click the Resource Center icon on the Start Page.
- 3. Choose Downloads>Logix Firmware.



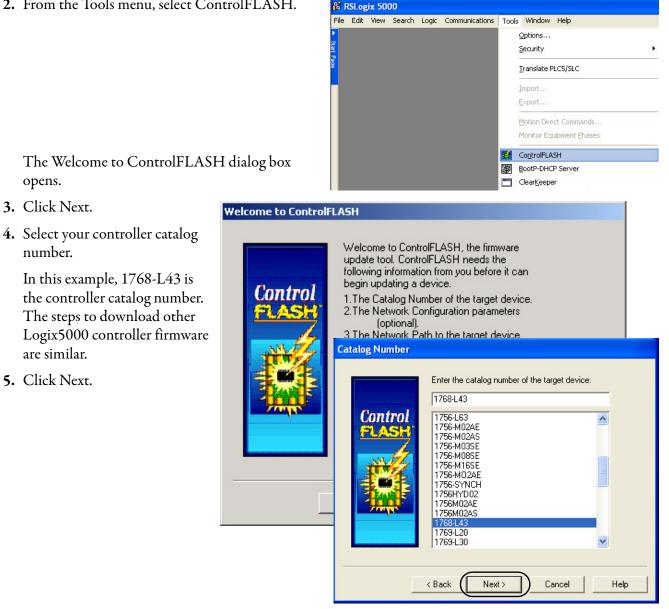
### The Get Support Now webpage opens.

Get Support Now	GET SUPPORT NOW
- Overview	Firmware Updates
<ul> <li>Self-Service Support</li> <li>Knowledgebase</li> </ul>	To view and download firmware updates, click on the appropriate link below.
- Downloads - Software Registration	Control Hardware*     RSLogix 5000, ControlLogix I/O, Flex I/O, NetLinx Comm Cards, PowerFlex and Stratix     Switches
Transfer	<ul> <li>FactoryTalk View ME* (formerly RSView ME) — PanelView Plus, VersaView CE (FUW utility)</li> </ul>
<ul> <li>Phone / OnSite Support</li> <li>North America:</li> </ul>	<ul> <li><u>Drives</u> — PowerFlex 7-Class and peripherals, PowerFlex 4-Class and peripherals, SCANport products and peripherals, 1756-DM drive modules, EDS file icons and DriveTools SP patches</li> </ul>
1-440-646-3434 - Direct Dial Menu	Condition Monitoring – XM Series Modules and Utilities, Datapac Opsys 1000, 1250, 1500, Enpac 2500
- Outside North America	<ul> <li>GuardPLC* – GuardPLC 1200, 1600, 1800, and 2000 controllers, and GuardPLC Distributed I/O</li> </ul>
Live Chat	<ul> <li>SMC Soft Starters — SMC-Flex control flash and hyperterminal updates</li> </ul>

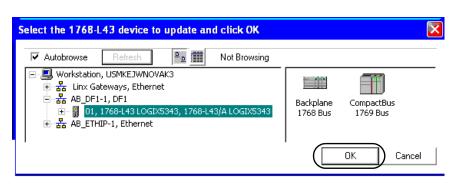
- 4. Click Control Hardware to access the controller firmware.
- 5. Follow the webpage instructions to download firmware.

### Load the Controller Firmware

- TIP This procedure shows how to load firmware in the controller using a serial connection. It is faster to load the firmware using an EtherNet/IP connection. For details, see the controller installation instructions.
- 1. Apply input power to the CompactLogix controller power supply.
- 2. From the Tools menu, select ControlFLASH.



- 6. Under AB\_DF1-1, select the 1768-L43 controller.
- 7. Click OK.



**8.** Move the controller keyswitch to Program.



**9.** Compare the current drive firmware revision to the latest revision listed.

If the Current Revision matches the newest Revision listed, then your controller already has the latest firmware and a firmware update is not needed.

- a. Click Cancel to abort the firmware upgrade.
- b. Go to Assign IP Addresses on page 263.

If the Current Revision does not match the latest revision listed, click Next.

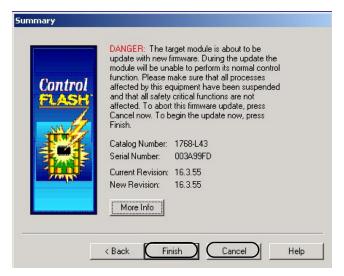
Control	Serial Number: 003A99FD Current Revision: 16.3.55 Select the new revision for this update:	
FLASH	Revisi       Restricti         16.2.48       Show All         16.3.55       Restrictions	
	Current Folder: c:\progra~1\contro~1	

**TIP** If you are unsure which revision to use, select the latest.

**10.** Click Finish, then click Yes to start the firmware update.

When the controller is updated, the status box displays Update Complete.

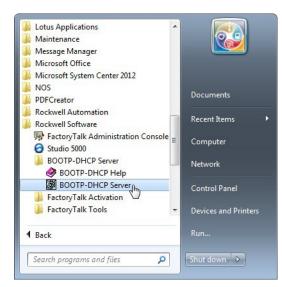
- 11. Click Ok.
- **12.** Click Cancel to close the ControlFLASH software.
- 13. Click Yes.



### Assign IP Addresses

The BOOTP/DHCP Server utility is used to assign IP addresses to most devices in this quick start, except the PanelView Plus terminal. The BOOTP/DHCP utility is installed during the Logix Designer application installation.

1. From the Start menu, launch the BOOTP/DHCP Server utility.



If you are running this utility for the first time, the Network Setup Error dialog box opens.

- a. Click OK.
- b. Enter the subnet mask from step 7 on page 257.

If you are not running this utility for the first time, select Tools>Network Settings.





**2.** Click OK.

The Request History field displays all devices in your network that need IP addresses.

The EtherNet/IP (MAC) addresses correspond to the pre-loaded addresses and typically are marked on the device labels.

N	etwork Settings								X	1
	Defaults								_	
	Subnet Mask:	255		255		255	•	0		
	Gateway:	0		0		0	•	0		
	Primary DNS:	0		0		0		0		
	Secondary DNS:	0		0		0	•	0		
	Domain Name:									
		$\square$	_	OK		)	Ca	ncel	1	
		Ĺ	-		-	<u> </u>				

3. Double-click a request from one of the devices.

File Tools Help	er 2.3					
Request History Clear History A	dd to Relation Lis	t				
(hrmin:sec) Type 14:11:48 BOC 14:11:44 DHC 14:11:44 BOC 14:11:43 BOC 14:11:43 BOC 14:11:45 BOC 14:11:36 BOC	TP         00:00:BC:0           CP         00:00:BC:2           DTP         00:00:BC:0           DTP         00:00:BC:0	1:84:86 8:7F:9A 8:85:86 8:85:86 8:7F:9A	IP Address	Hostname		-
Relation List New Delete E Ethernet Address (M	nable BOOTP	New Entry Ethernet Ad	dress (MAC):	00:00:BC:0		×
			IP Address: Hostname: Description:	192.16	8.1	. 101
Status			(	OK	)Car	icel

- 4. Enter a unique IP address for each device.
- 5. Click OK.

If you are not on an isolated network, obtain the IP addresses from your network administrator.

6. Repeat step 3 through step 5 for each device, except the PanelView Plus terminal.

**IMPORTANT** If you cycle power, the device will not retain its IP address unless you disable BOOTP/DHCP.

7. Select the first device in the Relation List field.

F	telation List New Delete Enable BO(	DTP Ena	able DHCP Disable B	OOTP/DHCP
	Ethernet Address (MAC)	Туре	IP Address	Hostname
	00:00:BC:21:8A:B6	DHCP	192.168.1.101	
	00:00:BC:21:D7:BE	BOOTP	192.168.1.103	
	00:00:BC:2C:90:A0	DHCP	192.168.1.105	
	00:00:BC:08:85:B6	BOOTP	192.168.1.107	
	00:00:BC:08:7F:9A	BOOTP	192.168.1.109	
⊢ S	itatus			
[[	Disable DHCP] Command succe	ssful		

- 8. Click Disable BOOTP/DHCP.
- 9. Repeat step 7 through step 8 for all devices except the PanelView Plus terminal.
- **10.** Close the BOOTP/DHCP utility.

If prompted to save changes, click No.

Browse the EtherNet/IP Network Devices

Follow these steps to verify that all your network devices are present in RSLinx Classic software.

- 1. Click the RSWho icon to view the EtherNet/IP driver and devices on the network.
- 몲
- 2. Verify that all your network devices are detected.

In this example, there are five network devices. The network configuration for your specific application will be different.

<del>ន</del> ័ RSWho - 1		_ 🗆 🗵
Autobrowse Refresh 🖳 🎬 Browsing - node 192.168.1.103 found		
<ul> <li>Workstation, STATION13</li> <li>Kunx Gateways, Ethernet</li> <li>KaB_DF1-1, DF1</li> <li>AB_ETHIP-1, Ethernet</li> <li>192.168.1.10, 1734-AENT PointIO EtherNet/IP Adapter, 1734-AENT Ethernet/IP Adapter</li> <li>192.168.1.103, PowerFlex 70, PowerFlex 70 240V 4.2A</li> <li>192.168.1.105, PanelView Plus 1000, PanelView-Plus</li> <li>192.168.1.107, 1768-ENBT/A, 1768-ENBT/A</li> <li>AB_VBP-1, 1789-A17/A Virtual Chassis</li> </ul>		

### Notes:

# Create and Add BOM Device Modules Without the DMAT Wizard

In this appendix you select an initial preconfigured BOM file without using the DMAT Wizard and import BOM device modules to an existing ProposalWorks file.

## **Before You Begin**

Collect specific application data, for example:

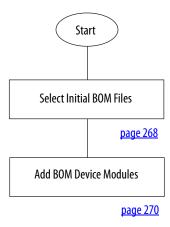
- System Input Voltage
- Ambient temperature and Altitude Specifications
- Transmission Type
- Motor data
- Load Data Inertia and Cycle Profiles
- Other System Sizing Info

### What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative.
- PowerFlex Family Selection Guide, publication <u>PFLEX-SG002</u>.
- Kinetix Motion Control Selection Guide, publication <u>GMC-SG001</u>.

## **Follow These Steps**

Complete the following steps to create a bill of materials and size your drives and motion system components.

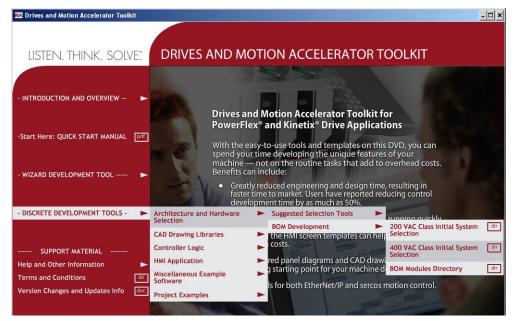


# **Select Initial BOM Files**

Follow these steps to select your initial BOM files.

- 1. Open and rename the initial ProposalWorks BOM file.
  - a. Navigate to and select the appropriate voltage class directory, based on your system power voltage, within the BOM development folder.

For the Widg-O-matic example, 400 VAC Class directory is selected.



The Voltage Class System Start folder opens.

b. Double-click the ProposalWorks file based on your power distribution hardware preferences.

### Initial ProposalWorks File Selection

ProposalWorks Initial BOM File	Distribution Equipment Type	Overcurrent Protection Type	
xxxVAC w-IEC CB-L.prp	IEC	Circuit breaker	
xxxVAC w-IEC Fused-L.prp	IEC	Fuse	
xxxVAC w-LIM-L.prp	UL, using Line Interface Module (LIM)	Circuit breaker with LIM module	
xxxVAC w-UL CB-L.prp	UL	Circuit breaker	
xxxVAC w-UL Fused-L.prp	UL	Fuse	

For the Widg-O-matic application example, the 400VAC w-LIM-L.prp file is selected.

ProposalWorks software launches and the selected file opens.

The initial BOM files include power and control distribution equipment, control circuit protection, operator devices, and terminal blocks.

	▲ Name ▲	Size	Туре
File and Folder Tasks 🛛 🛠	400V Sys Excel Files		File Folder
<b>21 11 1 1 1 1 1</b>	400VAC w-IEC CB-L.prp	244 KB	ProposalBuilder Doc.
💋 Make a new folder	400VAC w-IEC Fused-L.prp	253 KB	ProposalBuilder Doc.
Publish this folder to the Web	460VAC w-LIM-L.prp	242 KB	ProposalBuilder Doc.
Share this folder	480VAC w-UL CB-L.prp	246 KB	ProposalBuilder Doc.
Si lare unis rolder	480VAC w-UL Fused-L.prp	253 KB	ProposalBuilder Doc.

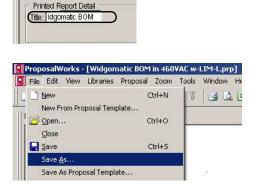
Printed Report Detail Title: LIM Initial BOM		Wt. kg		
ttem / De	vID / Note Qty	Typical Delivery	Wt (kq)	[
Click Refresh to update price	~			
view memesin to update price	5.			
100 Class VAC with LIM Initia	al BOM			
Review and adjust all Produce	Ratinge Accessories and On	tions to meet the needs of your app	lieation	
terren and aujust an i roude	riadings, Accessories and Op	tions to meet the needs of your app	invation.	
Input Power Section				
	2094-BL50S			
		460V, 50A		
1	2094-BL50S Line Interface Module,		N/A	1
	Line Interface Module,	460V, 50A Stocked	N/A	
	Line Interface Module, 1 140U-H-RVM12R	Stocked		
	Line Interface Module, 1 140U-H-RVM12R	Stocked	Red/Yellow	
2	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Dept 1	Stocked		
2	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 1 2090-XXLF-X330B	Stocked n Operating Mechanism, NEMA 4X, 12" Stocked	Red/Yellow	
2	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 1 2090-XXLF-X330B AC Line Filter, Univers	Stocked Deperating Mechanism, NEMA 4X, 12" Stocked sal, 30 AMP, 500VAC, 3 Phase	Red/Yellow N/A	
2	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 1 2090-XXLF-X330B	Stocked n Operating Mechanism, NEMA 4X, 12" Stocked	Red/Yellow	
2	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 1 2090-XXLF-X330B AC Line Filter, Univers	Stocked Deperating Mechanism, NEMA 4X, 12" Stocked sal, 30 AMP, 500VAC, 3 Phase	Red/Yellow N/A	
3	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X330B AC Line Filter, Univers 1	Stocked Departing Mechanism, NEMA 4X, 12" Stocked stocked Stocked Stocked	Red/Yellow N/A N/A	
3	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X330B AC Line Filter, Univers 1	Stocked Departing Mechanism, NEMA 4X, 12" Stocked stocked Stocked Stocked	Red/Yellow N/A N/A	-
3	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X330B AC Line Filter, Univers 1	Stocked Deperating Mechanism, NEMA 4X, 12" Stocked sal, 30 AMP, 500VAC, 3 Phase	Red/Yellow N/A N/A	suppli
2 3 Control Circuit Power - note	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Dept 1 2090-XXLF-X30B AC Line Filter, Univers 1 double click power supply and	Stocked Departing Mechanism, NEMA 4X, 12" Stocked stocked Stocked Stocked	Red/Yellow N/A N/A	r suppli
2 3 Control Circuit Power - note	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X30B AC Line Filter, Univers 1 double click power supply and 1497-H-BASX-0-N	Stocked n Operating Mechanism, NEMA 4X, 12" Stocked al, 30 AMP, 500VAC, 3 Phase Stocked modify 'family'' to select the highe	Red/Yellow N/A N/A r performance power	67.63
2 3 Control Circuit Power - note	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Deptt 1 2090-XXLF-X330B AC Line Filter, Univers 1 double click power supply and 1497-H-BASX-0-N 1497 - CCT Standard	Stocked  Deperating Mechanism, NEMA 4X, 12" Stocked  al, 30 AMP, 500VAC, 3 Phase Stocked  modify "family" to select the higher Transformer, 750VA, 240/430V 60Hz /	Red/Yellow N/A N/A r performance power 220/440V 50Hz Primar	65.65
4	Line Interface Module, 1 140LH-RVM12R Rotary, Variable-Depti 1 2090-XXLF-X330B AC Line Filter, Univers 1 double click power supply and 1497-H-BASX-0-N 1497 - CCT Standard 1	Stocked n Operating Mechanism, NEMA 4X, 12" Stocked al, 30 AMP, 500VAC, 3 Phase Stocked modify 'family'' to select the highe	Red/Yellow N/A N/A r performance power	65.65
2 3 Control Circuit Power - note	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X330B AC Line Filter, Univers 1 double click power supply and 1497-H-BASX-0-N 1497 - CCT Standard 1 1606-XLE120E	Stocked  Operating Mechanism, NEMA 4X, 12" Stocked  al, 30 AMP, 500VAC, 3 Phase Stocked  modify 'Yamily'' to select the higher  Transformer, 750VA, 240/430V 60Hz / Stocked	Red/Yellow N/A N/A r performance power 220/440V 50Hz Primar N/A	γ <u>, 110</u> γ
2 3 Control Circuit Power - note	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X330B AC Line Filter, Univers 1 double click power supply and 1497-H-BASX-0-N 1497 - CCT Standard 1 1606-XLE120E	Stocked  Deperating Mechanism, NEMA 4X, 12" Stocked  al, 30 AMP, 500VAC, 3 Phase Stocked  modify "family" to select the higher Transformer, 750VA, 240/430V 60Hz /	Red/Yellow N/A N/A r performance power 220/440V 50Hz Primar N/A	γ <u>, 110</u> γ
: Control Circuit Power - note	Line Interface Module, 1 140U-H-RVM12R Rotary, Variable-Depti 2090-XXLF-X330B AC Line Filter, Univers 1 double click power supply and 1497-H-BASX-0-N 1497 - CCT Standard 1 1606-XLE120E	Stocked  Operating Mechanism, NEMA 4X, 12" Stocked  al, 30 AMP, 500VAC, 3 Phase Stocked  modify 'Yamily'' to select the higher  Transformer, 750VA, 240/430V 60Hz / Stocked	Red/Yellow N/A N/A r performance power 220/440V 50Hz Primar N/A	γ <u>, 110</u> γ

2. Rename project title in the Title field.

For the Widg-O-matic application example, the 400 Class VAC with LIM Initial BOM file was renamed Widgomatic\_BOM.

- 3. Rename and save the BOM project file.
  - a. Click the File menu and choose Save As.
  - b. Type a new BOM project file name.
     By creating a new BOM project file specifically for your application, you preserve the initial toolkit BOM file for future reference.

In this example, the 400 Class VAC with LIM Initial BOM file was renamed WidgOmatic\_BOM.

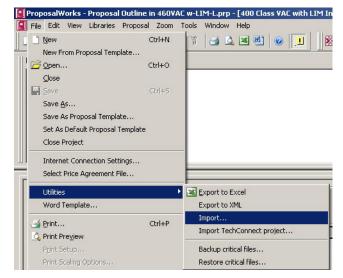




## **Add BOM Device Modules**

Follow these steps to add BOM device modules.

- 1. Import drive BOM files.
  - a. Click File and choose Utilities>Import.



The Import Equipment List from File dialog box opens.

b. Navigate to the 2-BOM Dev folder within the toolkit's Files folder.
Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\

DMAT\B-Files\2-BOM Dev.

- c. Double-click the 2\_200V Class Drives or 4\_400V Class Drives folder based on your system power voltage.
  For the Widg-O-matic machine application example, the 4\_400V Class Drives folder is selected.
- d. Select the file matching your initial drive family included in your application.For the Widg-O-matic machine

application example, the 480VAC K6500-L file.prp file is selected for the two Kinetix 6500 X-Y gantry drives in system.

e. Click Open.

The Import Completion Confirmation dialog box opens.

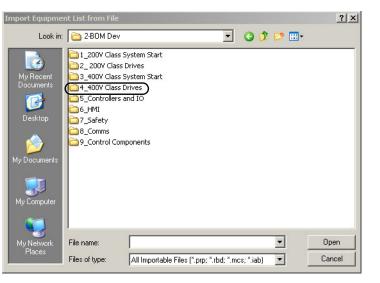
f. Click OK.

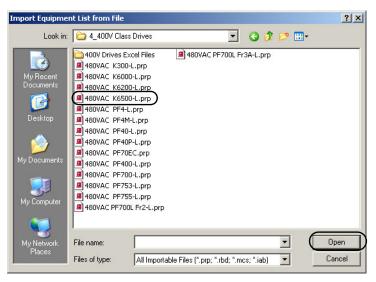
The selected drive equipment is added to the end of the initial BOM file.

2. Repeat <u>step 1</u> for each drive family in your system.

For the Widg-O-matic application example, the 480VAC PF753-L.prp and 480VAC K300-L.prp Drive BOM files are also imported into the initial BOM file to accommodate the conveyor and diverter drives in the system.

3. Import controller and I/O BOM files.

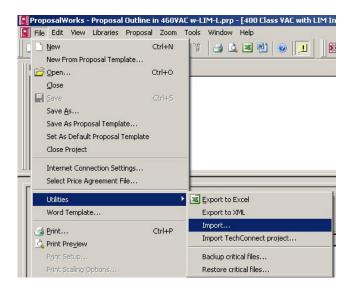




### 400 V Class VAC Kinetix 6500 Initial BOM

#### Kinetix 6500 Multi-axis Servo Drive System Section 14 2094-PRS4 Power Rail, Slim, 230V OR 460V, 4 Axis N/A Stocked 15 2094-BC02-M02-M Power Module, Integrated, 460V, 15kW Conv. 15A Inv., Kinetix 6500 EtherNet/IP Safe Torque-Off Control Modu 1 N/A 15.1 2090-K6CK-D44M Connector Kit Kinetix Safe Speed 44 pir N/A 11 15.2 2094-EN02D-M01-S0 EtherNet/IP Safe Torque-Off Control Module N/A 16 2094-BMP5-M Power Module, 460V, 5A Inv., Kinetix 6500 EtherNet/IP Safe Torque-Off Control Modu 1 N/A 161 2090-K6CK-D44M Connector Kit Kinetix Safe Speed 44 pin N/A

a. Click File and choose Utilities>Import.



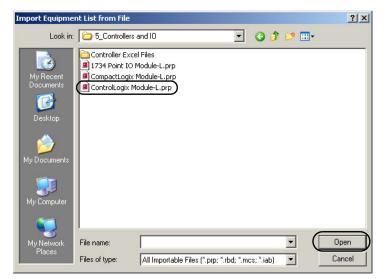
The Import Equipment List from File dialog box opens.

b. Navigate to the 2-BOM Dev folder within the toolkit's Files folder.



Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files\2-BOM Dev.

- c. Double-click the 5\_Controllers and IO folder.
- d. Select the CompactLogix Module-L.prp or ControlLogix Module-L.prp file based on the controller family required for your application.



For the Widg-O-matic machine application example, the ControlLogix Module-L.prp file is selected for support of the two Kinetix 6500 CIP Motion drives in the system.

A variety of Logix5000 controllers can be used in your drives and motion application. Logix5000 controller selection is based on drive capacity and general performance. Refer to the Controller and Drive Capacity table and the appropriate selection guide to assist in controller selection.

### **Controller and Drive Capacity**

	EtherNet/IP CIP Motion Drives	Sercos interface Drives		
Logix5000 <sup>(1)</sup> Controller Type	Kinetix 6500	Kinetix 6200, Kinetix 6000, Kinetix 6000M, Kinetix 2000, Kinetix 7000, and Ultra3000	Kinetix 300 Drives	PowerFlex Drives
	Drives, <sup>(2)</sup> max	Drives, <sup>(2)</sup> max	Drives, <sup>(2)</sup> max	Drives, <sup>(2)</sup> max
1768-L2 <i>x</i>	-	-	6	6
1768-L3 <i>x</i>	-	-	16	16
1768-L43, 1768-L43S	-	4	20	32
1768-L45, 1768-L45S	-	8	20	32
1756-L6 <i>x</i> , <sup>(3)</sup> 1756-L6 <i>x</i> S <sup>(3)</sup>	100	100	128	128
1756-L7x <sup>(3)</sup>	100	100	128	128

(1) Based on controller firmware, revision 18, and RSLogix 5000 software, version 18.

(2) Maximum drive quantity based on CIP or TCP connections and I/O packets for a singe communication module.

(3) Based on 1756-ENxTx EtherNet/IP communication module.

### e. Click open.

The Import Completion Confirmation dialog box opens.

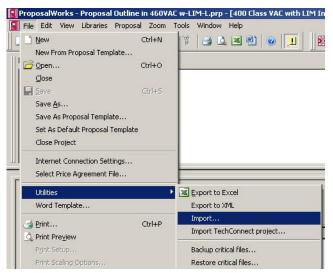
f. Click OK.

Logix Controller Section

42 *Verify Price in SAP	1756 ControlLogix System Group Selection					
42.1	1756-IF8 Analog Input - CurrentA	vottage % Pts (36 Pin)				
	1	Stocked	N/A	31 31		
42.2	1756-OF4 Analog Output - Current	t/Voltage 4 Pts (20 Pin)				
	1	Stocked	N/A			
42.3	1756-A13 13 Slot ControlLogix Ch	assis				
	1	Stocked	N/A	// // // // // // // // // // // // //		
42.4	1756-EN2TR Ether Net dual port 10-1	00M Interface Module (supports '	28 TCP/IP connections, up to	8 axis ), Ring and Ling	ear topologie	
1	1	Stocked	N/A			
42.5	1756-IA16 79-132 VAC Input 16 F	²ts (20 Pin)				
	1	Stocked	N/A			
42.6	1756-OA8 74-265 VAC 2 Amp Out	iput 8 Pts (20 Pin)				
	1	Stocked	N/A			
42.7	1756-IB16 10-31 VDC Input 16 Pts	: (20 Pin)				
	1	Stocked	N/A			
42.8	1756-OB8 10-30 VDC 2 Amp Outp	ut & Pts (20 Pin)		ai		
	1	Stocked	N/A			
42.9	1756-M08SE	Madula				
	8 Axis SERCOS Servo	MUQUIE				

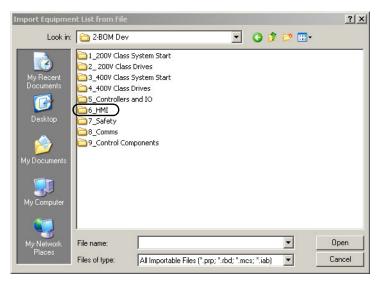
The selected controller and corresponding I/O hardware is added to the end of the initial BOM file.

- 4. Import HMI BOM files.
  - a. Click File and choose Utilities>Import.



The Import Equipment List from File dialog box opens.

b. Navigate to the 2-BOM Dev folder within the toolkit's Files folder.



Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files\2-BOM Dev.

c. Double-click the 6\_HMI folder.

d. Select the PVP 6 in Module-L.prp or PVP 10 in Module-L.prp file based on the relative size of your PanelView Plus required for your application.

Import Equipme	ent List from File	<u>?</u> ×
Look in	: 🔁 6_HMI 💽 🕑 😥 🖽 -	
My Recent Documents Desktop My Documents My Computer	HMI Excel Files PVP 6 in Module-L.prp PVP 10 in Module-L.prp	
My Network Places	File name:     Importable Files (",prp; ",rbd; ",mcs; ",iab)       Files of type:     All Importable Files (",prp; ",rbd; ",mcs; ",iab)	Open Cancel

For the Widg-O-matic machine application example, the PVP 10 in Module-L.prp file is selected for support of a PanelView Plus 1000 terminal in the system.

10 inch HMI Initial BOM

e. Click Open.

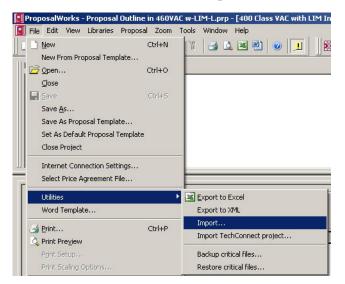
The Import Completion Confirmation dialog box opens.

f. Click OK.

The selected PanelView Plus hardware is added to the end of the initial BOM file.

44	2711P-T10C4A1				
	PanelView Plus 1000 T	ouch, Standard Communications	(Ethernet & RS-232), AC pow	ier, 64 MB	Flash/ 64 MB RAN
	1	Stocked	N/A		
45	2711P-CBL-EX04 Ethernet CAT5 crossov	er cable (industrial grade) 4.3 m i	(14 ft)		
	1	Stocked	N/A	-	

- **5.** Import the Ethernet communication BOM file.
  - a. Click File and choose Utilities>Import.



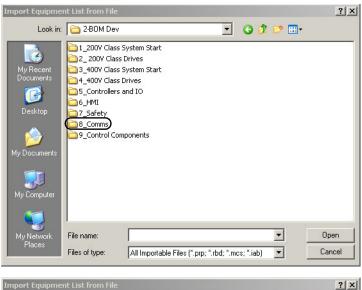
The Import Equipment List from File dialog box opens.

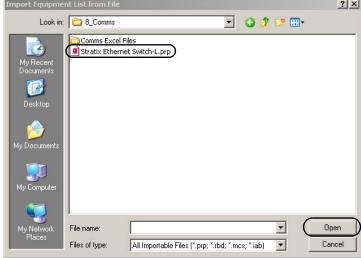
b. Navigate to the 2-BOM Dev folder within the toolkit's Files folder.
Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\

DMAT\B-Files\2-BOM Dev.

c. Double-click the 8\_Comms folder.

- d. Select the Stratix Ethernet Switch-L.prp file.
- e. Click Open.





The Import Completion Confirmation dialog box opens.

f. Click OK.

30	1783-US05T				
	Stratix 2000 Switch, Unm	anaged, 5 Copper Ports			
	1	Stocked	N/A		
1	1783-EMS08T Stratix 6000 Switch Entry	/-Level Managed, %-port			
	ou day, o o o o o o o o o o o o				
	1	Stocked	N/A		
2	1 1585J-M4TBJM-5	Stocked Conductors, RJ45, Straight Mal	M 100000	CMB, CMX, cUL, C	MG, Standard TIA 568-I

The Ethernet switch and cable hardware is added to the end of the initial BOM file.

6. Save your assembled BOM file.

# Assemble Project Drawing Set Without the DMAT Wizard

This appendix provides you with the steps necessary to assemble a project drawing set from the toolkit library without using the DMAT Wizard.

The libraries are organized into power, control, safety, I/O, and communication wiring/panel layout sections. These steps let you easily assemble all of the wiring and layout drawings for your specific system and minimize editing of your drawing set.

TIP If you do not have CAD software that is compatible with the dwg/dxf formats, the pdf files provide an excellent reference library for wiring all your system devices.

## **Before You Begin**

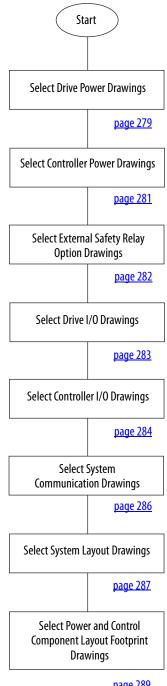
Complete your system layout and wiring (refer to <u>Chapter 2</u>).

### What You Need

- Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative.
- AutoCAD Electrical software to open the DWG or DXF files
- Adobe Reader software to open PDF files
- Line Interface Module Installation Instructions, publication 2094-IN005
- System Design for Control of Electrical Noise Reference Manual, publication GMC-RM001
- System Design for Control of Electrical Noise Video, publication GMC-SP004
- The user manual for your Drives and Motion hardware. Refer to Additional Resources on <u>page 15</u> for publication numbers.

# **Follow These Steps**

Complete the following steps to configure your Logix5000 integrated motion application.



### **Select Drive Power Drawings**

1. Create a project folder.

For the Widg-O-matic machine example, the Widgomatic folder was created.

<u>File E</u> dit <u>V</u> iew F <u>a</u> vorites <u>T</u> ools <u>H</u> elp	<u></u>
🚱 Back 👻 🕥 🖌 🏂 🔎 Search 💫 Folders 🔢	
Address 🛅 C:\Project Drawings	💌 🎅 Go

- 2. Browse to the CAD Drawing Libraries folder on the Drives and Motion toolkit DVD.
- 3. Navigate to the desired file type (DWG, DXF, or PDF) folder and select Power Section.

- 🗆 × RA Drives and Motion Accelerator Tool LISTEN. THINK. SOLVE". DRIVES AND MOTION ACCELERATOR TOOLKIT INTRODUCTION AND OVERVIEW **Drives and Motion Accelerator Toolkit for** PowerFlex® and Kinetix® Drive Applications Start Here: QUICK START MANUAL [pdf] With the easy-to-use tools and templates on this DVD, you can spend your time developing the unique features of your machine — not on the routine tasks that add to overhead costs. Benefits can include: WIZARD DEVELOPMENT TOO Greatly reduced engineering and design time, resulting in faster time to market. Users have reported reducing control development time by as much as 50%. - DISCRETE DEVELOPMENT TOOLS -Architecture and Hardware Selection onfigured logic can get you up and running quickly. **DWG Format Drawings** Power Section **CAD Drawing Libraries**  DXF Format Drawings Controller Logic Control Section SUPPORT MATERIAL HMI Application PDF Format Drawings dir Safety Section Help and Other Information statung point for your machine o Miscellaneous Example Software Drive I/O Section ns and Conditions dir for both EtherNet/IP and sercos r Controller I/O Section dir n Changes and Upo Project Exampl **Communications Section** dir Lavouts Section dir Rockwell Automation Rockwell Software

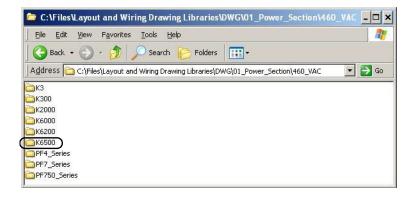
**4.** Double-click the voltage folder matching your system voltage.

For the Widg-O-matic example, the 460\_VAC folder was opened.

**5.** Double-click the folder matching the initial drive family included in your application.

For the Widg-O-matic machine application example, the Kinetix 6500 drive folder was opened.





Copy the power drawing for your drive family based on the Power Distribution Layout table.

🗀 C:\Files\Layout and Wirir	ng Drawing Libraries\DWG\01_Po	wer_Section\460_VAC\K6500	- 🗆 ×
File Edit View Favorites	Tools Help		
🛛 📀 Back 🔹 🕥 🖌 🏂 🏅	🔾 Search 🌔 Folders 🛛 🙀 🏂	× 9 📖	
Address 🔁 C:\Files\Layout and	Wiring Drawing Libraries\DWG\01_Power_	Section\460_VAC\K6500	💌 🛃 Go
010_K6500_460VAC_w_LIM.dwg 010_K6500_460VAC_wo_LIM.dwa			
國 020_K6500_460VAC_Additional_C	법 Convert to Adobe PDF 嫒 Convert to Adobe PDF and EMail 뚾 Combine supported files in Acrobat		
1	Scan for Viruses 혳 WinZip		
	Send To	•	
	Cut		
	Сору		

### **Power Distribution Layout**

Power Distribution Layout Options	Power Drawing
Initial drives including a Bulletin 2094 line interface module (LIM) for main power/control distribution (includes 3 drives)	010_ <i>xxxx</i> _xxxVAC_w_LIM.xxx
Initial drives including traditional main power distribution components (includes 3 drives)	010_ <i>xxxx_xxx</i> VAC_wo_LIM <i>.xxx</i>
Additional drive drawings without main power distribution components (includes 4 drives)	020_ <i>xxxx</i> _xxxVAC_Additional_Drives.xxx

For the Widg-O-matic machine application example, the Kinetix 6500 drawing with LIM module was selected. Because the Kinetix 6500 drive is the initial drive family, a LIM module was selected as the main power distribution component. The LIM module can also supply power to the other drives in the system.

6. Paste the drawing you copied into the Project Drawings folder.

File Edit View Favorites To	ols H	lelp		
🔇 Back 🔹 🕥 🖌 🏂 🔎	Search	Polde	ers 🔯 🎯	× 9 🖦
Address 🗁 C:\Project Drawings\Wi	idgomat	ic		2
Jame 🔺		Size	Туре	Date Modified
a 010_K6500_460VAC_w_LIM.dwg		29 KB	DWG File	8/6/2010 5:08 PM
View				
Arrange Icons By				
Refresh				
Customize This Folder				
Paste				

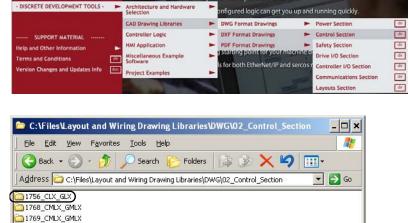
- 7. Copy and paste the 020\_*xxxx*\_*xxx*VAC\_Additional\_Drives.*xxx* drawing if you have more than three drives of the same family and for every four additional drives you have in your system.
- 8. Repeat step 5 through step 7 for every drive family in your system.

For the Widg-O-matic machine application example, the following drawings were copied to accommodate the two Kinetix 6500 servo drives, one PowerFlex 753 drive, and one Kinetix 300 drive.

_ Eile Edit ⊻iew Favorites Tools Help				
🔇 Back 👻 💮 🖌 🎓 Search 🌔 Fold	lers 🔯 🎯	X9	<b></b> •	
Address 📴 C:\Project Drawings\Widgomatic				💌 🔁 Go
			[	
Name 🔺	Size	Туре	Date Modified	
and the second se	Size 29 KB	DWG File	8/6/2010 5:08 PM	
Name  D10_K6500_460VAC_w_LIM.dwg D020_PF750_Series_460VAC_Additional_Drives.dwg		d manhalana		

### **Select Controller Power Drawings**

- 1. Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Control Section.
- 2. Double-click the controller folder matching your actual Rockwell Automation Logix5000 controller based on the Logix5000 Controller Selection table.



### Logix5000 Controller Selection

Logix5000 Controller Options	Supported Drive Families	Controller Folder
ControlLogix or GuardLogix controllers	All PowerFlex drives and all sercos and CIP motion drives	1756-CLX_GLX
L4x CompactLogix or L4xS Compact GuardLogix controllers	All PowerFlex drives and all sercos interface drives up to 8 drives, total	1768_CMLX_GMLX
L3x CompactLogix or L3xS Compact GuardLogix controllers	All PowerFlex drives	1769_CMLX_GMLX

For the Widg-O-matic machine application example, the 1756\_CLX\_GLX folder was chosen because only the ControlLogix platform currently supports the Kinetix 6500 CIP motion drives.

3. Copy the controller drawing for your actual controller platform based on the Controller Power Distribution Layout table.

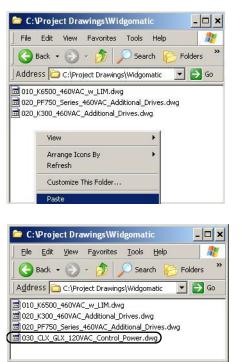
📁 C:\Files\Layout and Wiring Drawi	ng Libraries\DWG\02_Control_Secti	ion\1756_CLX_GLX - 🗆 🗙
File Edit View Favorites Tools H	elp	an 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 1997 - 19
Back 🔹 🕥 + 🏂 🔎 Search	🎼 Folders 🛛 🔯 🏂 🗙 🍫	•
Address 🛅 C:\Files\Layout and Wiring Dra	wing Libraries\DWG\02_Control_Section\1756	_CLX_GLX 🔄 🔁 Go
030_CLX_GLX_120VAC_Control_Power.dwg		
040_CLX_GLX_24VDC_Control_w_LIM.dwg	Open	1
O40_CLX_GLX_24VDC_Control_wo_LIM.dwg	隘 Convert to Adobe PDF 嫒 Convert to Adobe PDF and EMail 뚾 Combine supported files in Acrobat	
	Scan for Viruses @ WinZip	
	Send To 🔸	
	Cut	
	Сору	

### **Controller Power Distribution Layout**

Controller Power Distribution Layout Options	Power Drawing
120V AC controller power supply	03 <i>x_xxxx_xxx</i> _120VAC_Control_Power <i>.xxx</i>
24V DC controller power supply when using a LIM module for main power/control	04x_xxxx_xxx_24VDC_Control_w_LIM.xxx
24V DC controller power supply when using traditional power distribution components for main power/control	04 <i>x_xxxx_xxx</i> _24VDC_Control_wo_LIM <i>.xxx</i>

For the Widg-O-matic machine application example, the 120V AC drawing was chosen.

4. Paste the drawing into your Project Drawings folder.



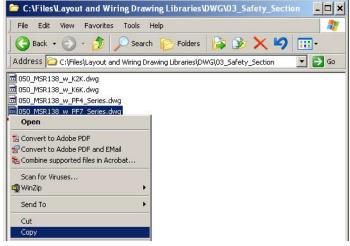
For the Widg-O-matic machine application example, the 030\_CLX\_GLX\_120VAC\_Control Power.dwg file was copied to accommodate the ControlLogix controller.

5. Repeat <u>step 2</u> through <u>step 4</u> for every controller family in your system.

## **Select External Safety Relay Option Drawings**

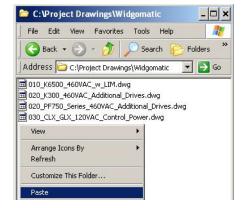
- 1. Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Safety Section.
- 2. Copy the External Safety Relay Option drawings for your specific system hardware.





For the Widg-O-matic machine application example, no external safety drawings were selected because the built-in drive safety I/O was used.

**3.** Paste the drawing into your Project Drawings folder.



# Select Drive I/O Drawings

- 1. Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Drive I/O Section.
- DISCRETE DEVELOPMENT TOOLS 
   Architecture and Hardware
   Selection onfigured logic can get you up and running quickly dr **CAD Drawing Libraries DWG Format Drawings** Power Section Control Section dr Controller Logic DXF Format Drawings PORT MATERIA HMI Application PDF Format Drawings Safety Section dr ther Inform In stalling to a young man Miscellaneous Example Software Drive I/O Section dir for both EtherNet/IP and s Controller I/O Section ect Exa Communications Secti dr uts Sectio

C:\Files\Layout and Wiring Drawing Libraries\DWG\04\_Drive\_10

File Edit View Favorites Tools Help

2. Double-click the folder matching your initial drive family.

For the Widg-O-matic machine application example, the K6500 folder was selected for the Kinetix 6500 drives.

**3.** Copy the drive I/O drawings required for your specific application.

For the Widg-O-matic machine application example, all of the drive I/O drawings were selected.

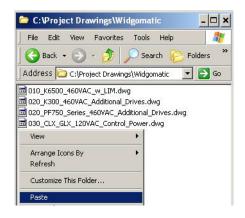
Address 🛅 C:\I	Files\Lavout	and Wiring Dra	wing Libraries\D'	WG\04 Drive IO	 Go
					10
СКЗ					
🚞 КЗОО					
🚞 K2000					
K6000					
K6200					
K6500					
PF4_Series					
PF7_Series					
PF750_Series					
Contraction of the second					

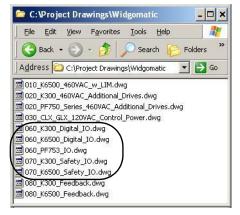


- 🗆 ×

- 4. Paste the drawings into your Project Drawings folder.
- Repeat step 2 through step 4 for every drive in your system with safety options.

For the Widg-O-matic machine application example, the following drive I/O drawings were copied to accommodate the two Kinetix 6500 servo drives, one PowerFlex 753 drive, and one Kinetix 300 drive.





### Select Controller I/O Drawings

 Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Controller I/O Section.

DISCRETE DEVELOPMENT TOOLS -	Architecture and Hardware Selection	🕨 onfigu	ired logic can get you up	and	running quickly.	
	CAD Drawing Libraries	► DWG	Format Drawings	۲	Power Section	de
SUPPORT MATERIAL	Controller Logic	DXF F	Format Drawings	-	Control Section	dir
Help and Other Information	HMI Application		Format Drawings	•	Safety Section	80
Terms and Conditions	Miscellaneous Example	► Pstatt	ing point for your machin	ie a	Drive I/O Section	stir
Version Changes and Updates Info	doc	Is for b	ooth EtherNet/IP and serc	os r	Controller I/O Section	dir
	Project Examples	F			Communications Section	dir
					Layouts Section	dr

2. Double-click the folder matching your Controller I/O.

For the Widg-O-matic machine application example, the 1756\_IO\_CLX\_GLX folder was selected supporting the 1756 ControlLogix controller I/O modules.

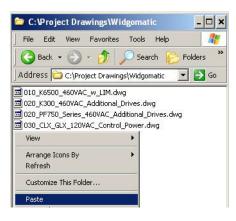
😂 C:\Files\Layout and Wiring Drawing Libraries\DWG\05_PLC_10	
Eile Edit View Favorites Tools Help	
🕒 🚱 Back 👻 🕥 👻 🏂 🔎 Search 🌮 Folders 🛛 🎼 🎲 🗙 🍫	»
Address 🗁 C:\Files\Layout and Wiring Drawing Libraries\DWG\05_PLC_IO 🛛 🔽 🄁	Go
🛅 1734_Point_IO	
1756_IO_CLX_GLX	
1769_IO_CMLX_GMLX	

3. Copy the controller I/O drawings required for your specific application.



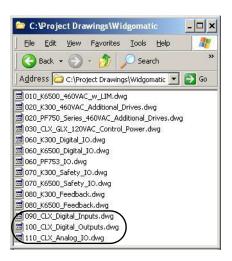
For the Widg-O-matic machine application example, all of the 1756 I/O drawings were selected.

4. Paste the drawings into your Project Drawings folder.



5. Repeat step 2 through step 4 for every unique controller in your system.

For the Widg-O-matic machine application example, the following controller I/O drawings were copied to accommodate the 1756 ControlLogix controller I/O.



## **Select System Communication Drawings**

1. Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Communications Section.

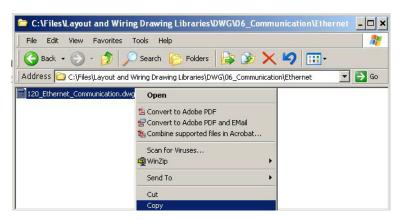
- DISCRETE DEVELOPMENT TOOLS -	•	Architecture and Hardware Selection	-	onfigured logic can get you up and	I running quickly.	
		CAD Drawing Libraries	-	DWG Format Drawings	Power Section	dr
SUPPORT MATERIAL		Controller Logic		DXF Format Drawings	Control Section	dir
Help and Other Information		HMI Application	-	PDF Format Drawings	Safety Section	dr
Terms and Conditions	dr	Miscellaneous Example Software	-	starting point for your machine o	Drive I/O Section	dr
Version Changes and Updates Info	dac			ls for both EtherNet/IP and sercos r	Controller I/O Section	dir
	-	Project Examples			Communications Section	dr
		Contraction in the local division of the loc	-		Layouts Section	dir

2. Double-click the folder matching your drive communication network.

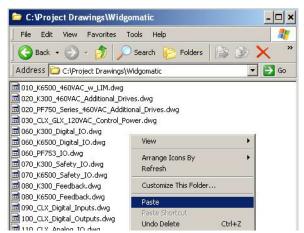


For the Widg-O-matic machine application example, the Ethernet folder was selected supporting Ethernet communication on the two Kinetix 6500 servo drives, one PowerFlex 753 drive, and one Kinetix 300 drive.

**3.** Copy the communication network drawing required for your drive communication.



**4.** Paste the drawings into your Project Drawings folder.



5. Repeat <u>step 2</u> through <u>step 4</u> for your HMI and other device communication in your system, if different than your drive communication network.

For the Widg-O-matic machine application example, the Ethernet communication drawing was copied to accommodate all of the drives and HMI terminals in the system.

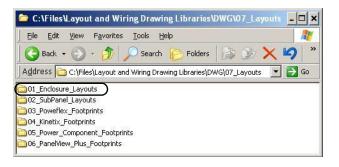


### Select System Layout Drawings

1. Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Layouts Section.

- DISCRETE DEVELOPMENT TOOLS -	•	Architecture and Hardware Selection	-	onfigured logic can get you up	and	running quickly.	
		CAD Drawing Libraries	-	DWG Format Drawings	-	Power Section	dir
SUPPORT MATERIAL		Controller Logic		DXF Format Drawings	-	Control Section	dr
Help and Other Information	1124	HMI Application	-	PDF Format Drawings	-	Safety Section	dr
Terms and Conditions	(ar)	Miscellaneous Example		g starting point for your machin	ea	Drive I/O Section	dir
Version Changes and Updates Info	doc	Software		Is for both EtherNet/IP and serc	os r	Controller I/O Section	dir
		Project Examples	-			Communications Section	dr
			×.		-16	Lavouts Section	dr

 Double-click the 01\_Enclosure\_Layouts folder and open either the Large (60"x60"x12") or Small (60"x36"x12") enclosure folder based on your system enclosure needs.

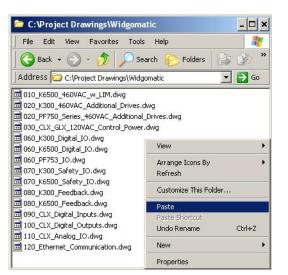


For the Widg-O-matic machine application example, the Small enclosure folder was selected.

📁 C:\Files\Layout and Wi	ring Drawing Libraries\DWG\07_L	ayouts\01_	Enclosure_Layouts\Smal	×
File Edit View Favorites	Tools Help			-
🛛 🚱 Back 🝷 🕥 👻 🏂	🔎 Search 🦻 Folders 🛛 🙀 遂	XS	·	
Address 🛅 C:\Files\Layout a	nd Wiring Drawing Libraries\DWG\07_Layou	ts\01_Enclosu	re_Layouts\Small	- 🔁 Go
140_Sm_Enclosure_Layout.dw	Open			
	뚾 Convert to Adobe PDF 嫒 Convert to Adobe PDF and EMail 뚽 Combine supported files in Acrobat			
	Scan for Viruses എ WinZip	•		
	Send To	•		
	Cut			
	Сору			

3. Right-click the 140\_xx\_Enclosure\_Layout.xxx drawing required for your application and choose Copy.

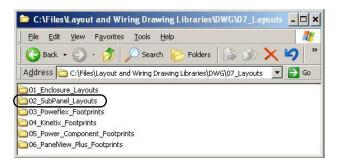
**4.** Paste the enclosure layout drawing into your Project Drawings folder.



 Double-click the 02\_Subpanel\_Layouts folder and open either the Large (Approx. 56"x 56") or Small (57"x 33") subpanel folder based on your enclosure selection and system subpanel needs.

For the Widg-O-matic machine application example, the Small subpanel folder was selected.

**6.** Right-click the appropriate drawing, based on the Subpanel Selection Layout table, and choose Copy.



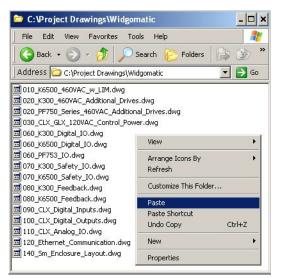
C:\Files\Layout and Wiring Dra	wing Libraries\DWG\07_Layou 💶 🕽	4
File Edit View Favorites Tools	Help 🥂	
🛛 😋 Back 🔹 🕥 🗸 🏂 🔎 Sear	rch 🜔 Folders 🛛 📴 🍞 🗙 🍤 🛛 *	*
Address 🛅 C:\Files\Layout and Wiring I	Drawing Libraries\DWG\07_Layouts\02 💌 🛃 Go	
150_CLX_w_LIM_Sm_Panel_Layout.dwg	Open	1
ISO_CLX_wo_LIM_Sm_Panel_Layout.dw         ISO_CMLX_w_LIM_Sm_Panel_Layout.dw         ISO_CMLX_wo_LIM_Sm_Panel_Layout.dw	법 Convert to Adobe PDF 욹 Convert to Adobe PDF and EMail 賤 Combine supported files in Acrobat	
	Scan for Viruses	
	Send To 🔸	
	Cut	
	Сору	

### **Subpanel Selection Layout**

Logix5000 Controller Family	Power Distribution Layout	Sub-panel Drawing
ControlLogix or GuardLogix	LIM module for three-phase/control power distribution	150_CLX_w_LIM_xx_Panel_Layout.xxx
Controllers	Traditional three-phase/control power distribution components	150_CLX_wo_LIM_xx_Panel_Layout.xxx
CompactLogix or Compact	LIM module for three-phase/control power distribution	150_CMLX_w_LIM_xx_Panel_Layout.xxx
GuardLogix Controllers	Traditional three-phase/control power distribution components	150_CMLX_wo_LIM_xx_Panel_Layout.xxx

For the Widg-O-matic machine application example, the 150\_CLX\_w\_LIM\_Sm\_Panel\_Layout.dwg file was selected.

- 7. Paste the subpanel drawing into your Project Drawings folder.
- 8. Repeat <u>step 2</u> through <u>step 7</u> for every unique enclosure you have in your system.

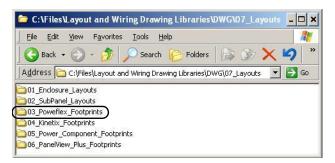


# **Select Power and Control Component Layout Footprint Drawings**

1. Navigate to the desired (DWG, DXF, or PDF) file type folder on the toolkit DVD and select Layouts Section.

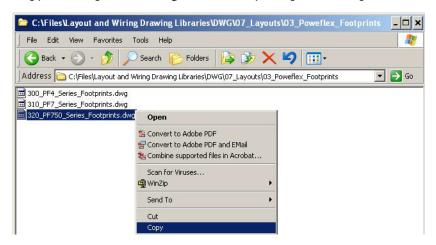
- DISCRETE DEVELOPMENT TOOLS -	•	Architecture and Hardware Selection	-	onfigured logic can get you up ar	nd	running quickly.		
		CAD Drawing Libraries	-	DWG Format Drawings	•	Power Section	dir	
SUPPORT MATERIAL		Controller Logic		DXF Format Drawings	-	Control Section	de	
Help and Other Information		HMI Application	-	PDF Format Drawings		Safety Section	dr	
Terms and Conditions	ितन	[dr]	Miscellaneous Example		g starting point for your machine	0	Drive I/O Section	dir
Version Changes and Updates Info	dax.			Is for both EtherNet/IP and sercos	s r	Controller I/O Section	dir	
		Project Examples	-			Communications Section	de	
			-			Layouts Section	de	

2. Double-click the 03\_Poweflex\_Footprints, 04\_Kinetix\_Footprints, 05\_Power\_Component\_Footprints, or 06\_PanelView\_Plus\_Footprints folder to access the corresponding power or control component footprints within your system for later insertion into your subpanel or communication drawings.



For the Widg-O-matic machine application example, the 03\_Poweflex\_Footprints folder was initially selected.

3. Copy the footprint drawings that match your specific component's family or series.

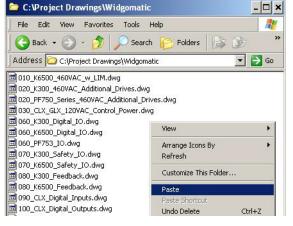


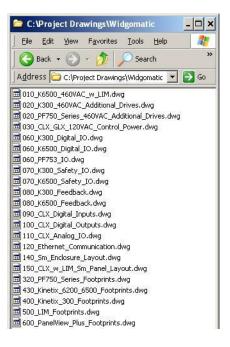
For the Widg-O-matic machine application example, the 320\_PF750\_Series\_Footprints.dwg file was copied to accommodate the layout of the PowerFlex 753 drive onto the Subpanel.

4. Paste the drawing or drawings into your Project Drawings folder.

 Repeat step 2 through step 4 to select your other Kinetix, Power Component, and PanelView Plus footprint drawings.

These project library drawing files comprise the initial drawing set used to create the Widg-O-matic machine application project drawings.





# Controller, Network, and Device Configuration Without the DMAT Wizard

In this appendix you configure your controller, network, and device hardware; then import the machine, application, and device modules into your Logix Designer application without using the DMAT Wizard or making edits after the initial file is created.

# **Before You Begin**

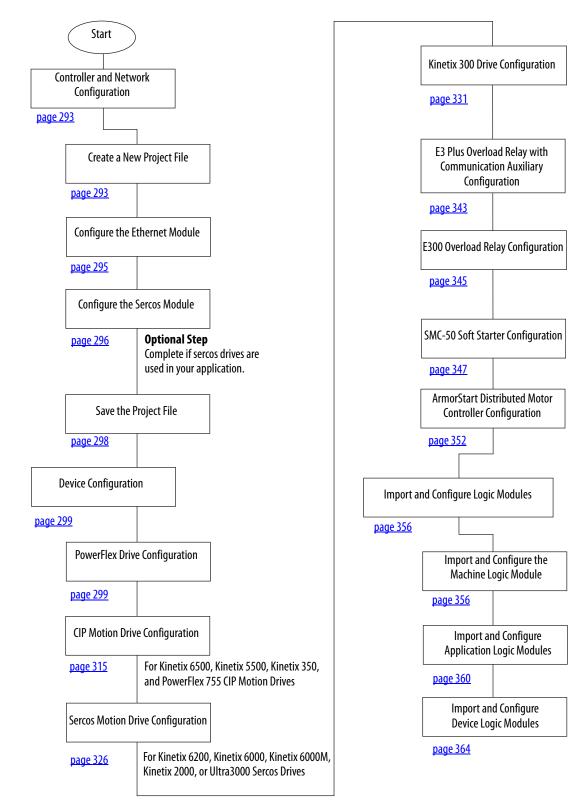
- Complete your system architecture and hardware selection (refer to <u>Chapter 1</u> and <u>Appendix E</u>).
- Complete your system layout and wiring (refer to <u>Chapter 3</u> and <u>Appendix F</u>).

# What You Need

- The Drives and Motion Accelerator Toolkit DVD, publication <u>IASIMP-SP017</u>. For a copy of the DVD, contact your local Rockwell Automation distributor or sales representative.
- RSLogix 5000 software, version 18.0 or later, or the Logix Designer application, version 21.0 or later, for Kinetix 300, Kinetix 6500, PowerFlex 753, and PowerFlex 525 drives.
- RSLogix 5000 software, version 19.0 or later, or the Logix Designer application, version 21.0 or later, for PowerFlex 755 CIP Motion drives and ArmorStart distributed motor controllers.
- RSLogix 5000 software, version 20.0 or later, or the Logix Designer application, version 21.0 or later, for Kinetix 350 servo drives.
- Logix Designer application, version 24.0 or later, for PowerFlex 527 drives.
- Sercos and Analog Motion Configuration and Startup User Manual, publication MOTION-UM001
- CIP Motion Configuration and Startup User Manual, publication MOTION-UM003
- ControlFLASH Firmware Upgrade Kit Quick Start, publication 1756-QS105
- The user manual for your Drives and Motion hardware. Refer to Additional Resources on <u>page 15</u> for publication numbers.

## **Follow These Steps**

Complete the following steps to configure your Logix5000 integrated motion application.



# **Controller and Network Configuration**

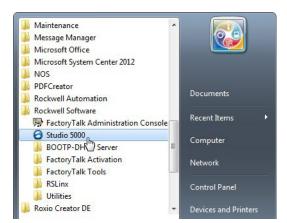
In this section you configure your controller, create a new project file, and setup communication for your Drives and Motion application.

## **Create a New Project File**

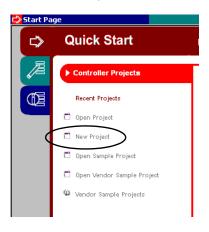
Throughout this chapter the controller and network configuration procedures are written specifically for a 1756-L7*x* ControlLogix controller and Bulletin 1756 communication modules. Steps for other Logix5000 controllers and communication modules are similar.

IMPORTANT	For best performance, 1756-L7 <i>x</i> ControlLogix controllers are recommended for use with CIP motion drive systems.
IMPORTANT	If you are creating a new project and have not configured your personal computer communication or controller hardware, refer to <u>Appendix D</u> , beginning on <u>page 257</u> .

1. From the Start menu, launch the Studio 5000 Logix Designer application.



2. Click New Project.



The New Controller dialog box opens.

New Controller			×
Vendor:	Allen-Bradley		
<u>T</u> ype:	1756-L73 ControlLogix5573 Controller	-	OK
Re <u>v</u> ision:	19 💌		Cancel
	Eedundancy Enabled		Help
Na <u>m</u> e:	WidgDmatic		
Description:		*	
		*	
<u>C</u> hassis Type:	1756-A7 7-Slot ControlLogix Chassis		
Sl <u>o</u> t:	0 * Safety Partner Slot: <none></none>		
Cr <u>e</u> ate In:	C:\RSLogix 5000\Projects		Browse
Security Authority:	No Protection	-	
	Lise only the selected Security Authority for Authentication and Authorization		

- 3. Configure the new controller.
  - a. From the Type pull-down menu, choose the controller type.
  - b. From the Revision pull-down menu, choose the revision.
  - c. Type the file Name.
  - d. From the Chassis Type pull-down menu, choose the chassis.
  - e. Enter the Logix5000 processor slot (leftmost slot = 0).
- 4. Click OK.
- 5. From the Edit menu, choose Controller Properties.

The Controller Properties dialog box opens.

- 6. Click the Date/Time tab.
- 7. Check Enable Time Synchronization.

This enables time synchronization for the controller. Time synchronization is needed for CIP Motion.

IMPORTANT	All controllers and communication
	modules must have time
	synchronization enabled to participate
	in CIP Sync.

8. Click OK.

Advanced	SFC E	xecution	File	Redunda	incy Non	volatile Memory	Memory			
General 9	Serial Port	System P	rotocol	User Protocol	Major Faults	Minor Faults	Date/Tim			
(i) The Dat Use the:	se fields to c	onfigure Tir	me attribut	troller local time, es of the Contro from Workstation	ller.	n local time.				
Date and Tir		die, Time e	inu zone i	ITOHT WY DIRECTION		ate and Time] •				
Time Zone:				5	*					
	Adj	iust for Dayl	ight Savin	g (+00:00) 🍝						
Time Syncl	nronize	9								
🔽 Enable T	me Synchro	onization		disabled controlle	R. If time synch online, active a r in this chassis	axes in any , or any other				
O is the sys	tem time ma	aster			nized device, m sted motion. Sa	ay experience ifety controllers ma	v			
🔾 Is a sync	hronized tim	e slave		fault if n	fault if no other time master exists in the					
O Duplicate	CST maste	er detected		local ch	BSSIS.					
O CST Mas	tership disa	bled								
	master					Advanced				
O No CST i										

## **Configure the Ethernet Module**

Follow these steps to configure Ethernet communication for your HMI terminal, PowerFlex drive, Kinetix 300, Kinetix 5500, and Kinetix 6500 servo drives.

By Category

By Vendor

- 1. Expand I/O Configuration in the Controller Organizer.
- 2. Right-click I/O Configuration and choose New Module.

The Select Module dialog box opens.

**3.** Expand the Communications category and select your 1756 Ethernet module.

For systems using Integrated Motion on the EtherNet/IP network, 1756-EN2*x* or 1756-EN3*x* module are required.

In this example, the 1756-EN2TR module is selected.

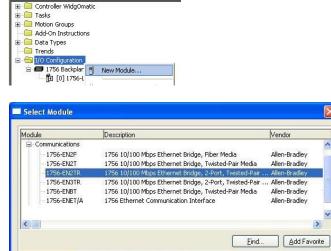
4. Click OK.

The New Module dialog box opens.

- 5. Configure the new module.
  - a. Type the module Name.
  - b. Enter the Logix5000 EtherNet/IP module slot (leftmost slot = 0).
  - c. Select an Ethernet Address option. In this example, the Private Network address is selected.
  - d. Enter the address of your EtherNet/IP module.

In this example, the last octet of the address is 10.

6. Click Change in the Module Definition area.



Favorites

OK

Cancel

Help

General*	Connection	Time Sync	Module Info	Internet Protocol	Port Configuration	Network	RSNetWorx	
Type: Vendor: Parent: Na <u>m</u> e: Descri <u>p</u> tior	Allen- Local S01_	Bradley	; 10/100 Mbps	Ethernet Bridge, 2	Port, Twisted-Pair M Ethernet Address Prjivate Netw IP Address: Host Name:	•	192.168.1. 10	]
Connecti	c Keying:	None	patible Module s	Change	Sl <u>o</u> t	1		

The Module Definition dialog box opens.

7. From the Time Sync Connection pull-down menu, choose Time Sync and Motion.

<u>R</u> evision:	3 🗸 1 🗘				
Electronic Keying:	Compatible Module				
Connection:	None	~			
Time Sync Connection:	Time Sync and Motion	~			

These changes will cause module data types and properties to change. Data will be set to default values unless it can be recovered from the existing module prope Verify module properties before Applying changes.

No

Yes

**IMPORTANT** Time Sync functionality is what enables motion control on an Ethernet network. Without this setting, you won't be able to run your motion application.

RSLogix !

1

🗄 🧰 Tasks

Motion Groups
 Add-On Instructions
 Data Types
 Trends
 I/O Configuration
 I/O So Backplane, 1756-A7

9- Ø 🛛

Change module definition?

🗓 [0] 1756-L63 WidgOmati

1] 1756-EN2TR 501\_EN2TI

Controller WidgOmatic

- **8.** Click OK to close the Module Definition dialog box.
- **9.** Click Yes when prompted to confirm your module definition changes.
- 10. Click OK to close the New Module dialog box.

Your new module appears under the I/O Configuration folder in the Controller Organizer.

## **Configure the Sercos Module**

Follow these steps to configure sercos communication,

for Kinetix 6200, Kinetix 6000, Kinetix 6000M, Kinetix 2000, Kinetix 7000, or Ultra3000 sercos drives used in your application.

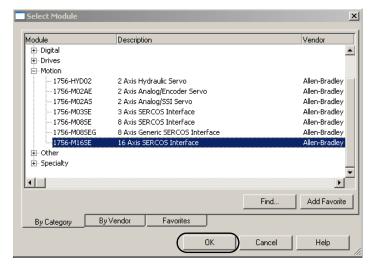
1. Right-click I/O Configuration in the Controller Organizer and choose New Module.

The Select Module dialog box opens.

2. Expand the Motion category and select 1756-MxxSE or 1768-M04SE as appropriate for your actual hardware configuration.

In this example, the 1756-M16SE module is selected.

3. Click OK.



The New Module dialog box opens.

- **4.** Configure the new module.
  - a. Type the module Name.
  - b. Enter the Logix5000 sercos module slot (leftmost slot = 0).
  - c. Check Open Module Properties.
- 5. Click OK.

Your new module appears under the I/O Configuration folder in the Controller Organizer.

**6.** Click the SERCOS Interface tab and reference the Sercos Data Rate table.

New Module									
Type: Vendor: Na <u>m</u> e: Description: <u>R</u> evision:	1756-M16SE 1 Allen-Bradley S02_M16SE	6 Axis SERCOS		il <u>o</u> t: 2 .eying: C	Compatible Kr	aying	~		
🕑 Open Mod	ule Properties		(			Cancel	Hel		
	n Instructions ypes	WidgOmatic 'R S01_EN2TR 5E S02_M16SE							
Module	Properties	s: Local:1 (	1756-M1	6SE )					
Data Rat Cycle Tin Transmit	e: [ ne: [ Power: [	SERCOS Inte Auto Detect 2 High 4	rface SEI	RCOS Int	erface Info	Modu	lle Info   Bacl	kplane	
Status: Offli									

#### Sercos Data Rate

Logix5000 Sercos Module	Number of Axes	Data Rate
1756-M03SE	Up to 3	
1756-M08SE	Up to 8	4 or 8 Mbps
1756-M16SE	Up to 16	
1768-M04SE	Up to 4	

7. From the Data Rate pull-down menu, match the DIP switch setting on the drive module or choose Auto Detect.

8. From the Cycle Time pull-down menu, choose the Cycle Time according to this table.

#### Sercos Cycle Time

Data Rate	Number of Axes	Cycle Time		
4 Mbps	Up to 2	0.5 ms		
	Up to 4	1 ms		
	Up to 8	2 ms		
	No support for axes 916			
	Up to 4	0.5 ms		
8 Mbps	Up to 8	1 ms		
	Up to 16	2 ms		

**TIP** The number of axes/module is limited to the number of axes as shown in <u>step 6</u>.

- 9. From the Transmit Power pull-down menu, match the DIP switch setting on the drive module.
- 10. Enter the Transition to Phase setting.

The Transition to Phase default setting is 4 (phase 4). The Transition to Phase setting stops the ring in the phase specified.

11. Click OK to close the Modules Properties dialog box.

### Save the Project File

When you configured the ControlLogix controller you named your (.acd) application file. In this example, the file name is WidgOmatic. Before closing the Logix Designer application, save your file.

Click 🔳 to save your Logix Designer application file.

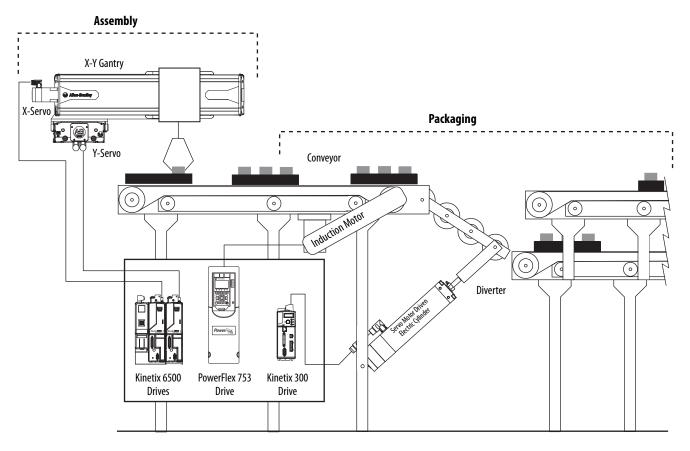


# **Device Configuration**

In this section you configure your Drives and Motion hardware by using the Logix Designer application and MotionView OnBoard software.

To assist you in device configuration, the Widg-O-matic machine application example is referenced in the device configuration steps. Two servo drives are configured for the X-Y gantry assembly section, one PowerFlex drive is configured for the conveyor, and one Kinetix 300 drive is configured for the packaging diverter.

#### Widg-O-matic Machine Application Example



# **PowerFlex Drive Configuration**

PowerFlex drive configuration applies to all 4-class and 7-class drives and includes these procedures:

- Update PowerFlex Add-On Profiles
- PowerFlex 525 Add-On Profiles
- Add and Configure PowerFlex Drives
- Set PowerFlex Drive Parameters
- Download Drive Parameters

### Update PowerFlex Add-On Profiles

**IMPORTANT** The PowerFlex Add-On Profiles are independent of RSLogix 5000 software or Logix Designer application releases. Update your PowerFlex Add-On Profiles to make sure your application runs correctly.

Add-On profiles (AOP) are available for download at the Custom Downloads Add-On Profiles website: <u>https://download.rockwellautomation.com/esd/download.aspx?downloadid=addonprofiles</u>

Follow these steps to download PowerFlex Add-On profiles.

1. Login to the Custom Download Add-On Profiles website.

The Custom Download Files dialog box opens.

Products & Technologies >	So	olutions & Services  News 8	& Innovation ►	Training	& Events 🕨	Sales & Pa	rtners ⊧ S	upport ▶ About Us ▶			
Rockwell Software	Custom Download Files The following items are available for download with this Download ID only.										
Support Center		Description	Download Code	Version	Release Date	Release Notes	Download Size	Comments			
KnowledgeBase Software Patches		AOP for RA E1 Plus		1.01.00	2012/08/20		27.86 MB	15.00.00 - Minimum RSLogix 5000 Software Revision			
FAQ		AOP for RA E3 Plus via 2100-ENET		1.01.02	2012/08/20	•	70.77 MB	17.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for E3 Plus 193-DNETCAT(R)		1.01.04	2012/08/20	1	27.85 MB	17.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for Drives-PowerFlex/SCANport		4.04.01	2012/09/05		247 MB	16.00.00 - Minimum RSLogio 5000 Software Revision			
		AOP for RA1769Analog		8.04.00	2012/09/12	1	73.42 MB	13.04.00 - Minimum RSLogix 5000 Software Revision			
		AOP for 1788-CN2FFR		1.01.16	2012/10/25	1	78.86 MB	15.00.00 - Minimum RSLogio 5000 Software Revision			
		AOP for 1788-EN2FFR		1.01.16	2012/10/25		78.81 MB	15.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for 1788-CN2PAR		2.01.01	2012/10/25	1	76.8 MB	16.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for 1788-EN2PAR		2.01.01	2012/10/25	1	76.8 MB	16.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for 1769-ASCII		2.04.02	2012/10/25	<b>B</b>	74.35 MB	16.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for FANUC Robotics		1.90.00	2012/10/25	<b>D</b>	30.47 MB	15.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for Fanue CNC		1.90.00	2012/10/25	<b>B</b>	30.51 MB	15.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for PF755		11.01	2012/11/07	<b>B</b>	1.45 MB	16.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for 1783 Stratix 5700/8000/8300 Swit		6.02.15	2012/11/15		35.64 MB	16.00.00 - Minimum RSLogix 5000 Software Revision			
		AOP for CLX High Performance I/O		3.01.01	2013/01/14	1	72.62 MB	18.00.00 - Minimum RSLogix 5000 Software Revision			

Total Download Size = 0 B Download Now

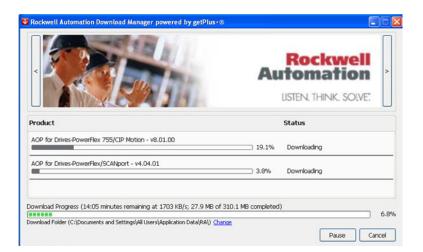
2. Check the AOP for Drives-PowerFlex 755/CIP Motion profile and/or the AOP for Drives-PowerFlex/SCANport<sup>™</sup> profile, as required per your project.

3. Click Download Now and accept the user license agreement.

If prompted to install the Download Manager, allow the installation

			My Profile → Sign O	Dut
Rockwell Automation	LISTEN. THINK. SOLVE:		Internet Explorer - Security Warning Do you want to install this software?	de
Products & Technologies > Rockwell Software > Support Center > KnowledgeBase > Coffee Review	Solutions & Services News & Innovation     Download Manager Installation     Your download will automatically begin after the download     Depending on your security settings, you may end		Publisher: Rockwell Automation  More options  Install Don't Install  While files from the Internet can be useful, this file type can potentially harm	
<ul> <li>Software Patches</li> <li>FAQ</li> </ul>	STEP 1 Back • O • O O O O O O O O O O O O O O O O	STEP 2 Address Address Addres	ga, rockwellautomation.cc     Do you want to install this software?       ctivex Control     Froit       tion Bar Help     *         * More options	

4. Note the location of the download folder.



**5.** Extract the AOP zip file and run Setup.

### **PowerFlex 525 Add-On Profiles**

**IMPORTANT** The PowerFlex 525 Add-On Profiles are independent of the Custom Download AOP files. Update your PowerFlex Add-On Profiles to make sure your application runs correctly.

The PowerFlex 525 Add-On Profile is available for download at the Allen-Bradley Web Updates website: <u>http://www.ab.com/support/abdrives/webupdate/index.html</u>

Follow these steps to download PowerFlex 525 Add-On profile.

1. Go to the Allen-Bradley Web Updates website.

The Allen-Bradley Web Updates dialog box opens.

			Sign In → Become a Member
Rockw	eli On listen, think, solve:		Rockwell Automation Worldwide     Search
Automatic	UN LISTEN, THINK, SOLVE:		ocurri V
Products & Technolo	ogies 🕨 Solutions & Services 🕨 News & Inn	ovation ▶ Training & Events ▶ Sales & Partners ▶	Support > About Us >
Allen-Bradley  Drives & Motors  Home Motor Products	ALLEN-BRADLEY WEB UPDATE This site contains Flash Update Files, Product your Allen-Bradley brand drive products up to	Help Files, Control Bar Files, GSD Files, EDS File links, DriveTo	ols SP / Drive AOP Database Files, and other downloads to keep
Support     Manuals     General Resources		ed below, an ActiveX Control may download and install onto you te pages will not function. You must use Internet Explorer to vie	ew these pages. Note for
<ul> <li>A to Z Product Directory</li> <li>Configuration and Selection Tools</li> </ul>	Click here for help with this site.		Vista Users
<ul> <li>Knowledgebase</li> <li>Events Listing</li> <li>Locate Us</li> </ul>	*NEW	* - DriveTools SP Database Files	Download Page
Newsletters & Magazines     Product Certification     Product Cross Reference     Publications Library     Technical Support	PowerFlex 520-Series Drives • PowerFlex 525 PowerFlex 7.Class Drives (DPI) • <u>PowerFlex 70 C</u> • <u>PowerFlex 70 C</u> • PowerFlex 70 Standard Control	PowerFlex 750.Series Drives o PowerFlex 753 o PowerFlex 755 o PowerFlex 755 HiP	PowerFlex 4-Class Drives (DSI) o PowerFlex 4 o PowerFlex 4M o PowerFlex 40 o PowerFlex 40P o PowerFlex 400

**2.** Click PowerFlex 525.



- Click Add-On Profiles for RSLogix 5000/Studio 5000 are included in the Drives AOP> PowerFlex 525 AOP (v1.01) and follow the download instructions.
- 4. Extract the RA\_PF5ClassAOP\_Ver\_1.01 zip file and run the MPSetup file.

## **Add and Configure PowerFlex Drives**

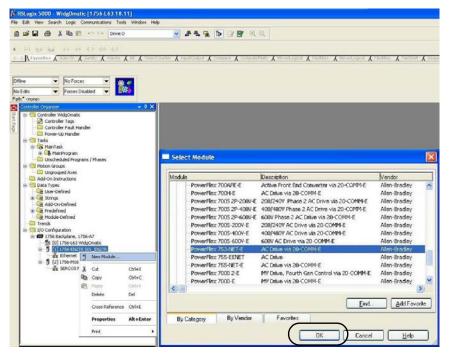
Follow these steps to add and configure each individual drive you intend to have in your system. For the Widg-O-matic machine application example, you configure a PowerFlex 753 drive.

- 1. Open your Logix Designer project file created in the previous section (for the Widgomatic example, the project file name was Widgomatic.acd).
- 2. Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.
- 3. Right-click the network communication module for your PowerFlex drive and select New Module.

For the Widg-O-matic example, the 1756-EN2TR module is selected.

The Select Module dialog box opens.

**4.** Expand the Drives category and select the appropriate PowerFlex drive module.



For the Widg-O-matic example, the PowerFlex 753 drive is selected for the conveyor drive.

5. Click OK.

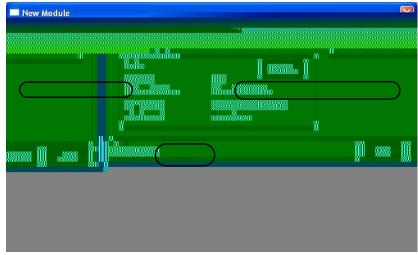
The New Module dialog box opens.

- 6. Configure the new module.
  - a. Type the module Name.
  - b. Select an Ethernet Address option.

In this example, the Private Network address is selected.

7. In the Module Definition field click Change.

The Module Definition dialog box opens.



8. Configure module definitions.

The Module Definition dialog box lets you configure and access drive data beyond standard I/O. Four examples are shown.

- a. Enter major and minor revisions appropriate for your drive hardware.
- b. Enter drive rating appropriate for your drive hardware and AC input voltage.
- c. Set datalink definitions for the intended drive.

**IMPORTANT** The datalinks listed for their respective drives must be configured exactly as shown for successful faceplate AOI import and operation. If additional datalinks are required for your application, modifications to the corresponding AOIs may be required.

### d. Check Use Network Reference.

IMPORTANT Use Network Reference must be checked to automatically set the speed reference, DPI™, and start source parameters to the Ethernet port.
 To configure the PowerFlex 525 drive to accept commands and report status via an Ethernet network, set P046 - [Start Source 1] and P047 - [Speed Reference 1] to EtherNet/IP.

General Connection Module I	Drive					
PowerFlex 525					Disconnect	ted
Download Upload Comp	-	ters roperties Wizards			2 Manual	•
C Alkedrater	arameters Parameters					
	Group: All Parameter	s v	bw Defaults	e:		é
	#	Name	Value	Units	Internal Value	Default
	35	Motor NP Poles	4		4	4
	36	Motor NP RPM	1600	RPM	1600	1750
	37	Motor NP Power	0.03	kW	3	0.40
	39	Torque Perf Mode	SVC	-	1	SVC
PowerFlex Moto	40	Autotune	Ready/Idle	-	0	Ready/Idl
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	41	Accel Time 1	3.00	Sec	300	10.00
	42	Decel Time 1	3.00	Sec	300	10.00
1P 110V .50HP	43	Minimum Freq	0.00	Hz	0	0.00
0 - PowerFlex 525 add+	44	Maximum Freq	60.00	Hz	6000	60.00
0 - PowerFlex 525 add+	45	Stop Mode	Ramp, CF	-	0	Ramp, CF
Status: Offline	46	Start Source 1	EtherNet/IP	-	5	Keypad
Nation of the local sector	47	Speed Reference1	EtherNet/IP	-/	15	Drive Pot
		opcourristerent of		NAME AND ADDRESS OF		and the second se

e. Click OK to close the Module Definition dialog box.

This Module Definition example applies to PowerFlex 750 Series drive datalinks and specifically shows the PowerFlex 753 module definitions for the Widg-O-matic machine example.

Revision:	2 • 3	✓ Input Data		Output Data	٦.
	2 • 3	DriveStatus		LogicCommand	
Electronic Keying:	Compatible Module	Feedback		Reference	
			(	Use Network Reference	
Drive Rating:	480V 27 (ND) 22 (HD)	AccelTime1		AccelTime1	
Rating Options:	Normal Duty	DecelTime1		DecelTime1	
That ing options.	(Normal Dady	LastFaultCode			•••
Special Types:	Standard	DCBusVolts			•••
		OutputCurrent	•••		•••
Selected Rating:	480V 27A	OutputPower			~
-	20GD027				•••
Selected Catalog:	2060027		•••		•••
					··· .
		when improper	ly using soft	azardous motion of machinery ma ware to configure a drive. for the Input and Output Data aj	-
Connection:	Parameters via Datalinks	member names	s in the drive	Module-Defined Data Types an	d defi
Data Format:	Parameters	necessary Dat	alink narame	eters in the RSLogix 5000 project	t Act

This Module Definition example applies to PowerFlex 70, PowerFlex 70EC, and PowerFlex 700 datalinks.

Module Definition <sup>*</sup>							×
(Revision:	2 💉 9	~	Patalink	Input Data		Output Data	
	Compatible Module		1	DriveStatus		DriveLogicRstt	
Electronic <u>K</u> eying:	Compatible Module	× 1		OutputFreq		CommandedFreq	5
Drive Rating:	240V 4.2A	~	-			Use Network Reference	$\mathcal{D}$
Convertidung.	2407 4.24		A	AccelTime1 - 140	~	AccelTime1 - 140	
		- (		DecelTime1 - 142	~	DecelTime1 - 142 💉	1
			<b>∨</b> B	Fault1Code - 243	~	Undefined_B1 🛛 👱	
				DCBusVoltage - 12	~	Undefined_B2	
		<u> </u>	СC	OutputCurrent - 3	~	Undefined_C1 🛛 🔽	1
				Undefined_C2	~	Undefined_C2	/
Connection:	Parameters via Datalinks	~				5	
Data Format:	Parameters						
Data Format.	r arameters			Sort Input/Output s	selectio	n lists by Parameter Name	
			- <u>-</u> •	hen improperly using soft	tware to d for the	us motion of machinery may occ o configure a drive. e Input and Output Data appear le-Defined Data Tvoes and defi	as
			n d	ecessary Datalink param	eters in	the RSLogix 5000 project. Actu and drive is determined by Datali	al
Create Database	Web Update		с		nunicati	n to the drive to ensure that the on module configurations are	
Match Drive				ОК		Cancel Help	]

Revision:	2 💙 8	~ )r	Datalink	Input Data		Output Data
	Come stible Madule			LogicStatus		LogicCommand
Electronic <u>K</u> eying:	Compatible Module			SpeedFeedback		SpeedReference
Drive Rating:	240V 4.2A	-	_			Use Network Reference
onronidang.	2401 4.26		A	AccelTime - 32		AccelTime - 32
				DecelTime - 33	-	DecelTime - 33 🛛 🗾
			<b>9</b> 8	DCBusVoltage - 306		Undefined_B1
				OutputCurrent - 308	~	Undefined_B2
		E	_c		-	
						3
		l			_	3
Connection:	Parameters via Datalinks	-				<u>j</u> j
Data Format:	Parameters					
		0	Y P m n	hen improperly using softwa arameter names selected fo ember names in the drive M ecessary Datalink paramete	are to Ir the Iodul Irs in	is motion of machinery may occu configure a drive. Input and Output Data appear a e-Defined Data Types and defin the RSLogix 5000 project. Actu nd drive is determined by Datalir

This Module Definition example applies to PowerFlex 700S 2P datalinks.

**IMPORTANT** The PowerFlex 4-class drives do not support datalinks. Therefore, the corresponding PowerFlex 4 faceplates do not require datalink configuration.

This Module Definition example applies to the PowerFlex 4-class drives.

Module Definition*			×
(Revision:	6 🔽 1 💌	Input Data	Output Data
Electronic <u>K</u> eying:	Compatible Module	DriveStatus	LogicCommand
Drive Rating:	3P 230V .25HP 🛛 🗸	OutputFreq	FreqCommand
Create Database	Web Update		
Match Drive			ancel Help

**IMPORTANT** For PowerFlex 4-class drive configuration, in addition to checking Use Network Reference, you must also check Use Network Start to control the drive from the Ethernet network port.

Drive Rating	Input Data	Output Data
1P 110V .50HP •	DriveStatus	LogicCommand Network Start Is Used
Revision	OutputFreq	FreqCommand Network Reference Is Used
	Output Current 🔹	Disabled 🔹
Electronic Keying	Disabled •	Disabled 👻
Compatible Module 🗸	Disabled -	Disabled 🔹
	Disabled -	Disabled 🔹
	A DANGER: Unexpected bazardous	motion of machinery may occur
If the revision of your drive is not listed: - click Create Database button below if drive is online. - click Veb Update to download the database from the web if drive is offline. Create Database	DANGER: Unexpected hazardous improperly using software to confi Parameter names selected for the member names in the drive Modu necessary Datalink parameters in transfer between controller and dr You must download configuration drive and communication module other.	gure a drive. Input and Output Data appear as e-Defined Data Types and define the RSLogix 5000 project. Actua ive is determined by Datalink par- to the drive to ensure that the co

This Module Definition example applies to the PowerFlex 525 EENET drives.

IMPORTANT The PowerFlex 525 drive supports up to four (4) datalinks IN and OUT, but is not required for the PowerFlex 525 faceplate functionality. The Output Current datalink is used to provide a reference/placeholder in the logic of the device module to scale datalink values accordingly.

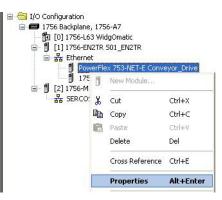
9. Click OK to close the New Module dialog box.

New Module		1	
		<b>)</b> 🕅 🕅	

### **Set PowerFlex Drive Parameters**

PowerFlex drive parameter settings are specific to your application and should be reviewed carefully before running your drive application. In this procedure, you use the Startup Wizard to set the most commonly configured parameters.

1. Right click the PowerFlex drive under I/O Configuration and choose Properties.



For the Widg-O-matic example, the PowerFlex 753 drive is selected.

The Module Properties dialog box opens.



2. Click the Drive tab.

The Drive tab dialog box opens.

3. Click 🗯 (startup wizard).

The Startup Wizard provides access to commonly used parameter groups and helps you setup the drive for the connected motor.

The Available Wizards dialog box opens.

4. Select the Startup Wizard and Click Select.

For the Widg-O-matic machine application example, the PowerFlex 753 Startup Wizard was chosen.



5. Click Yes when the Wizard Launch Confirmation dialog box opens.

The Startup Wizard dialog box opens. These steps guide you through configuration of the most critical PowerFlex 753 parameter groups. Other PowerFlex drives may have fewer parameter groups.

6. Click Next to proceed through the Welcome, Reset Parameters and System Time wizard steps.



The Motor Control wizard step opens.

Vizard Step	Motor Control			
🚛 Welcome				
E Reset Parameters	Motor Control Mode O Indi			
E System Time	Motor Control Mode O Indi	uction Vol	ts / Hz	
E Motor Data	<ul> <li>Index</li> </ul>	uction Ser	nsorless Vector	
E Stop Mode		uction Flu	x Vector	
E Direction Test				
📰 AutoTune				
📰 Inertia AutoTune	Speed / Torque / Position Mode		Beg	
📰 Ramp Rates / Speed Limits	Speed / Torque / Toshort Mode		neg	
📰 Speed Reference	VHz Curve	Custon	nV/Hz 🛛 🛃	
E Torque Reference	Bi	in Boost	12.65	Volt
Start / Stop				
📰 Other Digital Inputs	Start / Acc	el Boost	12.65	Volt
Digital Output Port 0	Break	Voltage	57.5	Volt
🗉 Digital Output Port 0				
📰 Analog Output Port 0	Break Fre	quency	15	Hz
📰 Pending Changes	Max	Voltage	230	Volt
			L	
	Feedback			
	Primary Speed Feedback Port: 0	Param 0	Ipen Loop Fdbk	
				$\equiv$ /
	Position Feedback Port: 0	, Param S	imulator Fdbk	
				Cancel < Back Next> Fini

- 7. Select the appropriate Motor Control Mode and Feedback options for your application.
  - **TIP** If motor is unavailable at setup time, select Simulator Fdbk to use the internal simulation feedback capabilities of the drive.
- 8. Click Next.

The Motor Data wizard step opens.

Vizard Step	Motor Data		
E Welcome			
Reset Parameters	Power Units	HP	
📰 System Time	Fower Units		
E Motor Control	Motor NP Power	1	HP
E Motor Data			
E Stop Mode	Motor NP FLA	2.9	Amps
E Direction Test	Motor NP Volts	230	VAC
E AutoTune	11001111 1000		
📰 Inertia AutoTune	Motor NP Hertz	60	Hz
E Ramp Rates / Speed Limits	Motor NP BPM	1740	BPM
E Speed Reference	MOLOFINE HEM	1740	nrm
Torque Reference	Motor OL Factor	1	
E Position PTP Reference			
E Start / Stop	Motor Poles	4	Pole
E Other Digital Inputs			
E Digital Output Port 0			
E Digital Output Port 0			
E Analog Output Port 0			

- 9. Enter motor data values appropriate for your application.
- 10. Click Next to proceed through Stop Mode, Direction Test, AutoTune, and Inertia AutoTune wizard steps.

The Ramp Rates / Speed Limits wizard step opens.

Wizard Step	Ramp Rates / Speed Limits Max Forward Speed: Min Forward Speed: Min Reverse Speed: Max Reverse Speed:
E Digital Output Port 0 Analog Output Port 0 Pending Changes	Acceleration:     Deceleration:       Accel Time 1:     10     Secs       S-Curve:     0     %       Actual:     10.000000     Secs       Secure:     0     %       Actual:     10.000000     Secs       Direction Mode:     Unipolar

- **11.** Enter the Max/Min Forward Speed, Max/Min Reverse Speed, and Acceleration/Deceleration parameters as appropriate for your application.
- 12. Click Next.

The Speed Reference wizard step opens.

**13.** Set the Speed Reference parameters appropriate for your application and drive hardware.

Vizard Step ✔☷ Welcome	Speed Reference
<ul> <li>✓ ■ Reset Parameters</li> <li>✓ ■ System Time</li> <li>✓ ■ Motor Control</li> <li>✓ ■ Motor Data</li> <li>✓ ■ Stop Mode</li> </ul>	Speed Units Hz  Speed Reference Port: 0, Param Port 6 Reference
✓ E Direction Test ✓ E AutoTune ✓ E Inertia AutoTune ✓ E Ramp Rates / Speed Limits	
	Reference Port: 6 - 20-COMM-E
Other Digital Inputs     Digital Output Port 0     Digital Output Port 0     Digital Output Port 0	
<ul> <li>Analog Output Port 0</li> <li>Pending Changes</li> </ul>	

- **TIP** The drive speed reference parameter is automatically set when Use Network Reference is checked in the Module Definition dialog box. Refer to <u>step 8</u> on <u>page 304</u>.
- 14. Continue to Click Next until you reach the Applied and Pending Changes wizard step.

All applied and pending changes are listed.

- 15. Click 🗁 to print your list of changes.
- 16. Click Finish to accept the changes.

Wizard Step	Applied and Pending Changes	
	Below is a list of changes that have already been made.  Wizard Step "Direction Test" Direction Test was not completed.	
✓ III Pending Changes	Below is a list of changes that will be made if you click Finish.	
	Wizard Step "Motor Control" Change parameter "125 - [Pri Vel Fdbk Sel]" value from "138" to "137".	× ×

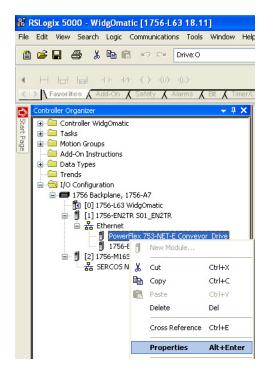
- 17. Click OK in the Module Properties dialog box to save the drive configuration.
- 18. Click 🔳 to save your Logix Designer application file.

👫 RSLogi	x 500	0 - W	idg0m	atic [1756-L6]	3 18.1	1]*
File Edit \	/iew S	Search	Logic	Communications	Tools	Win
	De	) <u>%</u>				
Offline			RUN			
No Forces		▶ <b>.</b> [	OK		P	
No Edits		2	BAT			
Redundancy		₿.Ŭ	- 170		٥	

### **Download Drive Parameters**

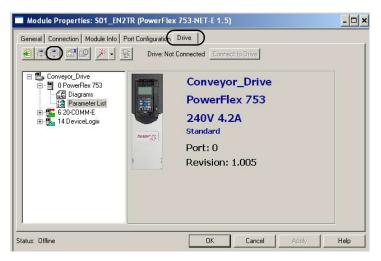
**IMPORTANT** Before downloading drive parameters, you must configure personal computer communication properties and EtherNet/IP driver. Refer to <u>Appendix D</u> on <u>page 257</u> for more information.

1. Expand the I/O Configuration folder in the Controller Organizer.



2. Right-click your PowerFlex drive and select Properties.

The Module Properties dialog box opens.



3. On the Drive tab, click the Download Parameter icon.

This Drive tab applies to the PowerFlex 525 drives.

PowerFlex 525	Disconnecto
Download pload Compare Parameters Properties Wizards	3 Manual
PowerFight	
1P 110V .50HP 0-PowerRex 525 add+	

The Connect To Drive dialog box opens.

- **4.** Expand the Ethernet communication tree and select the desired PowerFlex drive.
- 5. Click OK.

Multiple data download status dialog boxes open. Download may take several minutes.

Workstation, USMKEJWNOVAK4	Address	Device Type	Online Name	Status
문 옮 Linx Gateways, Ethernet - 杰 AB_ETHIP-1, Ethernet - 명 192.168.1.21, PowerFlex 753, PowerFlex 753		PowerFlex 753	PowerFlex 753	OK

The I/O Configuration Differences dialog box opens.

Dr	ive: AB_	ETHIP-1\192.168.1.21			
Da	atalink		Input Data		Output Data
Project	Drive	Project	Drive	Project	Drive
		DriveStatus	DriveStatus	LogicCommand	LogicCommand
		Feedback	Feedback	Reference	Reference
<b>7</b> A	R A	AccelTime1 - 535	Undefined_A1	AccelTime1 - 535	Undefined_A1
		DecelTime1 - 537	Undefined_A2	DecelTime1 - 537	Undefined_A2
<b>7</b> 8	<b>₽</b> B	LastFaultCode - 951	Undefined_B1	Undefined_B1	Undefined_B1
		DCBusVolts - 11	Undefined_B2	Undefined_B2	Undefined_B2
<b>⊽</b> C	R C	OutputCurrent - 7	Undefined_C1	Undefined_C1	Undefined_C1
		Undefined_C2	Undefined_C2	Undefined_C2	Undefined_C2
D	L D	Undefined_D1	Undefined_D1	Undefined_D1	Undefined_D1
		Undefined_D2	Undefined_D2	Undefined_D2	Undefined_D2

This I/O configuration dialog box applies to all PowerFlex drives (except PowerFlex 525).

This I/O configuration dialog box applies to the PowerFlex 525 drives.

To Configure	Go To
PowerFlex 525 drives	<u>step a</u>
All other PowerFlex drives	<u>step 6</u>

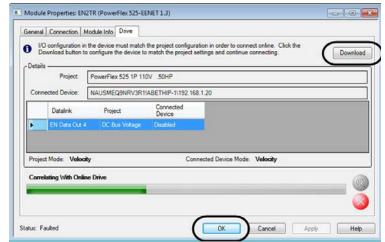
- a. Click Download.
- b. Click OK.
- c. Click OK to close the Module Properties dialog box.
- d. Skip to <u>step 11</u>.
- 6. Click Use Project.
- 7. Click Continue.

The Select Devices To Download dialog box opens.

Project devices that are different than the target drive devices are checked automatically.

- 8. Click Download.
- 9. Click Continue.

- 10. Click OK to close the Module Properties dialog box.
- **11.** Click 🔳 to save your Logix Designer application file.







File Edit Viev	/ Search	Logic	Communications	Tools	Win
	) 🛃 👗				
Offline		🗏 RUN			
No Forces	▶_			9	
No Edits	2				
Redundancy	5.0	- 1/0		٥	

# **CIP Motion Drive Configuration**

CIP Motion drive configuration applies to all Kinetix 6500 drive modules, Kinetix 5500 drives, Kinetix 350 drives, PowerFlex 527, and PowerFlex 755 CIP Motion drives. These procedures are included:

- Configure CIP Motion Drive Modules
- Configure the Motion Group
- Configure Axis Properties

These CIP motion drive configuration steps were written specifically for Kinetix 6500 drives. The Kinetix 5500, Kinetix 350, PowerFlex 527, and PowerFlex 755 CIP Motion drive configuration steps are similar. Examples for each drive family are given when significant differences exist.

For more information on drive configuration, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

## **Configure CIP Motion Drive Modules**

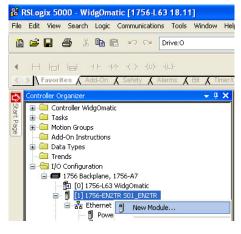
#### **Required Configuration Software**

Drive Family	Drive Cat. No.	Configuration Software	Version
Kinetix 6500	2094-EN02D-M01-Sx, 2094-BCxx-Mxx-M, and 2094-BMxx-M	RSLogix 5000	18 or later
KIIIEUX 0500	2094-EN02D-IND 1-5x, 2094-DCXx-INXx-IN, allu 2094-DINXx-IN	Logix Designer application	21 or later
Kinetix 5500	2198-H <i>xxx</i> -ERS	Logix Designer application	21 or later
Kinetix 350	2097-V3xPRx-LM	RSLogix 5000	20 or later
KIIIEUX 550	2097-V3XPKX-LIVI	Logix Designer application	21 or later
PowerFlex 755	CIP Motion drives	RSLogix 5000	19 or later
rowerriex 755		Logix Designer application	21 or later
PowerFlex 527	25C-xN1x4	Logix Designer application	24 or later

Follow these steps to configure the CIP Motion drive modules.

- 1. Open your Logix Designer project file created in <u>Appendix F</u>.
- **2.** Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.
- **3.** Right-click the network communication module for your CIP Motion drive and choose New Module.

For the Widg-O-matic example, the 1756-EN2TR module is selected.



The Select Module dialog box opens.

		Description	ı		
Hotion 2094-EN02D-M01-S0 2094-EN02D-M01-S1 PowerFlex 755-EENET-CM PowerFlex 755-EENET-CM-S PowerFlex 755-EENET-CM-S1 PowerFlex 755-HIPwr-EENET-CM-S PowerFlex 755-HIPwr-EENET-CM-S PowerFlex 755-HIPwr-EENET-CM-S1		Kinetix 650 PowerFlex PowerFlex PowerFlex M PowerFlex M-S PowerFlex	755 AC Drive via Embe 755 AC Drive via Embe 755 High Power AC Dri 755 High Power AC Dri	ion/Safe Torque-Of ion/Safe Speed Moi et - CIP Motion et - CIP Motion/Saf	nitor e Torque-Off
				<u>F</u> ind	Add Favorib

4. Expand the Motion category and select your CIP Motion module as appropriate for your actual hardware configuration.

For the Widg-O-matic example, the 2094-EN02D-M01-S1 control module is selected for both axes of the X-Y Gantry.

5. Click OK.

The New Module dialog box opens.

- 6. Configure the new control module.
  - a. Type the module Name.
  - b. Select an Ethernet Address option.In this example, the Private

Network address is selected.

c. Enter the address of your EtherNet/IP module.

New Module	
General*       Connection       Time Sync       Module Info       Internet Protocol         Type:       2094-EN02D-M01-S1 Kinetix 6500 Single Axis Ethem         Vendor:       Alen-Bradley         Parent:       S01_EN2TR         Name:       Gantry_X_Drive         Description:	Port Configuration Network Associated Axes Power Di
Power Structure: <none></none>	OK Cancel Help

For the Widg-O-matic application example, the last octet of the IP address is given in this table. The value you enter here must match the base node address of the Kinetix 6500 IAM power module,

#### Widg-O-matic X-Y Gantry Ethernet Address Configuration

Module Name	Ethernet IP Address
Gantry_X_Drive	191.168.1.31
Gantry_Y_Drive	191.168.1.32

7. Click Change in the Module Definition area.

The Module Definition dialog box opens.

**8.** From the Power Structure pull-down menu, choose the power module appropriate for your application.

Widg-O-matic X-Y Gantry Power Module Configuration

Module Name	Power Module Type	Power Structure Cat. No.
Gantry_X_Drive	IAM	2094-BC01-M01-M
Gantry_Y_Drive	AM	2094-BMP5-M

<u>R</u> evision:	1 💌 1‡	
Electronic <u>K</u> eying:	Compatible Module	~
<u>C</u> onnection:	Motion	~
<u>P</u> ower Structure:	2094-BC01-M01-M	~
Verify Power Rating	Cancel Help	۲ ۲

**IMPORTANT** For PowerFlex 755 CIP Motion drives, you must also choose the motor feedback device. Refer to your PowerFlex 755 user manual, publication <u>750-UM001</u>, for more information.

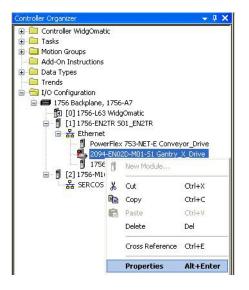
- 9. Click OK to close the Module Definition dialog box.
- 10. Click Yes when prompted to confirm your module definition changes.

SLogix !	5000	×
	These changes will cause module data types and properties to change.	
-	Data will be set to default values unless it can be recovered from the existing module properties.	
	Changing the Major Revision or Power Structure will cause any axis associations with the module to be removed.	
	Removing the axis association with the module will reset the Associated Module, Motor Device, and Feedback Device configuration for the axis tag.	
	Verify module properties before Applying changes.	
	Change module definition?	
	Yes No	

11. Click OK to close the New Module dialog box and save the configuration.

The new CIP Motion drive module appears under the EtherNet/IP module in the I/O Configuration folder.

12. Right-click the new CIP Motion module you just created and choose Properties.



The Module Properties dialog box opens.

General* Connection Time Sync M	odule Info Internet Protocol	Port Configuration Network Associated Axes Power Di
Axis <u>1</u> :	<none></none>	New A <u>x</u> is
Motor/Master Feedback Device:	Motor Feedback Port	
L <u>o</u> ad Feedback Device:	<none></none>	×
Axis <u>2</u> (Auxiliary Axis):	<none></none>	New Axis
Master Feedback Device:	<none></none>	~

- 13. Click the Associated Axes tab.
- 14. Click New Axis.

The New Tag dialog box opens.

- 15. Create the axis tag.
  - a. Type the axis Name.
  - b. Accept the Type, Data Type, Scope, and External Access default values.
  - c. Click OK.

The New Tag dialog box closes.

The new axis is assigned as Axis 1.

#### Widg-O-matic X-Y Gantry Axis Assignments

Axis	Axis Name	Digital Input 1	Digital Input 2
1	Gantry_X_Axis	Enable	Home
2	Gantry_Y_Axis	Enable	Home

New Tag		
<u>N</u> ame:	Gantry_X_Axis	ОК
Description:		Cancel
		Help
	×	
<u>U</u> sage:	<normal></normal>	
Тур <u>е</u> :	Base Connection	
Alias <u>F</u> or:	~	
Data <u>T</u> ype:	AXIS_CIP_DRIVE	
<u>S</u> cope:	🔁 WidgOmatic 🛛 👻	
E <u>x</u> ternal Access:	Read/Write	
Style:	×	
Constant		
Dpen AXI	S_CIP_DRIVE Configuration	

**16.** Click Apply.

ieneral Connection Time Sync Mo	dule Info Internet Protocol	Port Configuration	Network Asso	ciated Axes*	Power Di
Axis 1:	Gantry_X_Axis	<b>~</b>	New Axis	)	
Motor/Master Feedback Device:	Motor Feedback Port				
Load Feedback Device:	<none></none>	~			
Axis 2 (Auxiliary Axis):	<none></none>		New Axis	]	
Master Feedback Device:	<none></none>	~			

This assigns the associated axes to the control module.

**IMPORTANT** For PowerFlex 755 CIP Motion drives, you must configure the motor feedback device. Refer to your PowerFlex 755 user manual, publication <u>750-UM001</u>, for more information.

17. Click the Digital Input tab.

Module Prop	erties: SO1_EN2TR (2	094-EN02D-M0	1-51 1.1	)			
Time Sync Modu	ule Info Internet Protocol	Port Configuration	Network	Associated Axes	Powe	Digital Input*	Notion Diag 🔹 🕨
Digital Input 1:	Enable	~					
Digital Input 2:	Home	~					
Digital Input 3:	Unassigned	~					
Digital Input 4:	Unassigned	~					
Status: Offline				ОК	Cancel	Apply	

The digital inputs (1...4) are assigned default values.

You can reassign them, using the pull-down menus, according to the needs of your application. You can also unassign digital inputs, if your application does not use them or you want to remove the default assignments.

For the Widg-O-matic machine example, digital inputs 1 and 2 are assigned Enable and Home (respectively) and digital inputs 3 and 4 are unassigned.

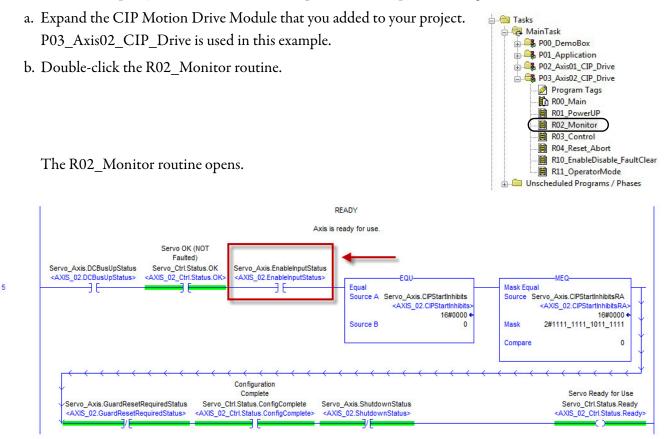
Widg-O-matic X-Y Gantry Digital Input Assignments

Axis	Axis Name	Digital Input 1	Digital Input 2
1	Gantry_X_Axis	Enable <sup>(1)</sup>	Home
2	Gantry_Y_Axis	Enable	Home

(1) When using the Enable digital input, you can add a check in the device module code to make sure it is on before running your machine. Refer to the steps below to see how.

**IMPORTANT** PowerFlex 755 CIP Motion drives support only one digital input. Refer to your PowerFlex 755 user manual, publication <u>750-UM001</u>, for more information.

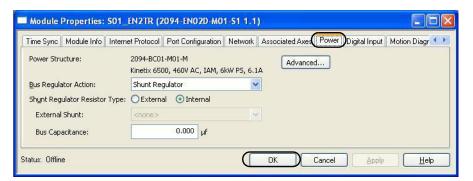
Follow these steps if your CIP Motion drive requires Enable Input Checking.



- c. Add an XIC (Examine On) instruction to Rung 5 and assign tag Servo\_Axis.EnableInputStatus to it.
- d. Save and close the R02\_Monitor routine.

The Module Properties dialog box re-appears.

- 18. Click Apply.
- **19.** Click the Power tab.



The Widg-O-matic machine example uses the default values for the IAM power module as shown. If your application requires additional shunt configuration, refer to <u>step 20</u>. If not, skip to <u>step 22</u>.

**20.** From the Bus Regulator Action pull-down menu, choose the shunt option appropriate for your actual hardware configuration.

Choose	То
Disable	Disable the shunt resistor internal to the IAM power module.
Shunt Regulator	Choose an internal or external shunt option.
Common Bus Follower <sup>(1)</sup>	To configure your IAM power module as a common-bus follower IAM module.

(1) Drive will not accept CommonBus Follower selection if three-phase power or DC bus power is applied.

lf You Choose	Then
Churt	Select Internal to use the shunt resistor internal to the IAM power module.
Shunt Regulator	Select External to use the External Shunt pull-down menu and choose between the Bulletin 1394 shunt modules and the Bulletin 2094-BSP2 shunt module. <sup>(1)</sup>

(1) Drive will not accept Internal, 2094-BSP2, or 1394-SRxxxx selection if DC bus voltage is present without having three-phase power applied.

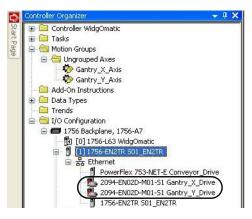
**21.** Calculate additional bus capacitance, if this applies to your application, and enter the value here (version 18.00 or later).

The Additional Bus Capacitance field only applies to the IAM power module.

IMPORTANT DC common-bus applications must calculate Total Bus Capacitance and Additional Bus Capacitance and set the Add Bus Cap parameter in the leader IAM power module. Refer to the Kinetix 6200 and Kinetix 6500 Modular Multi-axis Servo Drives User Manual, publication 2094-UM002 for more information on making the calculations.

### **22.** Click OK.

23. Repeat step 2 through step 18 and step 22 for the each additional 2094-EN02D-M01-Sx control module.



When your CIP Motion drive configuration is complete, all of the drive modules should appear in the I/O Configuration folder under your Ethernet module.

For the Widg-O-matic machine example, the X-Y gantry configuration appears as shown.

## **Configure the Motion Group**

Follow these steps to configure the motion group.

1. Right-click Motion Groups in the Controller Organizer and choose New Motion Group.

The New Tag dialog box opens.

- **2.** Type the new motion group Name.
- 3. Click OK.

The new motion group appears under the Motion Groups folder.

4. Right-click the new motion group in the Controller Organizer and choose Properties.

The Motion Group Properties dialog box opens.

- 5. Click the Axis Assignment tab and move your axes (created earlier) from Unassigned to Assigned.
- 6. Click the Attribute tab and edit the default values as appropriate for your application.
- 7. Click OK.

The assigned axes appear under the new Motion Group.

🕀 🧰 Control	ler WidgOmatic		
	Ckonpe		
	New Motion Group		
V	Cut Ctrl+X		
- ×	Cut Cut+x		
New Tag			
Name:	MotionGroup		
Description:		Cancel	
		Help	
<u>U</u> sage:	<normal></normal>		
Тур <u>е</u> :	Base Conne	ection	
Alias <u>F</u> or:		×	
Data <u>T</u> ype:	MOTION_GROUP		
Scope:	VidgOmatic	<b>*</b>	
E <u>x</u> ternal Access:	Read/Write	*	
Style:		~	
Constant			
Dpen MOT	ION_GROUP Configuration		
	ontroller Organizer E 🛅 Controller WidgOmatic	◆ 早 2	Ě.
art P	🛛 🧰 Tasks		
ge	- 🔄 Motion Groups	and a second as	
	🖻 🔠 Ungrouped Axes 🏷 Gantry_X_Axis	New Axis New Coordinate System	
	🛛 🤣 Gantry_Y_Axis	1997 - 1997 -	
9	Add-On Instructions	Monitor Group Tag	
	- 🧰 Trends 🖥 🧰 I/O Configuration	Fault Help	
		Clear Motion Group Faults	
		Motion Direct Commands Cross Reference	Ctrl+E
			CUITE
		Print	
		Properties	Alt+Ent

Axis Assignment	Attribute Tag	
<u>U</u> nassigned:		A <u>s</u> signed:
		Gantry_X_Axis Gantry_Y_Axis
	Add>	< Remove
K		

•

Goto Module

Print

Properties

Monitor Axis Tag Fault Help Clear Axis Faults Motion Direct Commands... Manual Tune... Motion Generator... Cross Reference

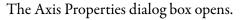
Ctrl+E

Alt+Enter

## **Configure Axis Properties**

Follow these steps to configure axis properties.

1. Right-click an axis in the Controller Organizer under your configured Motion Group and choose Properties.



2. Click the Motor category.

The Motor Device Specification dialog box opens.

- 3. From the Data Source pull-down menu, choose Catalog Number.
- 4. Click Change Catalog.

The Change Catalog Number dialog box opens.

neral	Motor Device S	pecification	_	_	_	_
Model (	<u>D</u> ata Source:	Catalog Number			Parameters	
otor Feedback aling	Catalog Number:	<none></none>		iange Catalog )		
aning bokup Tests	Motor Type:	Not Specified				
larity	Units:					
itotune	Units.	Rev	-			
ad						
Backlash						
Compliance Friction						
sition Loop						
locity Loop						
celeration Loop						
rque/Current Loop						
anner						
oming						
tions						
ive Parameters						
arameter List						
atus						
ults & Alarms						
g						

표 🧰 Controller WidgOmatic

🏷 Gantry\_X\_Axis 찾 Gantry\_Y\_Axis

Tasks
 Motion Groups
 Government

**5.** Select the motor catalog number appropriate for your application.

For the Widg-O-matic machine example, the MPL-B310P-M motor is used for both axes.

To verify the motor catalog number, refer to the motor name plate.

- 6. Click OK to close the Change Catalog Number dialog box.
- 7. Click Apply.

Motor data specific to your motor appears in the Motor category.

hange Catalog Nu Catalog Number:			
MPL-B310P-M		ſ	ок
MPL-B230P-Vxx4 MPL-B310P-H			Cancel
MPL-8310P-M MPL-8320P-H MPL-8320P-H MPL-8320P-S MPL-8330P-H MPL-8330P-H MPL-8330P-S MPL-8330P-S MPL-8330P-S			Help
Filters Voltage	Eamily	Feedba	ck <u>T</u> ype
<al></al>	<al></al>	kall>	~

8. Click the Scaling category and edit the parameter default values as appropriate for your application.

General	Scaling to Conv	ert Motion fro	om Con	troller Units to L	lser Defined	Units			
Motor     Motor Feedback	Load Type:	Direct Coupl	ed Bota	w 🗸		C	Parameters		
Scaling	Transmission					L	Language	_	
Hookup Tests	Ratio I:O:	17	_		Rev				
Polarity	mado <u>I</u> :U:	1			Hev				
Autotune	Actuator —								
🗉 Load	Туре;	<none></none>		× .					
Position Loop	Lead/Pitch:	1.0		Millimeter/Rev	14				
<ul> <li>Velocity Loop</li> <li>Acceleration Loop</li> </ul>		1200	_						
Torque/Current Loop	Diameter:	1.0		Millimeter	×				
Planner	Scaling								
Homing	<u>U</u> nits:	Position Unit	s						
Actions	Scaling:	1.0	_	Position Units	per	1.0		tor Rev 💉	
<ul> <li>Drive Parameters</li> </ul>		1.0		1 Oskion Onks	heī	1.0	1910		
Parameter List	Travel	-							
Status Faults & Alarms	<u>M</u> ode:	Unlimited	~						
Tag	Range:	1000.0	-	Position Units					
ray		1.0	_						
	Un <u>w</u> ind:	1.0		Position Units	p <u>e</u> r	1.0	Cycle		
	Soft <u>T</u> rave	Limits							
	Maximun	n Positive:	0.0	Po	sition Units				
	M svimi in	n Negative:	0.0		sition Units				

- 9. Click Apply, if you make changes.
- 10. Click the Load category and edit the parameter default values as appropriate for your application.

General	Characteristics of Motor Lo	oad			
Motor Motor Feedback	Load Inertia/Mass —	1	3		
Scaling	Load Coupling:	Rigid	*		
Hookup Tests Polarity	🔽 Use Load Ratio				
Autotune Load <u>Ratio</u> :		0.0	Load Inertia/Motor Inertia Kg-m^2		
l <mark>- Load</mark>					
Position Loop Velocity Loop	_otal Inertia:	0.000044	Kg·m^2		
- Acceleration Loop					
- Torque/Current Loop - Planner	Inertia/Mass Compensatio	on			
Homing	<u>S</u> ystem Inertia:	0.014468295	% Rated/(Rev/s^2)		
Actions Drive Parameters	System Acceleration:	6911.6646	Rev/s <sup>2</sup> @100 % Rated		
Parameter List Status Faults & Alarms	Active Load Compensation	ı			
Tag	Torque O <u>f</u> fset:	0.0	% Rated		

11. Click Apply, if you make changes.

#### **12.** Click the Actions category.

The Actions to Take Upon Conditions dialog box opens. From this dialog box, you can program actions and change the action for exceptions (faults).

13. Click Parameters.

- General	Actions to Take Upon I	Conditions				
a Motor → Motor Feedback → Scaling → Hookup Tests → Polarity → Autotune ⊕ Load → Position Loop → Velocity Loop	Stop Action: Motor Overload Action: Inverter Overload Action: Shutdown Action: Exceptionas	Current Decel & Disable <none> <none> Disable</none></none>	× × ×			ers IGER: Modifying Exception on settings may require
Acceleration Loop     Torque/Current Loop     Planner     Homing     Actions     Drive Parameter List     Status     Faults & Alarms     Tag	Bus Regulator Therma Bus Undervoltage Fac Bus Undervoltage Usi Commutation Startup I	vn al Overload Factory Limit al Overload User Limit story Limit Failure Failure emperature Factory Limit emperature User Limit	Action StopDrive StopDrive StopDrive StopDrive StopDrive StopDrive StopDrive StopDrive StopDrive StopDrive		disa pers Ref	rammatically stopping or bling the axis to protect connel, machine, and property. er to user manual for additional mation.
	Controller Initiated Exc		StopDrive	~~~		

The Motion Axis Parameters dialog box opens.

From this dialog box you can set delay times for servo motors and RBM modules.

General	Motion Axis Parameters	3		
Motor Model Motor Feedback	Parameter <u>G</u> roup:	Actions	<b>~</b>	Associated Page
Scaling	Name	۵	Value	Unit
Hookup Tests	FeedbackSignalLosst	JserLimit	100.0	% FL Voltage Drop
Polarity	InverterOverloadActio		<none></none>	-
Autotune	InverterThermalOverli	oadUserLimit	110.0	% Inverter Rated
- Load	MechanicalBrakeCont	rol	Automatic	
- Backlash	MechanicalBrakeEnga	ageDelay	0.0	s
- Compliance	MechanicalBrakeRele	aseDelay	0.0	s
Friction	MotorOverloadAction		<none></none>	
- Position Loop	MotorThermalOverloa	dUserLimit	110.0	% Motor Rated
- Velocity Loop	ProgrammedStopMod	Э	Fast Stop	
- Acceleration Loop	ResistiveBrakeContac	tDelay	0.0	S
- Torque/Current Loop	ShutdownAction		Disable	
- Planner	StoppingAction		Current Decel & Disable	
Homing	StoppingTimeLimit		1.0	S
Actions	StoppingTorque		295.2941	% Motor Rated
Drive Parameters     Parameter List     Status     Faults & Alarms     Tag				

- 14. Click OK.
- **15.** Repeat <u>step 1</u> through <u>step 14</u> for each axis.
- 16. Verify your device configuration and save the file.

# **Sercos Motion Drive Configuration**

This section applies to all Kinetix 6200, Kinetix 6000, Kinetix 6000M, Kinetix 2000, Kinetix 7000, and Ultra3000 sercos drives and includes these procedures:

- Configure Sercos Drive Modules
- Configure the Motion Group
- Configure Axis Properties

These sercos interface drive configuration steps were written specifically for Kinetix 6200 drives. The Kinetix 6000, Kinetix 2000, Kinetix 7000, and Ultra3000 sercos drive configuration steps are similar. You can also use the Kinetix 6000M integrated drive-motor (IDM) system when the IDM power interface module (IPIM) is added to the Kinetix 6000 power rail. Examples for each drive family are given when significant differences exist.

For more information on drive configuration, refer to the appropriate user manual listed in <u>Additional Resources</u> on <u>page 15</u>.

### **Configure Sercos Drive Modules**

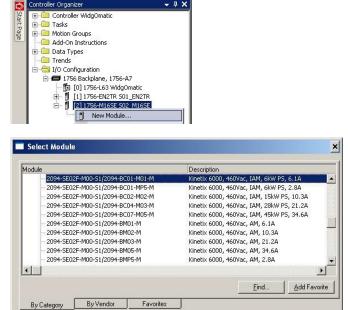
Follow these steps to configure the sercos drive modules.

- 1. Open your Logix Designer project file created in <u>Appendix F</u>.
- **2.** Right-click the sercos module you created and choose New Module.

The Select Module dialog box opens.

**3.** Expand the Drives category and select drive components appropriate for your actual hardware configuration.

In this example, the Kinetix 6200 2094-SE02F-M00-S1 control module and 2094-BC01-M01-M IAM power module are selected.



OK

Cancel

Help

Module Name	Power Module Type	Control Module/Power Module Cat. No.
Gantry_X_Drive	IAM	2094-SE02F-M00-S1/2094-BC01-M01-M
Gantry_Y_Drive	AM	2094-SE02F-M00-S1/2094-BMP5-M

IMPORTANT	To configure Kinetix 6200 drive modules (catalog numbers 2094-SE02F-M00-Sx, 2094-BCxx-Mxx-M, and 2094-BMxx-M)
	you must be using RSLogix 5000 software, version 17 or later, or the Logix Designer application, version 21 or later.

New Module

Allen-Bradley

Gantry\_X\_Drive

Type:

Vendor

Name: Description:

- 4. Click OK.
- **5.** Configure the new module.
  - a. Type the module Name.
  - b. Enter the Node address.

Set the node address in the software to match the node setting on the drive.

c. Check Open Module Properties.

#### Widg-O-matic X-Y Gantry Ethernet Address Configuration

Module Name	Node Address
Gantry_X_Drive	1
Gantry_Y_Drive	2

- 6. Click OK.
- 7. Click the Associated Axes tab.
- 8. Click New Axis.

General	Conr	nectior	Associated A	Power	Module Info			
N	ode	1:	<none></none>		•		(	New A <u>x</u> is
N	ode	129:	<none></none>		·	Auxiliary.	Axis	

Electronic <u>K</u> eying:	Compatible K	(eying	•
	ок	Cancel	
	Electronic <u>K</u> eying.		Electronic Keying: Compatible Keying

2094-SE02F-M00-S1/2094-BC01-M01-M Kinetix 6000, 460Vac, IAM, 6kW PS, 6.1A

4 1

Node: 1

÷

×

The New Tag dialog box opens.

9. Type the axis Name.

AXIS\_SERVO\_DRIVE is the default Data Type.

10. Click OK.

The axis appears under the Ungrouped Axes folder in the Controller Organizer.

Name:	Gantry_X_Axis	— (	OK
Description:		-	Cancel
			Help
		-	
<u>U</u> sage:	<normal></normal>	-	
Тур <u>е</u> :	Base 💽 Cont	nection	
Alias <u>F</u> or:		Ŧ	
Data <u>T</u> ype:	AXIS_SERV0_DRIVE		
<u>S</u> cope:	🖪 WidgOmatic	•	
E <u>x</u> ternal Access:	Read/Write	•	
Style:		*	

- **11.** Assign your axis to Node 1.
- 12. Click Apply.

Module Properties: S02\_M16SE (2094-SE02F-M00-S1/2094-BC01-M01-M 1.1) General Connection Associated Axes\* Power Module Info Node 1 Gantry X Axis -New Axis... <none: • ... Auxiliary Axis Node 129: Help 0K Cancel Apply Status: Offline

×

- 13. Click the Power tab.
- 14. From the Bus Regulator Configuration pull-down menu, choose the shunt option appropriate for your actual hardware configuration.

us Regulator Configuration: <a href="https://www.searchargerightscheric-state-stat&lt;br&gt;_ &lt;a href=" https:="" www.state-<br="">_ </a>
--

If your IAM power module is	And your hardware configuration includes this shunt option	Then choose
	Internal shunt resistors only	Internal or <none></none>
Configured as an IAM module or	Bulletin 2094 (rail mounted) shunt module <sup>(2)</sup>	2094-BSP2
common-bus leader IAM module <sup>(1)</sup>	Bulletin 1394 passive shunt module (connected to the 2094-BSP2 shunt module)	1394-SR <i>xxxx</i>
	Bulletin 1336 active shunt module	Internal or <none></none>
Configured as a common-bus follower IAM module $^{(3)}$	N/A. Shunts are disabled on follower IAM module	CommonBus Follow

(1) Drive will not accept Internal, <none>, 2094-BSP2, or 1394-SRxxxx selection if DC bus voltage is present without having three-phase power applied.

(2) To use the 2094-BSP2 shunt module with 2094-BCxx-Mxx-M power modules, you must be using Motion Database 5.12.1 or later. Contact Rockwell Automation Technical Support for more information.

(3) Drive will not accept CommonBus Follow selection if three-phase power or DC bus power is applied.

**15.** Calculate additional bus capacitance, if this applies to your application, and enter the value here (version 20.00 or later).

The Additional Bus Capacitance field only applies to the IAM power module.

IMPORTANT	DC common-bus applications must calculate Total Bus Capacitance and Additional Bus Capacitance and set the Add Bus Cap parameter in the leader IAM power module.
	Refer to the DC common bus appendix in the appropriate user manual listed in Additional Resources on <u>page 15</u> for more information on making these calculations.

- 16. Click OK to save and close the Module Properties dialog box.
- 17. For multi-axis systems, repeat <u>step 2</u> through <u>step 11</u> and <u>step 16</u> for each additional drive module including Kinetix 6200, Kinetix 6000, Kinetix 6000M, and Kinetix 2000 drives.

For more information on drive configuration, refer to the appropriate user manual listed in Additional Resources on page 15.

### **Configure the Motion Group**

Follow these steps to configure the motion group.

1. Right-click Motion Groups in the Controller Organizer and choose New Motion Group.

The New Tag dialog box opens.

- 2. Type the new motion group Name.
- 3. Click OK.

The new motion group appears under the Motion Groups folder.

4. Right-click the new motion group and choose Properties.

New Tag		×
Name:	UM_Motion	OK
Description:	×	Cancel Help
Usage:	<normal></normal>	
Туре:	Base Connection	
Alias For:	<b></b>	
Data Type:	MOTION_GROUP	
Scope:	🖪 UM_SERCOS 🗾	
External Access:	Read/Write	
Style:	V	

The Motion Group Properties dialog box opens.

- 5. Click the Axis Assignment tab and move your axes (created earlier) from Unassigned to Assigned.
- **6.** Click the Attribute tab and edit the default values as appropriate for your application.
- 7. Click OK.

🗣 Motion Group Properties - L	JM_Motion
Axis Assignment Attribute Tag	
Unassigned:	Assigned:
	Axis_1
Add>	< Remove
ОК	Cancel Apply Help

# **Configure Axis Properties**

Follow these steps to configure the Axis properties.

1. Right-click an axis in the Controller Organizer and choose Properties.

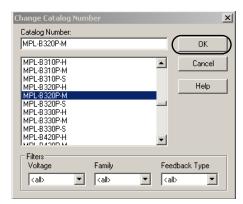
The Axis Properties dialog box opens.

🍄 Axis Properties - Ax	is_1
Homing Hookup General Motion Pla	Tune Dynamics Gains Output Limits Offset Fault Actions Tag nner Units Drive/Motor* Motor Feedback Aux Feedback Conversion
Amplifier Catalog Number	2094-SE02F-M00-S1/2094-BC02-M02-M
Motor Catalog Number:	<none> Change Catalog )</none>
Loop Configuration:	Position Servo
Drive Resolution:	200000 Drive Counts / Motor Rev  Calculate
Drive Enable Input Ch	necking
🔲 Drive Enable	Input Fault
Real Time Axis Informat	ion
Attribute 1:	<none></none>
Attribute 2:	Guard Status
	OK Cancel Apply Help

- 2. Click the Drive/Motor tab.
- 3. Click Change Catalog.

The Change Catalog Number dialog box opens.

- Select the motor catalog number appropriate for your application.
   To verify the motor catalog number, refer to the motor name plate.
- 5. Click OK to close the Change Catalog Number dialog box.
- 6. On the Drive/Motor tab, check Drive Enable Input Checking. When checked (default), means a hard drive-enable input signal is required. Uncheck to remove that requirement.
- 7. Click Apply.
- 8. Click the Motor Feedback tab and verify the Feedback Type shown is appropriate for your actual hardware configuration.
- 9. Click the Units tab and edit default values as appropriate for your application.



10. Click the Conversion tab and edit default values as appropriate for your application.

🗭 Axis Properties - Axis_1	
Homing Hookup Tune Dynamics Gains Output General Motion Planner Units Drive/Motor* Motor Fe	Limits   Offset   Fault Actions   Tag edback*   Aux Feedback Conversion*
Positioning Mode: Rotary	
Conversion Constant: 200000.0 Drive Counts/1.0 Position UI Based on 200000 Counts/M	
Position Unwind: 200000 Drive Counts/Unwind Based on 200000 Counts/M	lotor Rev
ОК	Cancel Apply Help

In this example, Rotary is chosen from the Positioning Mode pull-down menu.

- **11.** Click Apply if you made changes.
- **12.** Click the Fault Actions tab.

eral   Motion Planner ng   Hookup   Tun		1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1	orFeedback     Limits   0	Aux Feedback )ífset Fault A	Conversion
Enable Input:	isable Drive	<b>_</b>		iet Custom Stop	Action
Thermal: Dis	isable Drive	<b>*</b>			
r Thermal:	isable Dri Cus	tom Stop Action Attri	butes		E
back Noise:	tatus Onl <mark>y</mark> Na	ame	Value	Units	Туре
back:	hutdown St	toppingTorque	291.2458	% Rated	REAL
Jer	St	toppingTimeLimit	10.0	s	REAL
on Error: Dis		rakeEngageDelayTime	0.0		REAL
Overtravel: Dis	ianhla Dri	rakeReleaseDelayTime esistiveBrakeContactDelay	0.0		REAL
Dvertravel:	isable Dri	esistivebrakecontactbelay	0.0	•	NEAC
e Loss: Sh	hutdown		Close	Cancel	Help
Jos			Close	Cancel	

13. Click Set Custom Stop Action.

The Custom Stop Action Attributes dialog box opens. From this dialog box you can set delay times for servo motors and RBM modules.

- 14. Click OK.
- 15. Repeat step 1 through step 14 for each Bulletin 2094 AM power module and control module combination.
- 16. Verify your device configuration and save the file.

# **Kinetix 300 Drive Configuration**

Kinetix 300 drive configuration applies to all 2097-3*x*PR*x* drive modules and includes these procedures:

- Update Kinetix 300 Add-On Profiles
- Add Kinetix 300 Drives to Your Logix Designer Project
- Configure Kinetix 300 Drives

### Update Kinetix 300 Add-On Profiles

**IMPORTANT** The Kinetix 300 Add-On Profiles are independent of the RSLogix 5000 software or Logix Designer application releases. Update your Kinetix 300 Add-On Profiles to make sure your application runs correctly.

Add-On profiles (AOP) are available for download at the Custom Downloads Add-On Profiles website: <u>https://download.rockwellautomation.com/esd/download.aspx?downloadid=addonprofiles</u>

Follow these steps to download Kinetix 300 Add-On profiles.

1. Login to the Custom Download Add-On Profiles website.

The Custom Download Files dialog box opens.

Products & Technologi	es 🕨 So	olutions & Services  News 8	Innovation 🕨	Training	& Events >	Sales & Pa	rtners 🕨 Sı	ıpport ► About Us ►
Rockwell Software		tom Download Files	with this Download I	D only.				
Support Center		Description	Download Code	Version	Release Date	Release Notes	Download Size	Comments
KnowledgeBase Software Patches		AOP for RA E1 Plus		1.01.00	2012/08/20	1	27.86 MB	15.00.00 - Minimum RSLogio 5000 Software Revision
FAQ		AOP for RA E3 Plus via 2100-ENET		1.01.02	2012/08/20	<b>e</b>	70.77 MB	17.00.00 - Minimum RSLogic 5000 Software Revision
		AOP for 1791 Safety ES-IB16 &ES- IB8XOB\/4		5.03.01	2012/08/20	1	33.57 MB	16.00.00 - Minimum RSLogio 5000 Software Revision
		AOP for 1799 Embedded DIO 2-Port ENet IP		1.01.06	2012/08/20		28.63 MB	16.00.00 - Minimum RSLogio 5000 Software Revision
		AOP for 2097 Kinetix Drives		2.01.02	2012/08/20		28.26 MB	17.00.00 - Minimum RSLogio 5000 Software Revision
		AOP for 280E,281E,284E ArmorStart ENet		1.04.03	2012/08/20		78.69 MB	17.00.00 - Minimum RSLogic 5000 Software Revision
		AOP for PF755		11.01	2012/11/07	P	1.45 MB	16.00.00 - Minimum RSLogio 5000 Software Revision
		AOP for 1783 Stratix 5700/8000/8300 Swit		6.02.15	2012/11/15	P	35.64 MB	16.00.00 - Minimum RSLogi 5000 Software Revision
		AOP for CLX High Performance I/O		3.01.01	2013/01/14	P	72.62 MB	18.00.00 - Minimum RSLogi 5000 Software Revision

- 2. Check AOP for 2097 Kinetix Drives.
- Click Download Now and accept the user license agreement.
   If prompted to install the Download Manager, allow the installation.

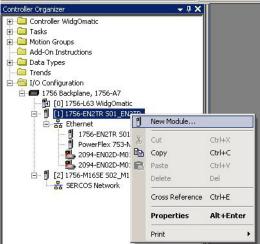
4. Click the Add-On Profile icon and follow the download instructions.

5. Extract the AOP zip file and run Setup.

# Add Kinetix 300 Drives to Your Logix Designer Project

Follow these steps to add each Kinetix 300 drive in your system to the Logix Designer project file. For the Widg-O-matic machine application example, you add a single drive.

- 1. Open your Logix Designer project file created in <u>Appendix F</u>.
- 2. Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.



 Right-click the network communication module for your Kinetix 300 drive and choose New Module. For the Widg-O-matic example, the 1756-EN2TR module is chosen.

The Select Module dialog box opens.

Module	Description
🚊 Drives	
- 150 SMC Flex-E	Smart Motor Controller via 20-COMM-E
- 150-SMCDialogPlus-EN1	Smart Motor Controller via 1203-EN1
- 1305-ACDrive-EN1	AC Drive via 1203-EN1
- 1336E-IMPACTDrive-EN1	AC Drive via 1203-EN1
- 1336F-PLUSIIDrive-EN1	AC Drive via 1203-EN1
2094-EN02D-M01-50	Kinetix 6500 Single Axis Ethernet Drive
	Kinetix 6500 Single Axis Ethernet Safety Drive
	Kinetix 300, 2A, 120/240V, No Filter
- 2097-V31PR2	Kinetix 300, 4A, 120/240V, No Filter
	Kinetix 300, 2A, 240V. Integrated Filter
By Category By Vendor	Favorites

4. Expand the Drives folder and select the appropriate Kinetix 300 drive for your application.

For the Widg-O-matic example, the 2097-V31PR0 drive is selected as the diverter drive.

5. Click OK.

The New Module dialog box opens.

6. Name the module.

	197-V31PR0 Kinetix 300	, 2A, 120/240V, No	Filter		
	en-Bradley )1_EN2TR		Ethernet Address		
	- iverter_Drive		IP Address:	192 . 168 .	1.35
Descri <u>p</u> tion:		<u> </u>	C Host <u>N</u> ame:		
I Module Definition					
Series:	A	Change	)		
Revision:	1.1				
Electronic Keying	r: Compatible	Module			
Connection:	Data				

For the Widg-O-matic application example, the name is Diverter\_Drive.

7. Enter the IP Address.

For the Widg-O-matic application example, the IP address is 192.168.1.35.

8. In the Module Definition field, click Change.

The Module Definition dialog box opens.

- **9.** Enter major and minor revisions appropriate for your drive hardware.
- **10.** Click OK to save and close the Module Definition dialog box.
- 11. Click OK to save and close the New Module dialog box.
- **12.** Verify your device configuration and save the file.

eries:	A	
<u>R</u> evision:		
Electronic <u>K</u> eying:	Compatible Module	-
Connection:	Data	-

### **Configure Kinetix 300 Drives**

In this section you configure each Kinetix 300 drive by using MotionView OnBoard software. Follow these three procedures to configure a single drive.

- Connect to the Kinetix 300 Drive
- Set Kinetix 300 Drive IP Address
- Configure Kinetix 300 Drive Parameters

#### Connect to the Kinetix 300 Drive

Configuration of the Kinetix 300 drive is performed over the standard 10/100 Mbps Ethernet communication port using MotionView OnBoard software contained within the drive itself. To access the MotionView software, the drive and your personal computer must be configured to operate on the same network.

- TIP The Kinetix 300 drive's IP address is scrolling across the keypad display. The default IP address for each Kinetix 300 drive (192.168.124.200) is used in this connection example.
- 1. Run a Java enabled web browser such as Internet Explorer.
- 2. Enter the drive's IP address into the browser.

The File Download dialog box opens.

3. Click Open.

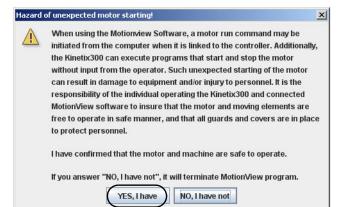
The Security Warning dialog box may open.

4. If the Security Warning dialog box opens, click Run.

File Ed	lit View	Favorites	Tools	Help		
ddress [	http://19	92.168.124.2	00			
Downlo	oad					×
) o you	want to op	pen or save	this fil	e?		
-	want to oj Name:			e?		
Do you '	Name: Type:	MotionView. JNLP File, 41	jnlp 90 bytes			
-	Name: Type:	MotionView.	jnlp 90 bytes			

The Hazard of unexpected motor starting dialog box opens.

5. Read the cautionary text and Click Yes, I have.



The MotionView software opens.

**6.** Click Connect.

🧏 MotionView OnBoard 3	. 25		
Allen-Bradley	Kinetix 300	English 🔻	Rockwell Automation
Connect	Disconnect	Save Connection	Stop/Reset
Load Connection	Print	Save Configuration	
Load Configuration	Restore Defaults	Upgrade	

The Connection dialog box opens.

7. Enter the drive IP Address.

The drive IP address is scrolling across the keypad display.

8. Click Connect.

Connected :	Connect to drive :	
		Discover
	ess : 192.168.124.200	Connect

MotionView software connects to the drive. Your drive's IP address and drive organizer appear.

9. Click the drive IP address to display the drive identification data.

Allen-Bradie	y Kine	LIX J	00	English	- Roc Autom
Connect	Disconne	:t	Save Connection	Load Connection	Stop/Re
Print	Save Configur	ation	Load Configuration	Restore Defaults	
Upgrade					
e [ 192.168.124.200	] : DISABLED				
Motor			Description	Val	ue
General © Communication		Driv	e ID String	B0410013310002	
✓ ● Ethernet			ce Family	B04	Ti -
● EtherNet/IP (0	lP)	20032053	ware Revision	1.00	
Digital IO		Vect	or Processor Revision	1.33	
Analog IO <ul> <li>Limits</li> </ul>		Har	dware Revision	1.00	
Velocity Limits		Dev	ation Revision	020	
Position Limits		Moti	onView OnBoard Revision	3.25	
Indexing		Mot	or Database Revision	007	
- Homing - Tools		Seri	al Number	351701013	
Monitor		Cata	log Number	2097-V31PB2	
V Faults		Proc	luct Code	278	
		Driv	е Туре	E94P040Y2NES-2	0
		2010/020	e Name		
		Grou	ıp ID	0	

#### Set Kinetix 300 Drive IP Address

The drive's IP address scrolls across the keypad display. The drive IP address must match the IP address used in your application. Follow this procedure if you need to change the IP address of your Kinetix 300 drive. If the address is correct then skip this section.

1. Open MotionView software and connect to your Kinetix 300 drive.

Follow the procedure in the previous section or if the MotionView Java application has been downloaded, double-click the MotionView Onboard icon.



2. From the drive organizer, select Communication>Ethernet.

Allen-Bradley	<b>Kinetix</b> 300		
Connect	Disconnect	Save Connection	Load Connection
Load Configuration	Restore Defaults	Upgrade	
Communication     Ethernet     EtherNet/IP (CIP)	Obtain IP Add IP Address	ress using DHCP	.1.35
Digital IO Analog IO	Subnet Mask	255.255	.255.0
	Default Gateway	0.0.0.0	

- 3. Uncheck Obtain IP Address using DHCP.
- 4. Enter the IP Address.

For the Widg-O-matic application example, the IP address is 192.168.1.35.

5. Enter Subnet Mask 255.255.255.0

After changing these parameters a warning message pop-up asks you to cycle power.



6. Click Ok.

#### Configure Kinetix 300 Drive Parameters

The Kinetix 300 drive parameters are configured using MotionView Onboard software over the EtherNet/IP network. For more information on drive parameters, refer to the Kinetix 300 EtherNet/IP Indexing User Manual, publication <u>2097-UM001</u>.

IMPORTANT	If your application does not use the Kinetix 300 safety circuit, make sure that the safe torque-off circuit is bypassed. Refer to the Kinetix 300 EtherNet/IP Indexing Servo Drives User Manual, publication <u>2097-UM001</u> , for more information on wiring the safety circuit.
TIP	By default, the Kinetix 300 drive uses a hardware enable signal. Refer to the Kinetix 300 EtherNet/IP Indexing User Manual, publication <u>2097-UM001</u> , for enable circuit wiring examples.

1. Open the MotionView software. If the MotionView Java application has been downloaded, double-click the MotionView Onboard icon.



2. Click the drive identification in the drive organizer and enter your Kinetix 300 drive name in the Drive Name field (optional).

Connect	Disconnect	Save Connection	Load Connection	Print	Stop/Reset
Load Configuration	Restore Defaults	Upgrade	Save Configuration		
Diverter_Drive [ 192.16	8.1.35])				
- Motor - General		Description	Value		Min
<ul> <li>Communication</li> </ul>	Drive ID String		B04100133100020		
Ethernet     EtherNet/IP (CIP)	Device Family		B04		
● IO	Firmware Revi	sion	1.00		
Digital IO	Vector Process	or Revision	1.33		
Analog IO <ul> <li>Limits</li> </ul>	Hardware Rev	ision	1.00		
Velocity Limits	Deviation Revi	sion	020		
<ul> <li>Position Limits</li> <li>Dynamics</li> </ul>	MotionView Or	Board Revision	3.25		
Indexing	Motor Databas	e Revision	007		
- Homing - Tools	Serial Number		351701013		
Monitor	Catalog Numb	er	2097-V31PR2		
Faults	Product Code		272		
	Drive Type		E94P040S1NES-20		
	Drive Name		Diverter_Drive		
	Group ID		0		0

For the Widg-O-matic application example, Diverter\_Drive is the Drive Name.

**3.** Select Motor in the drive organizer.

0 IO Digital IO	Currently sel	ected Motor : Sy	nchronous M	lotor			
Analog IO Limits	Vendor :	Rockwell Automation		Motor Model :	TLY-A110P-rxx2		ID : 696
Velocity Limits	Electrical	10 0000			Feedback		
Position Limits		Kt (Torque Constant)	0.230957	Nm/A 🔫	Absolute encod	ler, battery backe	d, multi turn
Dynamics Indexing		Ke (Voltage Constant),	24.1858196	V/KBpm 👻	Encoder		
Homing		(p-p, Sine Peak)			Туре	TS5669N124, 3	33 bits (16bit turns + 17 bit/tu
Tools			00.0000	- Contraction of the second	Status Code	0×40	
Monitor	24.840.004/2	Inductance phase-phase )		mH	100000000000000000000000000000000000000		
Faults	Bm (	Resistance phase-phase )	92.0000	Ohm	Overspeed		
		Nominal phase current	0.3866406	Amp	Counting E		
		Intermittent Current	1.0605	Amp	<ul> <li>Battery Erro</li> </ul>		
	1	Jominal Drive Bus Voltage	325 0000	Vdc	-		
		Number of poles		Vuc	Clear E		
	1	Nominal Drive Bus Voltage		Vdc	O Battery Ala	rm	
		rianibor or pores	-				

Allen-Bradley motors and actuators with intelligent feedback devices automatically populate data fields in the motor configuration. For Allen-Bradley motors and actuators with incremental encoders, click Change Motor and choose from the provided list.

For the Widg-O-matic application example, the Kinetix 300 demo box containing a 2097-V31PR0 drive and a TLY-A110P-BJ62AA motor was used.

4. Select General in the drive organizer.

Diverter_Drive [ 192.10	Description	Value	Units	Min
General Communication	re Mode	EtherNet/IP External Reference		
	rrent Limits			
	irrent Limit	3.4299998	А	0.0000
Digital IO Analog IO Limits	KHZ Peak Current Limit	9.8999996	А	0.0000
Velocity Limits	locity Mode Acceleration			
Position Limits Dynamics	able Accel / Decel Limits	Enable 🗸		
Indexing 🗛	cel Limit	100.0000 D	RPM / Sec	0.1000
	ecel Limit	100.0000	RPM / Sec	0.1000
Monitor Faults Fau	lt Reset	Manual Only 🗸 🗸		
Mo	tor Temperature Sensor	Disable 👻		
MA	ASTER ENCODER : Master To S	System Ratio		
M	aster	1		-32768
Sy	stem	1		1
Use	er Units	1.0000	Revolutions / Units	0.0000

5. From the Drive Mode pull-down menu, choose AutoTune.

AutoTune is the default setting. Run AutoTune on your motor/drive combination if not already done. For a detailed understanding of the AutoTune parameter, refer to the Kinetix 300 EtherNet/IP Indexing User Manual, publication <u>2097-UM001</u>.

If your drive has been tuned with this motor, you can switch the Drive mode to Index or EtherNet/IP External Reference.

- **TIP** The Kinetix 300 device module includes logic to switch the Drive mode as required by your application.
- 6. From the Accel/Decel Limits pull-down menu, choose Enable.
- 7. Type values in the Accel and Decel limit fields appropriate for your application.

For the Widg-O-matic application example, the Accel and Decel limit values are 200.

**TIP** The Kinetix 300 device module includes logic to adjust the Accel/Decel limits as required by the application.

- 8. From the Fault Reset pull-down menu, choose Manual Only.
- 9. Type a value in the User Units Value field.

For the Widg-O-matic application example, the User Units value is 1.0.

**10.** Select Communication>Ethernet>EtherNet/IP (CIP) in the drive organizer to display the Input and Output Assembly Links (datalinks) to the controller.

The Widg-O-matic application example and Kinetix 300 drive do not require any additional Assembly Links. Leave the entries at default values.

11. Select IO>Digital IO in the drive organizer.

Diverter_Drive [ 192.10	Output 1 Function	Not Assigned	-		
Motor General	Output 2 Function	Not Assigned	•		
<ul> <li>Communication</li> </ul>	Output 3 Function	Not Assigned	-		
Ethernet EtherNet/IP (CIP)	Output 4 Function	Not Assigned	-		
IO	Input A1 Debounce Time	0		ms	0
Digital IO Analog IO	Input A2 Debounce Time	0		ms	0
Limits	Input A3 Debounce Time	0		ms	0
Velocity Limits Position Limits	Input A4 Debounce Time	0		ms	0
Dynamics	Input B1 Debounce Time	0	17	ms	0
Indexing	Input B2 Debounce Time	0		ms	0
Homing Tools	Input B3 Debounce Time	0		ms	0
Monitor	Input B4 Debounce Time	0		ms	0
Faults	Input C1 Debounce Time	0		ms	0
	Input C2 Debounce Time	0		ms	0
	Input C3 Debounce Time	0		ms	0
	Input C4 Debounce Time	0		ms	0
	Hard Limit Switches Action	Not Assigned	•		
	Enable Switch Function	Inhibit	•)		
	Brake Engage Delay	160		ms	0
	Brake Release Delay	110		ms	0

You can leave the input and output functions at default values.

- 12. From the Enable Switch Function pull-down menu, choose Inhibit.
- **13.** Select Limits>Velocity Limits in the drive organizer.

Diverter_Drive [192.16     Motor     General	Description	Value	Units
<ul> <li>Communication</li> </ul>	Zero Speed	0.1600	User Units / Sec
Ethernet     EtherNet/IP (CIP()	Speed Window	1.6000	User Units / Sec
	At Speed	16.0000	User Units / Sec

These values set status bits used in the Kinetix 300 drive.

14. Type values for the Zero Speed, Speed Window, and At Speed parameters.

The Velocity Limit parameter values are the recommended starting values.

**15.** Select Position Limits in the drive organizer.

Motor General	Description	Value	Units
Communication	Position Error	32767	Counts
<ul> <li>Ethernet</li> <li>EtherNet/IP (CIP)</li> </ul>	Max Error Time	100.0000	ms
● 10	Abort Decel	100.0000	User Units / Sec
Digital IO Analog IO	Position Limit	0.1000	User Units
<ul> <li>Limits</li> </ul>	Soft Limits	Off	👻 User Units
Velocity Limits Position Limits	Positive Limit	0.0000	User Units
Dynamics	Negative Limit	0.0000	User Units
Indexing Homing Tools Monitor Faults			

16. Type a value for the Abort Decel field.

The Abort Decel parameter is used when the drive stops for a fault, index abort, or disable function.

For the Widg-O-matic application example, the Abort Decel parameter value is 200. The other values set status bits used in the Kinetix 300 drive.

**TIP** The Kinetix 300 device module includes logic to adjust the Abort Decel limit required by the application.

17. Type values for the other Position Limit parameters.

The Position Limit parameter values are the recommended starting values.

**18.** Select Indexing in the drive organizer.

Diverter_Drive [192.10 Motor General	j. J	Description	Value	Units
<ul> <li>Communication</li> </ul>	AutoStart	Index	Disable	-
Ethernet     EtherNet/IP (CIP)	Start Inde	ax .	0	
IO     Digital IO	Current li	ndex	0	
Analog IO Cimits		Start Indexing	Abort Indexing	Reset Index
Velocity Limits Position Limits Dynamics		- Democratic Action		
Indexing	Ŧ	Index 00		
Homing Tools	Ŧ	Index 01		
Monitor	Ŧ	Index 02		
Faults	Ŧ	Index 03		
	Ŧ	Index 04		

- 19. From the AutoStart Index pull-down menu, choose Disable.
- 20. Leave all of the other Index configuration values as default.

**TIP** The Kinetix 300 device module includes logic to configure the Indexing parameters as required by the application.

**21.** Select Homing in the drive organizer.

Diverter_Drive [192.10 Motor					
General	Description		Value	Units	Min
Communication	Home Accel / Decel	10.0000		User Units / Sec <sup>2</sup>	0.0000
Ethernet EtherNet/IP (CIP)	Home Offset	0.0000		User Units	-8191.900
<ul><li>IO</li></ul>	Home Velocity Fast	1.0000		User Units / Sec	0.0000
Digital IO Analog IO	Home Velocity Slow	1.0000		User Units / Sec	0.0000
Limits	Home Switch	Input B1		•	
Velocity Limits Position Limits Dynamics	Homing Status	Homed			
Indexing	Start Homing	1	Abort Homing		
Homing Tools Monitor	ID Home Method	Direction	Logix Type	Home Sensor Polarity	
Faults	34 Marker	Forward	Home to marker	n/a	-

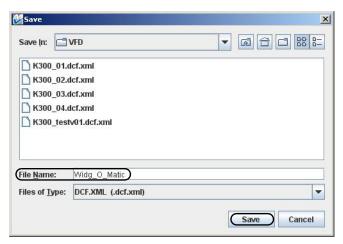
22. Enter values for the Homing parameters according to your application.

The values shown were used to configure the homing parameters for the Kinetix 300 demo box used in the Widg-O-matic application example.

23. From the MotionView menu bar, click Save Configuration.

Allen-Brack	dley Kinetix 3	00
	1992	
Connect	Disconnect	Save Connection

The Save dialog box opens.



**24.** Enter a file name.

For the Widg-O-matic application example, the file name is Widg\_O\_Matic.

25. Click Save.

# E3 Plus Overload Relay with Communication Auxiliary Configuration

E3 Plus overload relay configuration applies to E3 Plus overload relays with the 193-DNENCAT communication auxiliary module, and includes these procedures:

- Update E3 Plus Add-On Profiles
- Add E3 Plus Devices to Your Logix Designer Project

### **Update E3 Plus Add-On Profiles**

**IMPORTANT** The E3 Plus Add-On Profiles are independent of RSLogix 5000 software or Logix Designer application releases. Update your E3 Plus Add-On Profiles to make sure your application runs correctly.

Add-On profiles (AOP) are available for download at the Custom Downloads Add-On Profiles website: <u>https://download.rockwellautomation.com/esd/download.aspx?downloadid=addonprofiles</u>

Follow these steps to download E3 Plus Add-On profiles.

1. Login to the Custom Download Add-On Profiles website.

The Custom Download Files dialog box opens.

						and a state of the	20 1 3 A	
Products & Technolog	ies ► Sc	olutions & Services 🕨 News a	& Innovation 🕨	Training	& Events 🕨	Sales & Pa	rtners) Su	ıpport
	Cust	om Download Files						
Rockwell Software	The fo	llowing items are available for download	d with this Download I	D only.				
Support Center		Description	Download Code	Version	Release Date	Release Notes	Download Size	Comments
KnowledgeBase Software Patches		AOP for RA E1 Plus		1.01.00	2012/08/20		27.86 MB	15.00.00 - Minimum RSLogi 5000 Software Revision
FAQ		AOP for RA E3 Plus via 2100-ENET		1.01.02	2012/08/20	Ð	70.77 MB	17.00.00 - Minimum RSLogi 5000 Software Revision
		AOP for E3 Plus 193-DNETCAT(R)		1.01.04	2012/08/20		27.85 MB	17.00.00 - Minimum RSLogi 5000 Software Revision
		AOP for Drives-PowerFlex/SCANport		4.04.01	2012/09/05	1	247 MB	16.00.00 - Minimum RSLogi 5000 Software Revision
		AOP for RA1769Analog		8.04.00	2012/09/12		73.42 MB	13.04.00 - Minimum RSLogi 5000 Software Revision

Total Download Size = 0 B

Download Now

- **2.** Check AOP for E3 Plus 193-DNENCAT(R).
- Click Download Now and accept the user license agreement. If prompted to install the Download Manager, allow the installation.
- 4. Click the Add-On Profile icon and follow the download instructions.
- 5. Extract the AOP zip file and run MPSetup.

### Add E3 Plus Devices to Your Logix Designer Project

Follow these steps to add each 193-DNENCAT device in your system to the Logix Designer project file.

- 1. Open your Logix Designer project file created in the previous section (for the Widgomatic example the project file was named Widgomatic.acd).
- 2. Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.

Select Module

3. Right-click the network communication module for your E3 Plus Device and choose New Module.

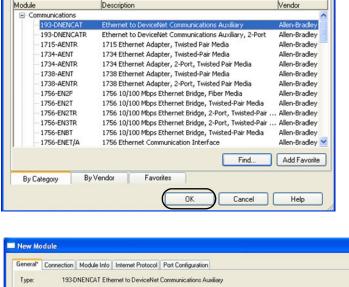
The Select Module dialog box opens.

4. Expand the Communications folder and select the Ethernet to DeviceNet Communications Auxiliary module.



The New Module dialog box opens.

- **6.** Name the module.
- 7. Enter the IP Address.
- 8. In the Module Definition field, click Change.



Vendor: Parent:	Allen-Bradley S01_EN2T		Ethernet Address		
Na <u>m</u> e:	DNENCAT		Private Netw	ork: 192.168.1.	40 🗢
Description: Module Del Series: Revision: Electronic K Connection Data Mappi	A 2.1 Keying: Com c Data	Change	IP Address:     Host Name:		

The Module Definition dialog box opens.

- 9. Enter the series and revision appropriate for your hardware.
- 10. Click OK to save and close the Module Definition dialog box.
- 11. Click OK to save and close the New Module dialog box.



12. Verify your device configuration and save the file.

IMPORTANT	You must set the following parameters in the E3 Plus overload relay or the AOI does not function properly in your Logix Designer
	application:
	- Param 50 Output Accombly - 105

- Param 59, Output Assembly = 105
  Param 60, Input Assembly = 100
- Param 61, Assy Word 0 Param = 21 (supplies status of Inputs and Outputs)
- Param 62, Assy Word 1 Param = 4 (supplies Avg current)
- Param 63, Assy Word 2 Param = 14 (supplies Trip Status)
- Param 64, Assy Word 3 Param = 15 (supplies Warning Status)

Refer to the Bulletin 193 EtherNet/IP Communications Auxiliary User Manual, <u>193-UM014</u>, for details on how to configure parameters.

# E300 Overload Relay Configuration

E300 overload relay configuration includes these procedures:

- Update E300 Add-On Profiles
- Add E300 devices to your Logix Designer Project

### **Update E300 Add-On Profiles**

**IMPORTANT** The E300 Add-On Profiles are independent of RSLogix 5000 software or Logix Designer application releases. Update your E300 Add-On Profiles to make sure your application runs correctly.

Add-On profiles (AOP) are available for download at the Custom Downloads Add-On Profiles website: <u>https://download.rockwellautomation.com/esd/download.aspx?downloadid=addonprofiles</u>

Follow these steps to download E300 Add-On profiles.

1. Login to the Custom Download Add-On Profiles website.

The Custom Download Files dialog box opens.

Rockwell Automation ust	TEN. THINK. SOLVE!						
Products & Technologies >	Solutions & Services > News & Innovation > Training & Events > Sal	es & Partners 🕨	Support > Al	oout Us 🕨			
Rockwell Software	Other Download Files			Download Size			
Support Center	Add On Profiles - IMPORTANT	ALL	2014/03/28	86 B			
KnowledgeBase     Software Patches	IMPORTANT WARNING: The list below is not sorted in alphabetical order. Please	IMPORTANT WARNING: The list below is not sorted in alphabetical order. Please use Ctrl-F to search for the AOP you need					
<ul> <li>FAQ</li> </ul>	1769 Boolean	1.03.01	2012/08/20	6.7 MB			
	17.00.00 - Minimum RSLogix 5000 Software Revision						
	☑ 193-ECM-ETR E300 Ethernet Overload Relay	1.00.11	2013/12/20	77.2 MB			
	17.00.00 Minimum RSLogix 5000 Software Revision. Minimum Module/ Firmware	Revision is 1.0					

- 2. Check the AOP for 193-ECM-ETR E300 Ethernet Overload Relay.
- Click Download Now and accept the user license agreement.
   If prompted to install the Download Manager, allow the installation.
- 4. Click the Add-On Profile icon and follow the download instructions.
- 5. Extract the AOP zip file and run MPSetup.

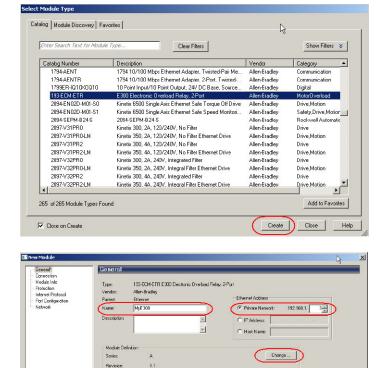
#### Add E300 Devices to Your Logix Designer Project

Follow these steps to add each E300 device in your system to the Logix Designer project file.

- 1. Open your Logix Designer project file created in the previous section (for the Widgomatic example the project file was named Widgomatic.acd).
- 2. Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.
- 3. Right-click the network communication module for your E300 device and choose New Module.

The Select Module dialog box opens.

**4.** Expand the Communications folder and select the E300 relay.



5. Click OK.

The New Module dialog box opens.

- 6. Name the module.
- 7. Enter the IP Address.
- **8.** In the Module Definition field, click Change.

The Module Definition dialog box opens.

Status: Creating

Electronic Keving

Control Module

Competible Module

MOMESHUB-302

193-EI0-43-120

Dverload

Digital Module 1

Digital Module 2 Digital Module 3

Digital Module 4:

Operator Station

The E300 Control Strategy may override control of module outputs from the controlle

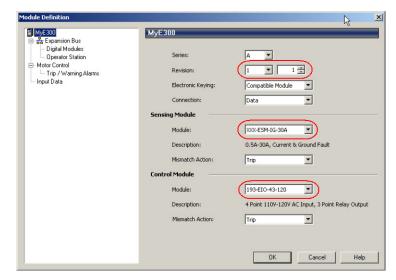
Undefined

Undefined

Undefined

OK Cancel Heb

- **9.** Enter the series and revision appropriate for your hardware.
- **10.** Select the appropriate sensing and control modules.
- **11.** Click OK to save and close the Module Definition dialog box.
- **12.** Click OK to save and close the New Module dialog box.
- **13.** Verify your device configuration and save the file.



# SMC-50 Soft Starter Configuration

SMC-50 soft starter configuration includes these procedures:

- Update SMC-50 Add-On Profiles
- Add SMC-50 Devices to your Logix Designer Project
- Download Soft Starter Parameters

## **Update SMC-50 Add-On Profiles**

**IMPORTANT** The SMC-50 Add-On Profiles are independent of RSLogix 5000 software or Logix Designer application releases. Update your SMC-50 Add-On Profiles to make sure your application runs correctly.

Add-On profiles (AOP) are available for download at the Custom Downloads Add-On Profiles website: <u>https://download.rockwellautomation.com/esd/download.aspx?downloadid=addonprofiles</u>

Follow these steps to download SMC-50 Add-On profiles.

1. Login to the Custom Download Add-On Profiles website.

The Custom Download Files dialog box opens.

AOP for RA E1 Plus	1.01.00	2012/08/20	1	27.86 MB	15.00.00 - Minimum RSLogix 5000 Software Revision
AOP for RA E3 Plus via 2100-ENET	1.01.02	2012/08/20	<b>B</b>	70.77 MB	17.00.00 - Minimum RSLogix 5000 Software Revision
AOP for E3 Plus 193-DNETCAT(R)	1.01.04	2012/08/20		27.85 MB	17.00.00 - Minimum RSLogix 5000 Software Revision
AOP for Drives-PowerFlex/SCANport	4.04.01	2012/09/05	Þ	247 MB	16.00.00 - Minimum RSLogix 5000 Software Revision
AOP for RA1769Analog	8.04.00	2012/09/12		73.42 MB	13.04.00 - Minimum RSLogix 5000 Software Revision
AOP for 1788-CN2FFR	1.01.16	2012/10/25	1	78.86 MB	15.00.00 - Minimum RSLogix 5000 Software Revision

- 2. Check the AOP for Drives-PowerFlex/SCANport profile.
- Click Download Now and accept the user license agreement.
   If prompted to install the Download Manager, allow the installation.
- 4. Click the Add-On Profile icon and follow the download instructions.
- 5. Extract the AOP zip file and run MPSetup.

#### Add SMC-50 Devices to Your Logix Designer Project

Follow these steps to add each SMC-50 device in your system to the Logix Designer project file.

- 1. Open your Logix Designer project file created in the previous section (for the Widgomatic example the project file was named Widgomatic.acd).
- 2. Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.
- Right-click the network communication module for your SMC-50 device and choose New Module.
   The Select Module dialog box opens.

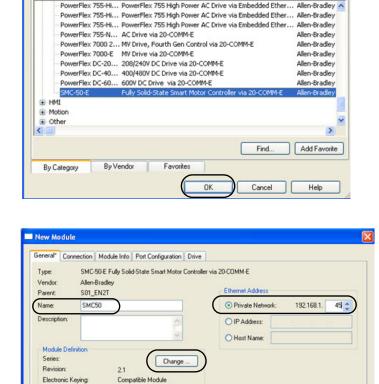
Module

Description

- **4.** Expand the Drives folder and select the SMC-50 module.
- 5. Click OK.

The New Module dialog box opens.

- 6. Name the module.
- 7. Enter the IP Address.
- **8.** In the Module Definition field, click Change.



OK

Cancel Help

Parameters via Datalinks

Parameters

Vendor

The Module Definition dialog box opens.

Status: Creating

Connection

Data Formal

Revision:	2	/ 1	*	Datalink	Input Data		Output Data	
	Compatible M	a di da			LogicStatus		LogicCommand	
Electronic Keying:	Compatible M	odule	Y		PhaseACurrent		NotUsed	
Drive Rating:	Standard		~	-			Use Network Refe	rence
	ordinadia			<b>A</b> ∑	MtrThermUsage - 18	_	SlowSpeed - 72	~
					Fault1 - 138		Undefined_A2	~
				₽B	VoltsPhaseA_B - 2		Undefined_B1	~
					StopMode - 65	~	Undefined_B2	×
				C				
				D		- İ		
connection:	Parameters vi	a Datalinks	~					
Data Format:	Parameters		~		Sort Input/Output s			
Data Format: If the revision of you - click Create Data - click Web Updat the web if drive is To match revision a - click Match Drive	Parameters ur drive is not listed base button belo e to download th offline.	t wil drive is or e database fro	m	edrive: Y	Sort Input/Output s ANGER: Unexpected, h hen improperly using soft arameter names selected ember names in the drive ecessary Datalink param ata transfer between con arameters. ou must download config ontroller, drive and comm onsistent with each other	azardou ware to Modu eters in troller a uuration unicati	us motion of machinery o configure a drive. Input and Output Data le-Defined Data Types the RSLogix 5000 proj nd drive is determined I to the drive to ensure t	may occ appear and defi ect. Actu by Datal hat the

The Module Definition dialog box lets you configure and access drive data beyond standard I/O.

9. Configure module definitions.

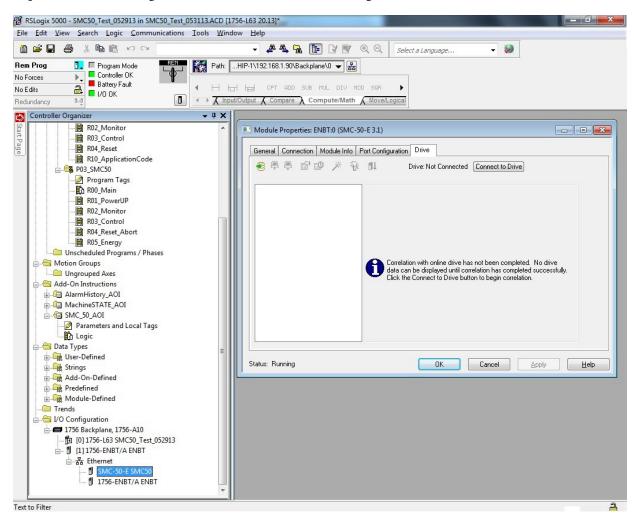
IMPORTANT	The datalinks listed for the SMC-50 soft starter must be configured exactly as shown for successful faceplate AOI import
	and operation. If additional datalinks are required for your application, modifications to the corresponding AOI can be
	required.

- a. Enter major and minor revisions appropriate for your drive hardware.
- b. Enter drive rating appropriate for your drive hardware.
- c. Set datalink definitions.
- 10. Click OK to save and close the Module Definition dialog box.
- 11. Click OK to save and close the New Module dialog box.
- 12. Verify your device configuration and save the file.

### **Download Soft Starter Parameters**

**IMPORTANT** Before downloading drive parameters, you must configure personal computer communication properties and EtherNet/IP driver. Refer to <u>Appendix D</u> on <u>page 257</u> for more information.

- 1. Download application to the Logix5000 controller and go online.
- 2. Expand the I/O Configuration folder in the Controller Organizer.



3. Double-click your SMC-50 soft starter module.

The Module Properties dialog box opens.

General Connection	ENBT:0 (SMC-50-E 3.1)
	Differences Found Differences were found between the project and the drive. How do you want to proceed? No drive successfully. Upload Download Cancel Help Show Details
Status: Running	OK Cancel Apply Help

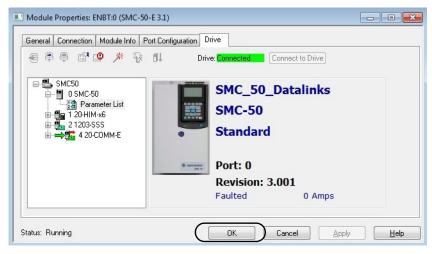
4. On the Drive tab, click the Connect to Drive icon.

The Differences Found dialog box opens.

5. Click Download.

Project parameters transfer to the drive.

Following download, the Module Properties dialog box displays green Drive Connected status indicator and soft starter information is displayed. If not, follow other version compatibility update dialog boxes to connect to soft starter.



- 6. Click OK.
- 7. Click 📕 to save your Logix Designer application file.

👪 RSLo	gix 50	00 - W	idgOm	atic [1756-L6	3 18.1	1]*
File Edit	View	Search	Logic	Communications	Tools	Win
		S 🕹		3 10 10		
Offline		0, I	RUN		L.A.	
No Forces		▶ <b>.</b> .	OK		-9-	-
No Edits		2	BAT			
Redundand	ÿ	0.0	- 1/0		٥	

# **ArmorStart Distributed Motor Controller Configuration**

ArmorStart distributed motor controller configuration includes these procedures:

- Update ArmorStart Add-On Profiles
- Add ArmorStart Devices to Your Logix Designer Project

# **Update ArmorStart Add-On Profiles**

**IMPORTANT** The ArmorStart Add-On Profiles are independent of RSLogix 5000 software or Logix Designer application releases. Update your ArmorStart Add-On Profiles to make sure your application runs correctly.

Add-On profiles (AOP) are available for download at the Custom Downloads Add-On Profiles website: <u>https://download.rockwellautomation.com/esd/download.aspx?downloadid=addonprofiles</u>

Follow these steps to download ArmorStart Add-On profiles.

1. Login to the Custom Download Add-On Profiles website.

The Custom Download Files dialog box opens.

2097 Kinetix Drives	2.01.02	2012/08/20	Þ	28.26 MB
17.00.00 - Minimum RSLogix 5000 Software Revision				
280E,281E,284E ArmorStart EtherNet/IP	1.04.03	2012/08/20	Þ	78.69 MB
17.00.00 - Minimum RSLogix 5000 Software Revision				
290E, 291E, 294E ArmorStart LT	2.01.02	2012/08/20	<b>P</b> )	82.11 MB
17.00.00 - Minimum RSLogix 5000 Software Revision				

- 2. Check the AOP for ArmorStart Bulletin 280E or 290E profile.
- Click Download Now and accept the user license agreement.
   If prompted to install the Download Manager, allow the installation.
- 4. Click the Add-On Profile icon and follow the download instructions.
- 5. Extract the AOP zip file and run MPSetup.

## Add ArmorStart Devices to Your Logix Designer Project

Follow these steps to add each ArmorStart device in your system to the Logix Designer project file.

- 1. Open your Logix Designer project file created in the previous section (for the Widgomatic example the project file was named Widgomatic.acd).
- 2. Expand the I/O Configuration folder in the Controller Organizer and browse to the controller backplane.

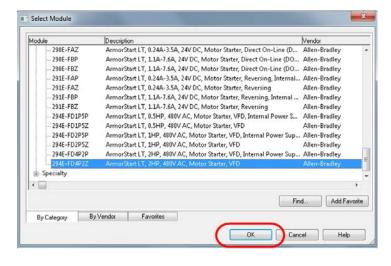
3. Right-click the network communication module for your ArmorStart device under other and click OK.

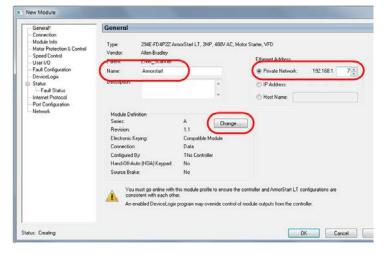
The Select Module dialog box opens.

- **4.** Expand the Drives folder and select the ArmorStart module.
- 5. Click OK.

The New Module dialog box opens.

- 6. Name the module.
- 7. Enter the IP Address.
- 8. In the Module Definition field, click Change.





The Module Definition dialog box opens.

Module Propert     General     Connection     Module Info     Connection     Module Info     Module Info     User I/0     Seed Contro     User I/0     Fault Configur     DeviceLogix     Status     Intermet Proto-     Port Configur	todule Definition Series: Revision: Electronic Keying: Connection: Configured By: User 1/0	A ▼ 1 ▼ 1÷ Compatible Module ▼ Data ▼ This Controller ▼	Dptions Hand Off-Auto (HDA) Keypad: Yes Source Brake: Yes	
- Network	0 Input v	I Irput -	2 Input •	
Status: Offline	Output -	Dutput -	Cancel Help	Р Нер

- 9. Enter the appropriate information for your hardware.
  - a. From the Hand-Off-Auto (HOA) Keypad and Source Brake pull-down menus, choose Yes. These options are required to be enabled.
  - b. From the User I/O pull-down menus, choose Output for I/O 3, 4, 5 and choose Input for I/O 1, 2, 3.
     You can change the User I/O settings based on application requirements. If modified, the module definition changes affecting the AOI input and output data type. Refer to How to Change the AOI Input and Output Data Type on page 390.

IMPORTANTThe User I/O configuration must be defined in the HMI 29xE faceplate parameter file for parameters #10, #11, #12, #13,<br/>#14 and #15.HOA Keypad and Source Brake options must be enabled to work with the Logix AOI and HMI faceplate. These settings<br/>won't affect hardware performance, even if the hardware doesn't have the options.

- 10. Click OK to save and close the Module Definition dialog box.
- 11. Click Yes to acknowledge the Change module definition warning.

New Module	Module Definition*			23	
General* – Connection – Module Info – Speed Confue – Speed Confue – Pault Configured – DeviceLogix ⊖ Status – Fault Status – Internet Protoco – Port Configuredia – Network	Data will b Verify mod	A Compatible Module Data This Controller This Controller sets to default values unless it can be recover lule properties before Applying changes. odule definition? Yes No		Yes   Yes  nodule properties.	5 A. V
	Output -	Gulput v	Outp	<b>5</b> u	
Status: Creating		OK	Cancel	Help	Help

<b>12.</b> Click OK to save and close the New Module dialog	New Module	×
box.	Generation — Connection* — Modue Info* — Motor Protection & Control* — Speed Control* — Speed Control* — Fault Configuration* — DeviceLogix* — Fault Status* — Internet Protocol* — Port Configuration* — Network*	General         Type:       234E-FD 4P2Z AmorStart LT, 2HP, 480V AC, Motor Stater, VFD         Vendor:       Allen-Bradey         Parent:       ENe_Scanner         Name:       Amorstart         Description:       © Private Network:         192.158.1.       7         Pescription:       © Private Network:         192.158.1.       7         Pescription:       © Private Network:         192.168.1.       7         Private Network:       192.168.1.         Module Definition       ©         Series:       A         Revision:       1.1         Electronic Keying:       Compatible Module         Cornection:       Data         Configured By:       This Controller         Hand-Off-Mudo [HDA] Keypad:       Yes         Source Brake:       No         Vou must go online with this module profile to ensure the controller and AmorStart LT configurations are consistent with each other.         An enabled DeviceLogix program may override control of module outputs from the controller.
	Status: Creating	OK Cancel Help

- 13. Verify your device configuration and save the file.
- 14. Refer to the ArmorStart Distributed Motor Controller user manuals, publications <u>290E-UM001</u> and <u>280E-UM001</u>, for more information on how to configure the device.

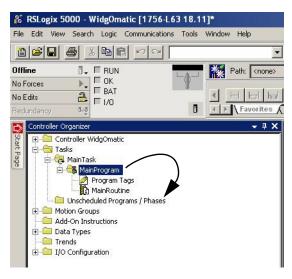
# **Import and Configure Logic Modules**

In this section you import the machine, application, and device modules into your Logix5000 application without using the DMAT Wizard or making edits after initial file is created.

### Import and Configure the Machine Logic Module

Follow these steps to add the preconfigured machine logic program file to your Logix Designer project and configure it to your specific application.

1. Open your Logix Designer project that you added to the Device Configurations in <u>Appendix G</u>.



For the Widg-O-matic machine application example, the WidgOmatic project was opened.

- 2. Expand the Tasks folder in your Controller Organizer and drag-and-drop the MainProgram folder to the Unscheduled Programs / Phases folder.
- 3. Right-click the Main Task folder, and choose Import Program.



**4.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 01\_Machine Logic folder.

nport Program	<b>b</b>					1
Look jn:	6 4-Controller L	ogic	•	00	🕑 🛄 •	
	01_Machine Lo					
My Recent	02_Application					
Documents						
Desktop						
1						
My Documents						
My Computer						
	File <u>n</u> ame:				•	I <u>m</u> port
My Network	Files of type:	RSLogix 5000 XML Files (*.L5	5X)		Ţ	Cancel
Places	Files <u>c</u> ontaining:	Rrogram			•	Help
	Int <u>o</u> :	🔀 Main Task			-	
					_	

Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

5. Select the Machine\_Module.L5*x* file and click Import.

Import Program	1					×
Look jn:	C 01_Machine	Logic	-	00	P 🔜	•
My Recent Documents Desktop My Documents My Computer	Machine_Modu	ile 1.5X				
My Network Places	File <u>n</u> ame: Files of type: Files <u>c</u> ontaining: Int <u>o</u> :	Machine_Module	L5X)		•	Limport Cancel Help

Find Within: Final Name		
mport Content:		
👼 MainTask	Configure Progr	am Properties
PXX_MachineName Program Tags	Import Name:	PXX_MachineName
	Operation:	Create 🔽 🗅
References		References will be imported as configured in the References folders
していたい Add-On Instructions	Final <u>N</u> ame:	PXX_MachineName   Properties
Errors/Warnings	Description:	Machine Module
	<u>S</u> chedule In:	🔀 MainTask.
	Inhibit Progra	m
	Assigned Rout	tines
	Main:	🗈 R00_Main
	Fault	<none></none>

The Import Configuration dialog box opens.

6. Type the desired name for your machine in the Final Name field.

ort Content: - 🥰 MainTask	Configure Prog	ram Properties	
P01_WidgOmatic	Import Name:	PXX_MachineName	
Routines	Operation:	Create	- 1
References		Beferences will be imported in the References wi	rted as ences folders
Add-On Instructions	Final <u>N</u> ame:	P01_WidgOmatic	Properties
- 🐹 Errors/Warnings	Description:	Machine Module	*
			Y
	<u>S</u> chedule In:	🔁 MainTask	•
	🗖 Inhibit Progr	əm	
	Assigned Rou	tines	
	Main:	🛱 R00_Main	
	Fault	<none></none>	

For the Widg-O-matic application example, P01\_WidgOmatic is the Final Name.

7. Click Tags in the Import Content organizer.

- 😂 P01_WidgOmatic		Import Name	Operation	-	Final Name 🛛 🛆	2	Alias For	Data Type	Descript
Program Tags 	1	_MachineName	Create	1	_MachineName			UDT_Mach	
	1	BlankAlarmName	Create	1	BlankAlarmName			STRING	
Tags	1	CIPMotionAlar	Create	D	CIPMotionAlarmH			BOOL	
Add-On Instructions	1	CIPMotionAlar	Create	1	CIPMotionAlarmIn			BOOL	
🗃 🔤 🔚 🛗 Data Types	1	CIPMotionAlar	Create	1	CIPMotionAlarmN			STRING	
- 🔯 Errors/Warnings	1	CIPMotionAlar	Create	2	CIPMotionAlarmTri			DINT	
	1	E3AlarmHands	Create	1	E3AlarmHandshake			BOOL	
	9	E3AlarmInProc	Create	1	E3AlarmInProcess			BOOL	
	1	E3AlarmName	Create	1	E3AlarmName			STRING	
	1	E3AlarmTrigger	Create	1	E3AlarmTrigger			DINT	
	19	HMI_ClearReq	Create	1	HMI_ClearReqPB			BOOL	HMI Clea
	1	HMI_OperReqPB	Create	1	HMI_OperReqPB			BOOL	HMI Ope
	I II	UNI DDDD	C	1	UNU DDDD			DOOL	HMI Pro-

The Configure Tag References dialog box opens.

8. Replace \_ MachineName with the desired tag name of your machine.

For the Widg-O-matic application example, WidgOmatic is the tag name.

P01_WidgOmatic			Import Name	Operation	-	Final Name 🛛 🛆	1	Alias For	Data Type	Descript
- 🧭 Program Tags - 🛱 Routines	×	9	_MachineName	Create	1	Widg0matic 🗾 💌			UDT_Mach	
References		9	BlankAlarmName	Create	1	BlankAlarmName			STRING	
🖌 📈 🖉 Tags		ŋ	CIPMotionAlar	Create	L	CIPMotionAlarmH			BOOL	
Add-On Instructions		9	CIPMotionAlar	Create	1	CIPMotionAlarmIn			BOOL	· · ·
Data Types		ŋ	CIPMotionAlar	Create	1	CIPMotionAlarmN			STRING	
- 🔯 Errors/Warnings		g	CIPMotionAlar	Create	1	CIPMotionAlarmTri			DINT	
		9	E3AlarmHands	Create	1	E3AlarmHandshake			BOOL	
		9	E3AlarmInProc	Create	1	E3AlarmInProcess	•••		BOOL	
		9	E3AlarmName	Create	1	E3AlarmName	•••		STRING	
		9	E3AlarmTrigger	Create	1	E3AlarmTrigger			DINT	
		g	HMI_ClearReq	Create	D	HMI_ClearReqPB			BOOL	HMI Clea
		9	HMI_OperReqPB	Create	1	HMI_OperReqPB			BOOL	HMI Ope
	1	P	LINE Deserved	Carata	1	LUME Deserver			DOOL	HMI Pro-
	-	-			_					
	1									
						6		ок	Cancel	Help

9. Click OK.

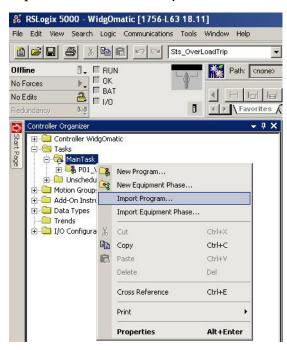
The new Machine Program appears in the Controller Organizer within the Main Task folder.

Controller Organizer	🗕 🔶 🔶
🖅 🛅 Controller WidgOmatic	
🗄 😁 Ta <u>sks</u>	
🛱 🔁 MainTask	
🖹 🤮 P01_WidgOmatic	
Program Tags	
R00 Main	
R01 PowerUP	
R02 Monitor	
R03 Control	
G Unscheduled Programs / Phase	:5
🕂 🕞 MainProgram	
🕀 🧰 Motion Groups	
🗄 🧰 Add-On Instructions	
🗄 🧰 Data Types	
Trends	
🕀 🧰 I/O Configuration	

## **Import and Configure Application Logic Modules**

Follow these steps to add preconfigured application logic to your Logix Designer project and configure it for each of your specific applications within your machine.

1. Expand the Tasks folder in your Controller Organizer, and right-click the Main Task folder.

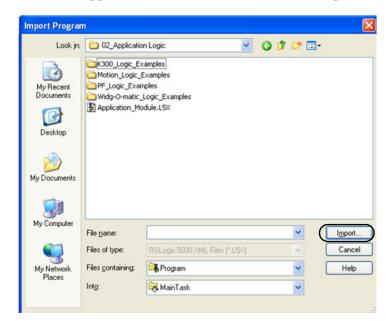


- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 02\_Application Logic folder.

	in: Controller L		] 🔾 🕫	• 📰	
	01_Machine Lo	n Logic			
My Recent Documents	03_Device Mo	dules			
Desktop					
iy Document:					
ly Document:					
My Cocuments My Computer	File <u>n</u> ame:	[			Import.
My Computer		RSLogix 5000 XML Files (*.L5X)			Cance
My Computer	File <u>n</u> ame:	RSLogix 5000 XML Files (*.L5X)		•	-

Your personal computer's harddrive path is C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

4. Select the Application\_Module.L5*x* file and click Import.



The Import Configuration dialog box opens.

Find: Find: Final Name		Eind/Replace
port Content:	Configure Prog	Demosting
MainTask     MainTask     PXX_ApplicationName     PXX_Program Tags	Import Name:	PXX_ApplicationName
Routines	Operation:	Create 💌 🗅
		References will be imported as configured in the References folders
j - 一団 Add-On Instructions Add-On Instructions	Final <u>N</u> ame:	PXX_ApplicationName   Properties
Errors/Warnings	Description:	Application Module
		<b>x</b>
	<u>S</u> chedule In:	🙀 MainTask
	🔲 In <u>h</u> ibit Progr	am
	Assigned Rou	tines
	Main:	🛱 R00_Main
	Fault	<none></none>

MainTask	Configure Progr		_	_
	Import Name:	PXX_ApplicationName		
Routines	Operation:	Create	-	
References		References will be imported configured in the Reference	as s folders	
ia Add-On Instructions	Final <u>N</u> ame:	P02_Assembly	F	Properties
- 🔯 Errors/Warnings	Description:	Application Module	*	
	<u>S</u> chedule In:	🕞 MainTask	<u> </u>	
	🔲 In <u>h</u> ibit Progra	am		
	Assigned Roul	tines		
	Main:	🔁 R00_Main		
	Fault	<none></none>		

5. Enter the desired name for your initial application in the Final Name field.

For the Widg-O-matic application example, the Final Name is P02\_Assembly.

6. Click Tags within the Import Content organizer.

The Configure Tag References dialog box opens.

<b>P02_Assembly</b>		Import Name	Operation	1	Final Name 🛛 🛆		Alias For	Data Type	Description
	1	_ApplicationNa	Create	Y	_ApplicationName			UDT_AppS	
	1	_MachineName	Create	7	_MachineName			UDT_Mach	
Tags	19	ModuleAlarmH	Use Existing		ModuleAlarmHand			BOOL	
Add-On Instructions	1	ModuleAlarmIn	Use Existing		ModuleAlarmInPro			BOOL	
Data Types	1	ModuleAlarmN	Use Existing		ModuleAlarmName			STRING	
🔯 Errors/Warnings	9	ModuleAlarmTri	Use Existing		ModuleAlarmTrigger			DINT	
	•								J
					]	i i i i i i i i i i i i i i i i i i i	ОК	Cancel	Help

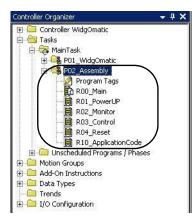
7. Replace the \_ApplicationName and \_MachineName with the desired tag names of your application and machine.

For the Widg-O-matic application example, Assembly was entered as the ApplicationName and WidgOmatic was entered as the MachineName.

<b>P02_Assembly</b>	-		Import Name	Operation	-10	Final Name 🖉		Alias For	Data Type	Description
- 🧭 Program Tags - 🙀 Routines		19	_ApplicationNa	Create	4	Assembly	1		UDT_AppS	
		1	_MachineName	Use Existing	1	WidgOmatic			UDT_Mach	
🖉 Tags		1	ModuleAlarmH	Use Existing		ModuleAlarmHand			BOOL	
Add-On Instructions		1	ModuleAlarmIn	Use Existing		ModuleAlarmInPro			BOOL	
Data Types		1	ModuleAlarmN	Use Existing		ModuleAlarmName			STRING	
🔞 Errors/Warnings		19	ModuleAlarmTri	Use Existing		ModuleAlarmTrigger			DINT	
	•									

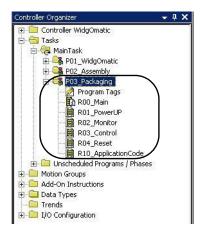
#### 8. Click OK.

The new application program appears in the Controller Organizer within the Main Task folder.



9. Repeat step 1 through step 8 for each application within your machine.

For the Widg-O-matic application example, a second application was entered named P03\_Packaging.



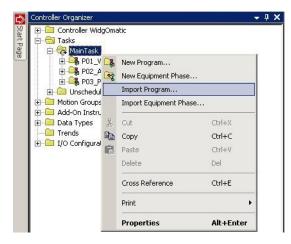
## Import and Configure Device Logic Modules

Follow these steps to add preconfigured device logic to your Logix Designer project and configure it for each of your specific devices within your machine.

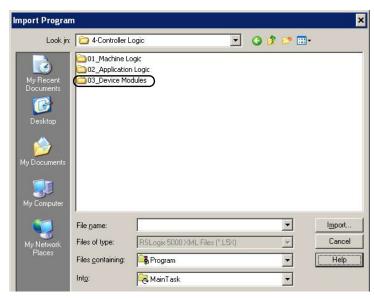
#### Import and Configure CIP Motion or Sercos Drive Modules

Follow these steps to add preconfigured CIP Motion and sercos interface drive device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.



Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

**4.** Select the Device Module program file that fits your initial CIP Motion or sercos interface drive within your machine based on the Motion Drives Logic Modules table.



#### **Motion Drives Logic Modules**

Device Module Program File	Supported Devices
CIPMotion_Drive_Module.L5X	Kinetix 6500, Kinetix 5500, and PowerFlex 755 configured as a CIP Motion drive.
CIPMotion_FdbkOnly_Module.L5X	Auxiliary feedback-only axis on CIP Motion drives.
SERCOS_Drive_Module.L5X	Kinetix 2000, Kinetix 6000, Kinetix 6200, and Ultra3000 sercos interface drives
SERCOS_FdbkOnly_Module.L5X	Auxiliary feedback-only axis on sercos interface drives.
SERCOS_IDM_ParentIAM_Drive_Module.L5X	Kinetix 6000 and Kinetix 6200 sercos IAM interface drive when used with the Kinetix 6000M system
Virtual_Axis_Module.L5X	Virtual axis for CIP Motion or sercos interface drives configuration

For the Widg-O-matic application example, the CIPMotion\_Drive\_Module.L5X program file was selected for the first Kinetix 6500 CIP Motion drive.

5. Click Import.

The Import Configuration dialog box opens.

Import Configuration				×
Find: Find Within: Final Name	- <u>48</u> 44	<u>Find/Replace</u>		
Import Content:				
🙀 MainTask	Configure Progr	am Properties		
PXX_ModuleName	Import Name:	PXX_ModuleName		
	Operation:	Create	- L	
References		References will be importe configured in the Reference	d as ses folders	
Add-On Instructions	Final <u>N</u> ame:	PXX_ModuleName	Properties	
- 🛛 Errors/Warnings*	Description:	CIP Motion Drive Module (AXIS_CIP_DRIVE)	A	
			Y	
	<u>S</u> chedule In:	🕞 Main Task	<b>•</b>	

6. Enter the desired name for your initial Device in Final Name field.

MainTask	Configure Progra	am Properties	_	_
Program Tags	Import Name:	PXX_ModuleName		
Routines	Operation:	Create	-	2
		i References will be imported a configured in the References	s folders	
j - 一団 Add-On Instructions Add-On Instructions	(Final <u>N</u> ame:	P04_Gantry_X_Drive	-	Properties
Errors/Warnings*	Description:	CIP Motion Drive Module (AXIS_CIP_DRIVE)	*	
			Ŧ	
	<u>S</u> chedule In:	🕞 MainTask	•	
	💭 Inhibit Program	1.9		

For the Widg-O-matic application example, P04\_Gantry\_X\_Drive is the Final Name.

7. Click Tags within the Import Content organizer.

The Configure Tag References dialog box opens.

4_Gantry_X_Drive		Import Name	Operation	1	Final Name 🛛 🛆		Alias For	Data Type
Program Tags Routines	E	_AxisName	Create		AxisName			AXIS_CIP_DRIVE
References	1		Create	1	_AxisName_Ctrl			UDT_ServoCtrl
Tags	f	_AxisName_FP	Create	3	AxisName_FP			CIP_Faceplate_A0
On Instructions	1	_MachineName	Create		(_MachineName			UDT_MachCtrl
ta Types	f	_ModuleName	Create		(_ModuleName			UDT_ModuleStatu
gs*	۴ (	_MotionGroupName	Discard	1	_MotionGroupName			MOTION_GROUP
	1	CIPMotionAlarmHandshake	Use Existing		CIPMotionAlarmHandshake	•••		BOOL
		CIPMotionAlarmInProcess	Use Existing		CIPMotionAlarmInProcess			BOOL
	f	CIPMotionAlarmName	Use Existing		CIPMotionAlarmName			STRING
	1	CIPMotionAlarmTrigger	Use Existing		CIPMotionAlarmTrigger			DINT
	1	ModuleAlarmHandshake	Use Existing		ModuleAlarmHandshake			BOOL
	1	ModuleAlarmInProcess	Use Existing		ModuleAlarmInProcess			BOOL
	f	ModuleAlarmName	Use Existing		ModuleAlarmName	•••		STRING
		ModuleAlarmTrigger	Use Existing		ModuleAlarmTrigger			DINT
	4			1				

- 8. Replace Final Tag Names with associated axis, machine, drive, and motion group names that you have already configured.
  - a. Replace \_AxisName of \_AxisName, \_AxisName\_Ctrl, and AxisName\_FP tags with the name of the axis for your drive.
  - b. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - c. Replace \_ModuleName of \_ModuleName tag with the device name of your drive.
  - d. Replace \_MotionGroupName of \_MotionGroupName tag with the motion group name within your project.

RIVE Ctrl
ate_AOI
Dtd
eStatus
ROUP
-

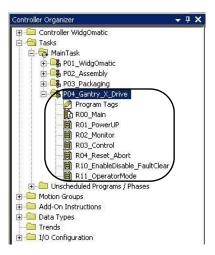
For the Widg-O-matic application example, these are the final tag names.

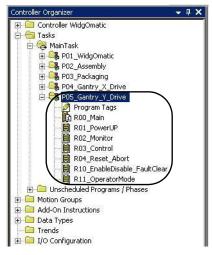
9. Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.

For the Widg-O-matic application example, the new program named P04\_Gantry\_X\_Drive appears in Controller Organizer.

**10.** Repeat <u>step 1</u> through <u>step 9</u> for each motion drive in your machine.



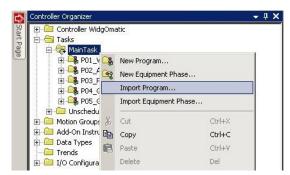


For the Widg-O-matic application example, a second Kinetix 6500 CIP Motion drive device program named P05\_Gantry\_Y\_Drive was imported and configured.

#### Import and Configure PowerFlex Standard Drive Modules

Follow these steps to add preconfigured PowerFlex standard drive device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



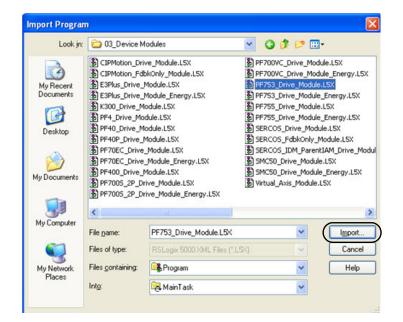
- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.



Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

**4.** Select the Device Module program file that fits your initial PowerFlex standard drive within your machine based on the PowerFlex Drives Logic Modules table.



#### **PowerFlex Drives Logic Modules**

Device Module Program File	Supported Devices
PF4xx_Drive_Module.L5X	PowerFlex 4-class standard drives (for example, PF40P_Drive_Module.L5X supports PowerFlex 40P Drives).
PF7 <i>xxx</i> _Drive_Module.L5X	PowerFlex 7-class standard drives (for example, PF70EC_Drive_Module.L5X supports PowerFlex 70EC Drives).
PF70EC_Drive_Module_Energy.L5X	PowerFlex 70EC drives with additional logic to support an energy data tab on the HMI faceplate.
PF700S_2P_Drive_Module_Energy.L5X	PowerFlex 700S_2P drives with additional logic to support an energy data tab on the HMI faceplate.
PF700VC_Drive_Module_Energy.L5X	PowerFlex 700VC drives with additional logic to support an energy data tab on the HMI faceplate.
PF753_Drive_Module.L5X	PowerFlex 753 standard drives
PF753_Drive_Module_Energy.L5X	PowerFlex 753 standard drives with additional logic to support an energy data tab on the HMI faceplate.
PF755_Drive_Module.L5X	PowerFlex 755 drive configured as a standard drive.
PF755_Drive_Module_Energy.L5X	PowerFlex 755 standard drives with additional logic to support an energy data tab on the HMI faceplate.
PF525_Drive_Module.L5X	PowerFlex 525 EENET drive.

For the Widg-O-matic application example, PF753\_Drive\_Module.L5X program file was selected for the only PowerFlex drive in the machine.

5. Click Import.

Import Configuration           Find:           Find Within: Final Name	<u></u>		×
Import Content:	Configure Progr	an Branadias	
Main Task	Import Name: Operation: Final Name:	Ptick ModuleName  Create  Create  Create  Create  Ptick Properties  Ptick ModuleName  Properties  Ptick Pti	
Components	Description: Schedule In:	PowerFlex 753 Drive Module	

The Import Configuration dialog box opens.

6. Enter the desired name for your initial device in Final Name field.

For the Widg-O-matic application example, the Final Name is P06\_Conveyor\_Drive.

7. Click Tags within the Import Content organizer.

🗟 MainTask	Configure Progr	am Properties	
PO6_Conveyor_Drive	Import Name:	PXX_ModuleName	
	Operation:	Create	- 1
References		References will be imported as configured in the References for	olders
しまた Add-On Instructions 一間 Data Types	Final <u>N</u> ame:	P06_Conveyor_Drive	▼ Properties
C Other Components	Description:	PowerFlex 753 Drive Module	
			-
	<u>S</u> chedule In:	🕞 MainTask	•
	🔲 Inhibit Progra	m	

The Configure Tag References dialog box opens.

	Jonhg	ure Tag References					
_Drive [		Import Name	Operation	1	Final Name 🛛 🗠	👚 Alias For	Data Type
	۳ ۱	_DriveName:I	Undefined	1	DriveName:		
	٦ ا	_DriveName:0	Undefined		_DriveName:0		
	IJ	_DriveName_FP	Create		DriveName_FP		PFlex_753_20COMM
structions	1	_MachineName	Create		_MachineName		UDT_MachCtrl
es	1	_ModuleName	Create		_ModuleName		UDT_ModuleStatus
nponents	1	ModuleAlarmHandshake	Use Existing		ModuleAlarmHandshake		BOOL
	_ 1	ModuleAlarmInProcess	Use Existing		ModuleAlarmInProcess		BOOL
	1	ModuleAlarmName	Use Existing		ModuleAlarmName		STRING
	_ 1	ModuleAlarmTrigger	Use Existing		ModuleAlarmTrigger		DINT
	1	PowerFlexAlarmHandshake	Use Existing		PowerFlexAlarmHandshake		BOOL
	1	PowerFlexAlarmInProcess	Use Existing		PowerFlexAlarmInProcess		BOOL
	_ 1	PowerFlexAlarmName	Use Existing		PowerFlexAlarmName		STRING
	19	PowerFlexAlarmTrigger	Use Existing		PowerFlexAlarmTrigger		DINT

- 8. Replace Final Tag Names with the associated drive and machine names you have already configured.
  - a. Where applicable, replace \_DriveName with the name of PowerFlex drive in I/O tree.
  - b. Replace \_DriveName of \_DriveName:I, \_DriveName:O, and \_DriveName\_FP tags with the name your PowerFlex drive.
  - c. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - d. Replace \_ModuleName of \_ModuleName tag with the device name of your drive.
  - e. If a device module with energy support was selected, there will be additional tags named \_DriveName\_BEO (base energy object). Replace \_DriveName in all of these tags with the name of your PowerFlex drive.

For the Widg-O-matic example, \_DriveName\_BEO was replaced with ConveyorDrive\_BEO.

S PXX_ModuleName			Import Name	Operation	1	Final Name	0 3	Alias For	Data Type
- 2 Program Tags - 2 Routines	٣	9	_DriveName:I	Undefined		_DriveName:I			
- References	٣	9	_DriveName:0	Undefined	1	_DriveName:0	1		
🖉 Tags		9	_DriveName_B	Create	Y	_DriveName_BE0			UDT_BEO
- Add-On Instructions		1	_DriveName_B	Create	4	_DriveName_BEOmsg_Get_Attr_kW		l	MESSAGE
Data Types		1	_DriveName_B	Create	7	_DriveName_BEOmsg_Get_Attr_kWh			MESSAGE
Other Components     Errors/Warnings		1	_DriveName_FP	Create		_DriveName_FP			PFlex_753_20COMM_A0
Citorar in Grange		1	_MachineName	Create		_MachineName			UDT_MachCtrl
		1	_ModuleName	Create		_ModuleName			UDT_ModuleStatus
		1	ModuleAlarmH	Use Existing		ModuleAlarmHandshake			BOOL
		9	ModuleAlarmin	Use Existing		ModuleAlarmInProcess			BOOL
		Ŋ	ModuleAlarmN	Use Existing		ModuleAlarmName			STRING
		9	ModuleAlarmTri	Use Existing		ModuleAlarmTrigger			DINT
		2	PowerFlexAlar	Use Existing		PowerFlexAlarmHandshake			BOOL

For the Widg-O-matic application example, the following tag names were entered.

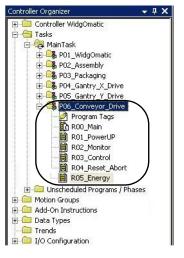
P06_Conveyor_Drive		Import Name	Operation	1	Final Name 🛛 🛆	AI	as For Data Type
Program Tags	× 1	_DriveName:I	Use Existing	1	Conveyor_Drive:I		AB:PowerFlex753F0E5
References	× 9	_DriveName:0	Use Existing		Conveyor_Drive:0		AB:PowerFlex753A6337.
Tags	× 1	_DriveName_FP	Create	7	Conveyor_Drive_FP		PFlex_753_20COMM_A0I
Add-On Instructions	× 9	_MachineName	Create	1	WidgOmatic		UDT_MachCtrl
Data Types	* 9	_ModuleName	Create	1	Conveyor_Drive		UDT_ModuleStatus
Other Components     Errors/Warnings	1	ModuleAlarmHandshake	Use Existing		ModuleAlarmHandshake		BOOL
Choisi wanings	9	ModuleAlarmInProcess	Use Existing		ModuleAlarmInProcess		BOOL
	1	ModuleAlarmName	Use Existing		ModuleAlarmName		STRING
	1	ModuleAlarmTrigger	Use Existing		ModuleAlarmTrigger		DINT
	9	PowerFlexAlarmHandshake	Use Existing		PowerFlexAlarmHandshake		BOOL
	1	PowerFlexAlarmInProcess	Use Existing		PowerFlexAlarmInProcess		BOOL
	9	PowerFlexAlarmName	Use Existing		PowerFlexAlarmName		STRING
	I II	Danier Flanklam Talaan	Use Distance		Dame Claudlam Trianag		DINT

9. Click Other Components under the Import Content organizer.

A MainTask	Lo	nfigure Compon	ent Heference	28		
Program Tags		Import Name	Operation	Final Name	10	Class Name
Program Tags	*	_DriveName	Undefined		$\mathcal{I}$	Module
References						
Tags						
Data Types						
Other Components						
- 🔯 Errors/Warnings						
	_					
			(		_	
				OK	C	ancel He

- 10. The Configure Components References dialog box opens.
- 11. Replace \_DriveName within the Final Name field with the name of your PowerFlex drive in the I/O tree.
- 12. Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.



For the Widg-O-matic application example, the new program named P06\_ Conveyor\_Drive appears in Controller Organizer.

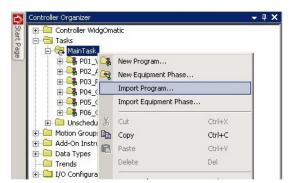
If a device module with energy support was selected, the program contains an additional routine named R05\_Energy. Refer to Set MSG Path in the E3 Plus Energy Monitoring Routine on <u>page 81</u>, for more information.

13. Repeat step 1 through step 12 for each PowerFlex drive in your machine.

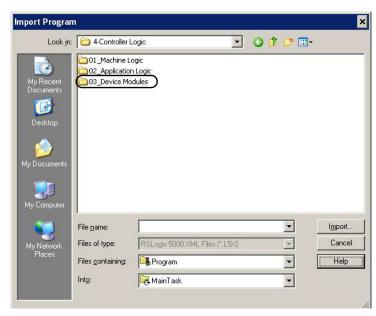
### Import and Configure Kinetix 300 EtherNet/IP Motion Drive Modules

Follow these steps to add preconfigured Kinetix 300 EtherNet/IP motion drive device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.



Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

**4.** Select the K300\_Drive\_Module.L5X program file for your initial Kinetix 300 Ethernet Motion Drive within your machine.



For the Widg-O-matic application example, K300\_Drive\_Module.L5X program file was selected as the only Kinetix 300 drive in the machine.

5. Click Import.

The Import Configuration dialog box opens.

Import Configuration					×
Find: Find Within: Final Name	✓ ▲ ▲ ▲ ▲	<u>Find/Replace</u>			
I <u>m</u> port Content:					
😽 🧔 MainTask	Configure Progr	am Properties	_		_
PXX_ModuleName	Import Name:	PXX_ModuleName			
Routines	Operation:	Create	- 1		
		(i) References will be imported a configured in the References	s folders		
Add-On Instructions	Final <u>N</u> ame:	PXX_ModuleName	▼ Pro	perties	
♥ Other Components - 図 Errors/Warnings	Description:	Ethernet IP K300 Drive Module	-		
			-		

6. Enter the desired name for your initial Device in Final Name field.

🔁 MainTask	Configure Prog	am Properties	
Program Tags	Import Name:	PXX_ModuleName	
	Operation:	Create	
Tags		(i) References will be imported as configured in the References folders	
Add-On Instructions	Final <u>N</u> ame:	P07_Diverter_Drive	Properties.
Other Components     Errors/Warnings	Description:	Ethernet IP K300 Drive Module	1
		*	

For the Widg-O-matic application example, the Final Name is P07\_Diverter\_Drive.

7. Click Tags within the Import Content organizer.

The Configure Tag References dialog box opens.

BO7_Diverter_Drive		3295				-		
Program Tags		Import Name	Operation	-6	Final Name 🖉 🖉		Alias For	Data Type
	۴ ۱	_DriveName:I	Undefined	7	_DriveName:I			
References	* 1	_DriveName:0	Undefined	1	_DriveName:0			
🛃 Tags	1		Create	1	_DriveName_Ctrl		1	UDT_K300_Ctrl
	1	_DriveName_FP	Create	L	_DriveName_FP		-	K300_Faceplate_A0I
Data Types	1	_DriveName_MSG_ClrFlt	Create	1	_DriveName_MSG_ClrFlt		1	MESSAGE
Other Components     Errors/Warnings	1	_DriveName_MSG_DriveFLT	Create	1	_DriveName_MSG_DriveFLT		1	MESSAGE
Circles/ warnings	1	_DriveName_MSG_SetAbo	Create	1	_DriveName_MSG_SetAbortDecel		1	MESSAGE
	1	DriveName_MSG_SetDriv	Create	1	_DriveName_MSG_SetDriveMode		1	MESSAGE
	1	_DriveName_MSG_SetupI	Create	1	_DriveName_MSG_SetupIndex		1	MESSAGE
	1	_DriveName_MSG_SetVel	Create	1	_DriveName_MSG_SetVelAccel		•	MESSAGE
	1	_DriveName_MSG_SetVel	Create	1	_DriveName_MSG_SetVelDecel		1	MESSAGE
		_DriveName_MSG_VelRat	Create	7	DriveName_MSG_VelRateEn		1	MESSAGE
	1		Create	(	_MachineName		1	UDT_MachCtrl
	1	_ModuleName	Create	1	_ModuleName	-	1	UDT_ModuleStatus
	1	K300AlarmHandshake	Use Existing		K300AlarmHandshake		1	BOOL
	1	K300AlarmInProcess	Use Existing		K300AlarmInProcess			BOOL
		K300AlarmName	Use Existing		K300AlarmName		1	STRING
	1		Use Existing		K300AlarmTrigger		1	DINT

- 8. Replace the Final Tag Names with the associated drive and machine names you have already configured.
  - a. Replace \_DriveName of \_DriveName:I, \_DriveName:O, \_DriveName\_Ctrl, \_DriveName\_FP and (8) \_DriveName\_MSG\_*xxxxx* tags with the name your Kinetix 300 drive.
  - b. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - c. Replace \_ModuleName of \_ModuleName tag with the device name of your drive.

For the Widg-O-matic application example, the following tag names were entered.

🚑 MainTask	Lonfigu	re Tag References						1
P07_Diverter_Drive		Import Name	Operation		Final Name 🗠		Alias For	Data Type
- 🧭 Program Tags - 🙀 Routines	×IJ	_DriveName:I	Use Existing	1	Diverter_Drive:I			AB:K300:1:0
References	_ 1	_DriveName:0	Use Existing	6	Diverter_Drive:0	•••	(	AB:K300:0:0
🛃 Tags	× 9	_DriveName_Ctrl	Use Existing		Diverter_Drive_Ctrl			UDT_K300_Ctrl
	× 9	_DriveName_FP	Use Existing	1	Diverter_Drive_FP			K300_Faceplate_A0I
	× 1	_DriveName_MSG_ClrFlt	Use Existing	X	Diverter_Drive_MSG_ClrFlt			MESSAGE
Other Components     Errors/Warnings	× 1	_DriveName_MSG_DriveFLT	Use Existing	1	Diverter_Drive_MSG_DriveFLT			MESSAGE
	× 9	_DriveName_MSG_SetAbo	Use Existing	-	Diverter_Drive_MSG_SetAbortDecel		i.	MESSAGE
	× 1	_DriveName_MSG_SetDriv	Use Existing	*	Diverter_Drive_MSG_SetDriveMode	•••		MESSAGE
	× 9	_DriveName_MSG_SetupI	Use Existing	*	Diverter_Drive_MSG_SetupIndex			MESSAGE
	_ 1	_DriveName_MSG_SetVel	Use Existing	*	Diverter_Drive_MSG_SetVelAccel			MESSAGE
	× 9	_DriveName_MSG_SetVel	Use Existing	*	Diverter_Drive_MSG_SetVelDecel			MESSAGE
	* 9	_DriveName_MSG_VelRat	Use Existing	1	Diverter_Drive_MSG_VelRateEn		0	MESSAGE
	× 9	_MachineName	Use Existing	1	WidgOmatic		1	UDT_MachCtrl
	× 1	_ModuleName	Use Existing	(	Diverter_Drive			UDT_ModuleStatus
	9	K300AlarmHandshake	Use Existing		K300AlarmHandshake		1	BOOL
	1	K300AlarmInProcess	Use Existing		K300AlarmInProcess			BOOL
	1	K300AlarmName	Use Existing		K300AlarmName			STRING
	9	K300AlarmTrigger	Use Existing		K300AlarmTrigger			DINT

9. Click Other Components within the Import Content organizer.

The Configure Components References dialog box opens.

🚑 MainTask	Configure Compo	nent Reference	s	~ ~
Pogram Tags	Import Name	Operation	Final Name	Class Name
🔤 🖉 Program Lags	ChriveName	Undefined	_DriveName	Module
🛵 🛛 🖉 Tags				
→) グ Tags 密 Add-On Instructions 쀖 Data Types				
Add-On Instructions				

**10.** Replace \_DriveName in the Final Name field with the name of your Kinetix 300 drive.

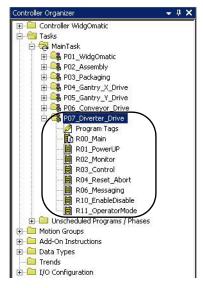
For the Widg-O-matic application example, Diverter\_Drive is the Final Name.

P07_Diverter_Drive	Import Name	Operation	Final Name	Class Name
- 🧭 Program Tags - 🛐 Routines	CiveName	Undefined	Diverter_Drive	Module
References		12		
🖉 Tags				
- 🔄 Add-On Instructions				
🛗 Data Types				
Other Components     Frrors/Warnings*				
Errors/warnings"				

11. Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.

For the Widg-O-matic application example, the new program named P07\_Diverter\_Drive appears in Controller Organizer.

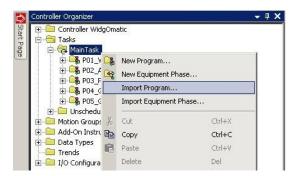


12. Repeat step 1 through step 11 for each Kinetix 300 drive in your machine.

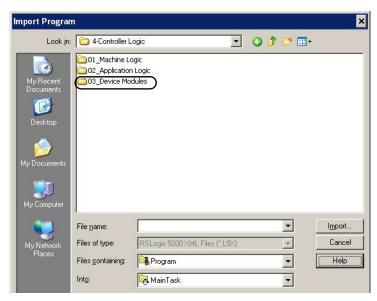
## Import and Configure E3 Plus Device Modules

Follow these steps to add preconfigured E3 Plus device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



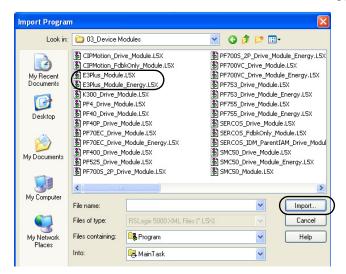
- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.



Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

4. Select E3Plus\_Module.L5X or E3Plus\_Module\_Energy.L5X if energy support is required.



5. Click Import.

The Import Configuration dialog box opens.

Import Configuration		
🗶 🎽 Find: Find Within: Final Name	✓ ▲ ▲	Eind/Replace
Import Content:		
😽 MainTask	Configure Progra	m Properties
PXX_ModuleName PXX_ModuleName Program Tags	Import Name:	PXX_ModuleName
	Operation:	Create
References		References will be imported as configured in the References folders
🔨 🔤 Add-On Instructions	Final <u>N</u> ame:	PX_ModuleName Properties
Data Types     Other Components		E3 Plus Module v01
<ul> <li>Errors/Warnings</li> </ul>	Description:	E 3 Plus Module VUI
	<u>S</u> chedule In:	
	🔲 In <u>h</u> ibit Program	🖳 MainTask 🛛 👻
	Assigned Routir	nes
	Main:	🔁 R00_Main
	Fault	<none></none>
		OK Cancel Help

6. Enter the desired name for your initial Device in the Final Name field.

Im	port Content:			
	-🤯 MainTask	Configure Program	n Properties	
	P11_E3Plus	Import Name:	PXX_ModuleName	
	- 👪 Routines	Operation:	Create	✓ □
*			(i) References will be importe configured in the Referen	ed as ces folders
۲	Add-Un Instructions      Minimum Data Types	Final <u>N</u> ame:	P11_E3Plus	Properties
۲	Other Components     Other Components     Other Components	<u>D</u> escription:	E3 Plus Module v01	~
	Chois/Wahnings			<b>V</b>
		<u>S</u> chedule In:	🕞 MainTask	~
		🔲 In <u>h</u> ibit Program		

In this example, the Final Name is P11\_E3Plus.

7. Click Tags within the Import Content organizer.

8. The Configure Tag References dialog box opens.

Import Content:		
🙀 MainTask	Configure Tag References	
P11_E3Plus	Import Name Op	eration 🔄 Final Name
Program Tags	🝸 🖞 _DeviceName:I Un	definedDeviceName:I
	🝸 🖞 _DeviceName:0 Un	defined 🗳 _DeviceName:0
🝸 🔤 🖓 Tags	Tag '_DeviceName:O' is not defined in import file or project. Imported logic references to tag will not veri	DeviceName_FP
Add-On Instructions		DeviceName_MSG
♥ Data Types		e Existing 🔟 MachineName 🔵
Errors/Warnings		eateModuleName
	E3AlarmHandshake Us	e Existing 🏼 🌛 E3AlarmHandshake

- 9. Replace Final Tag Names with the associated drive and machine names you have already configured.
  - a. Replace \_DeviceName of \_DeviceName:I, \_DeviceName:O, \_DeviceName\_FP, and \_DeviceName\_MSG tags with the name of your E3 Plus device.
  - b. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - c. Replace \_ModuleName of \_ModuleName tag with the device name of your E3 Plus device. If a device module with energy support was selected, there will be additional tags named \_DeviceName\_BEO.
  - d. Replace \_DeviceName in all of these tags with the name of your E3 Plus device.

Impo	Import Content:									
	🔁 MainTask	Con	figu	re Tag References				-		
	P11_E3Plus			Import Name	Operation		Final Name		<u></u>	Data Type
	🧭 Program Tags		IJ	_DeviceName:I	Use Existing		E3PLUS:I		•••	AB:E3PlusGen
			IJ	_DeviceName:0	Use Existing		E3PLUS:0		•••	AB:E3PlusGen
*	Tags		1	_DeviceName_BEO	Create		_DeviceName_BEO	-	••••	UDT_BEO
-	Add-On Instructions		IJ	_DeviceName_BEOmsg_Get_Status_0	Create		_DeviceName_BEOmsg_Get_Status_Object		•••	MESSAGE
*	- 👪 Data Types - 🗃 Other Components		IJ	DeviceName_BEOMSG_Read_Data	Create		_DeviceName_BEOMSG_Read_Data		•••	INT[20]
<b>`</b>	Errors/Warnings		IJ	_DeviceName_BEOMSG_Read_Request	Create		_DeviceName_BEOMSG_Read_Request		••••	INT[20]
			1	_DeviceName_FP	Create		E3Plus_FP		•••	E3Plus_Comm:

10. Click Other Components within the Import Content organizer.

Impo	ort Content:							
	😽 MainTask	C	onfigure Componei	nt References				
	Bill_E3Plus	Г	Import Name	Operation	Final Name	Δ	Class Name	
	🥂 Program Tags 	-	DeviceName	Undefined	DeviceName	-	Module	4
		-	Deviceivaille	ondenned	Devicertanie	-	Module	
	References							
<u>₹</u>	🖉 Tags							
-6								
	🕅 Data Types							
۲.	Other Components							
	🔞 Errors/Warnings							

The Configure Component References dialog box opens.

- 11. Replace the Final name (\_DeviceName) with the name of your E3 Plus device.
- 12. Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.



If a device module with energy support was selected, the program will contain an additional routine named R05\_Energy. Refer to Set MSG Path in the E3 Plus Energy Monitoring Routine on <u>page 81</u>, for more information.

#### Import and Configure E300 Device Modules

Follow these steps to add preconfigured E300 device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.

Look jn:	🌗 4-Controller L	ogic 🔹	G 🤌 📂 🖽 🗸	
An	Name	*	Date modified	Туре
Recent Places	📙 01_Machine	Logic	4/8/2015 4:14 PM	File folde
Recent Places	🔒 02_Applicat	ion Logic	4/8/2015 4:14 PM	File folde
	03_Device N	Aodules	4/8/2015 4:14 PM	File folde
Desktop				
<b>F</b>				
<b>6</b>				
Libraries				
Computer				
	•			,
				Import
Natural	File <u>n</u> ame:			
(till) Network	File <u>n</u> ame: Files of type:	Logix Designer XML Files (*.L5X)	-	Cancel
(tille) Network	100 0 0 To 2000	Logix Designer XML Files (*.L5X)	-	Cancel Help

Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

4. Select E300\_Module.L5X or E300\_Module\_Energy.L5X if energy support is required.



5. Click Import.

The Import Configuration dialog box opens.

Import Configuration					X
Find:	- 🛃 🖧	Eind/Replace			
Import Content:					
- 🧖 MainTask	Configure Progra	m Properties			
PXX_ModuleNa		PXX_ModuleName			
	Operation:	Create	-		
♥ References Tags		(i) References will be imported as configured in the References for	olders		
- 🗟 Add-On Ir - 🕅 Data Type		PXX_ModuleName		Properties	
		E300 Module v02 Support for E300 v3,4, and 5	*		
	≦chedule In:	RainTask	•		
	🕅 In <u>h</u> ibit Program				
	Assigned Routi	nes			
	Main:	R00_Main			
	Fault:	<none></none>			
				OK Cancel Help	
Ready					

- Import Configuration Eind/Replace... 🗶 💃 Find: Find Within: Final Name Import Content: MainTask PXX\_ModuleName Program Tags Configure Program Properties PXX\_ModuleName Import Name: Program Tags -Operation: Create (i) References will be imported as configured in the References folders Add-On Instructions Final Name: P11\_E300 ▼ Properties... - 🕅 Data Types - 🏕 Other Components E300 Module v02 Support for E300 v3,4, and 5 Description: The American Street Provide Street P Schedule In: 🛃 Main Task • Inhibit Program Assigned Routines Main: R00\_Main Fault: <none> OK Cancel Help Ready
- 6. Enter the desired name for your initial Device in the Final Name field.

In this example, the Final Name is P11\_E300.

- 7. Click Tags within the Import Content organizer.
- 8. The Configure Tag References dialog box opens.

#	🍒 Find:	+	A A Eind/R	eplace						
	Find Within: Final Name									
Imp	ort Content:									
	🚑 MainTask	Config	ure Tag References							
			Import Name	Operation		Final Name 🗠	<b>P</b>	Alias For	Data Type	Descript
		۲ 1	_DeviceName:I	Undefined	1	_DeviceName:I				
	References	۳ ۱	_DeviceName:0	Undefined		_DeviceName:0				
٣	🛃 Tags		ag '_DeviceName:O'				•••		E300_rev0	
	Add-On Instructions		roject. Imported logi	c references t	o ta	g will not	•••		UDT_Mac	
*	Data Types     Other Components		erify.	USC Existing	-		•••		UDT_Mod	
7	Other Components     Errors/Warnings	2	E 300AlarmHa	Use Existing		E 300AlarmHands			BOOL	
		1	E 300AlarmInPr	Use Existing		E300AlarmInProc			BOOL	
		2	E300AlarmName	Use Existing		E300AlarmName	••••		STRING	
		2	E 300AlarmTrig	Use Existing		E 300AlarmTrigger			DINT	
		2	ModuleAlarmH	Use Existing		ModuleAlarmHan	•••		BOOL	
		2	ModuleAlarmIn	Use Existing		ModuleAlarmInPr	•••		BOOL	
		2	ModuleAlarmN	Use Existing		ModuleAlarmName			STRING	
			T	III.		84-36-3-81T-1			DINT	
								OK	Cancel	Help

- 9. Replace Final Tag Names with the associated drive and machine names you have already configured.
  - a. Replace \_DeviceName of \_DeviceName:I, \_DeviceName:O, \_DeviceName\_FP, and \_DeviceName\_MSG tags with the name of your E300 device.
  - b. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - c. Replace \_ModuleName of \_ModuleName tag with the device name of your E300 device. If a device module with energy support was selected, there will be additional tags named \_DeviceName\_BEO.

d. Replace \_DeviceName in all of these tags with the name of your E300 device.

4	🍒 Find:	Ŧ	Eind/R	eplace						
	Find Within: Final Name									
mpo	ort Content:									
	- 🔁 MainTask	Config	ure Tag References							
	PXX_ModuleName		Import Name	Operation	1	Final Name 🗠	7	Alias For	Data Type	Descrip
	Program Tags	* 8	_DeviceName:I	Use Existing	0	E300:1	••••		AB:E300:1:2	
	References	* •	_DeviceName:0	Use Existing		E300:0			AB:E300:0:0	
2	- 🧭 Tags	× 9	_DeviceName	Create	1	E300[FP 🚽			E300_rev0	
	Add-On Instructions	1	_MachineName	Use Existing		_MachineName			UDT_Mac	
	Data Types	1	_ModuleName	Use Existing		_ModuleName	•••		UDT_Mod	
7	Other Components  Total Components  Other Compo	1	E 300AlarmHa	Use Existing		E 300AlarmHands			BOOL	
	Chronsy warnings	1	E 300AlarminPr	Use Existing		E300AlarmInProc			BOOL	
		1	E 300AlarmName	Use Existing		E300AlarmName	••••		STRING	
		1	E 300AlarmTrig	Use Existing		E 300Alarm Trigger			DINT	
		1	ModuleAlarmH	Use Existing	-	ModuleAlarmHan			BOOL	
		1	ModuleAlarmIn	Use Existing		ModuleAlarmInPr			BOOL	
			ModuleAlarmN	Use Existing		ModuleAlarmName	•••		STRING	
		1	T	III.					DINIT	
					-		-			
							_	ок		

10. Click Other Components within the Import Content organizer.

The Configure Component References dialog box opens.

5 5	Find: Find Within: Final Name	- 🎢 🐴	Eind/Replace	]					
port Cor	itent:								
	lainTask	Configure Compone	nt References						
I	PXX_ModuleName	Import Name	Operation	Final Name	4	Class Name	1		
	Program Tags	CeviceName	Undefined	E300	-	Module	l		
- <b>R</b> E	Tags     Tags     Tags     Data Types     Other Components     Tors/Warnings			Ethe	-EN3 <sup>-</sup> ernet 1756- 193-E	Machine_1 IR My_Ethernet EN3TR My_Eth CM-ETR/A E30 NENCATR/A 0	met		
						0		Cancel	Help

- 11. Replace the Final name (\_DeviceName) with the name of your E300 device.
- **12.** Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.

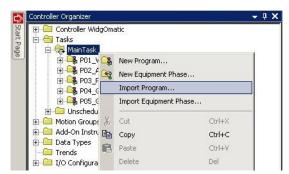


If a device module with energy support was selected, the program will contain an additional routine named R05\_Energy. Refer to Set MSG Path in the E3 Plus Energy Monitoring Routine on <u>page 81</u>, for more information.

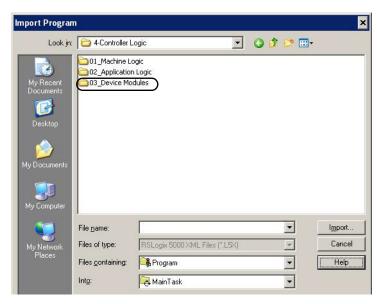
### Import and Configure SMC-50 Soft Starter Device Modules

Follow these steps to add preconfigured SMC-50 soft-starter device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



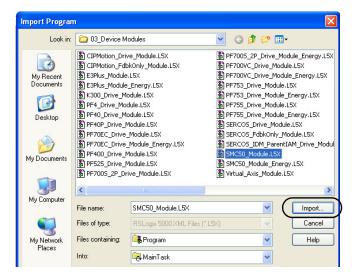
- 2. Choose Import Program.
- **3.** Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.



Your personal computer's harddrive path is

C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller Logic.

4. Select SMC50\_Module.L5X or SMC50\_Module\_Energy.L5X if energy support is required.



- 5. Click Import.
- 6. The Import Configuration dialog box opens.

Find: Find: Find Name	<u> </u>	Find/Replace
Import Content:	Configure Prog	ram Properties
MainTask Program Tags Program Tags Routines References Ad4On Instructions Data Types Other Components Concernents	Import Name: Operation: Final Name: Description:	PX_ModuleName Create Create Create Create Configured in the References folders PX_ModuleName Properties SMC:50 Module v01
	Schedule In:	🔫 MainTask 🛛

7. Enter the desired name for your initial Device in Final Name field.

Import	Content:	Configure Progra	m Properties		
-9	Amin Task Top SMC50 Program Tags	Import Name:	PXX_ModuleName		
*	Program Lags	Operation:	Create (i) References will be imported configured in the Referen	ed as ces folders	
		Final <u>N</u> ame:	P10_SMC50	Properties	
*	Other Components     Errors/Warnings	Description:	SMC-50 Module v01		
				~	
		<u>S</u> chedule In:	🚑 MainTask	~	
		🔲 In <u>h</u> ibit Program			

In this example, the Final Name is P10\_SMC50.

8. Click Tags within the Import Content organizer.

9. The Configure Tag References dialog box opens.

Import Content:		
😽 🙀 MainTask	Configure Tag References	
Program Tags	Import Name	Operation 🔄 Final Name
Routines	C DeviceName:I	UndefinedDeviceName:I
	🚩 🖞 _DeviceName:0	Undefined DeviceName:0
🝸 🏹 Tags	🖞DeviceName_FP	Create DeviceName_FP
Add-On Instructions	DeviceName_MSG	Create DeviceName_MSG
♥ Data Types	🖞DeviceName_MSG_DATA	CreateDeviceName_MSG_DATA
Errors/Warnings	MachineName	Use Existing 🕼_MachineName
	🖞ModuleName	CreateModuleName

- 10. Replace Final Tag Names with the associated drive and machine names you have already configured.
  - a. Replace \_DeviceName of \_DeviceName:I, \_DeviceName:O, \_DeviceName\_MSG, \_DeviceName\_MSG\_DATA, and \_DeviceName\_FP tags with the name of your SMC-50 device.
  - b. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - c. Replace \_ModuleName of \_ModuleName tag with the device name of your SMC-50 device. If a device module with energy support was selected, there will be additional tags named \_DeviceName\_BEO.
  - d. Replace \_DeviceName in all of these tags with the name of your SMC-50 device.

Import Content:		
- 🔁 MainTask	Configure Tag References	
	Import Name	Operation 🔄 Final Name 🛆
Program Tags	🖞DeviceName	Create 🗋 _DeviceName
	🚩 🖞 _DeviceName:I	Undefined 🗋 _DeviceName:I
🚩 🦳 🌌 Tags	🚩 🖞 _DeviceName:0	Undefined DeviceName:0
🔄 💮 Add-On Instructions	DeviceName_BEO	Create 🗋 _DeviceName_BEO
Ther Components	DeviceName_BEOmsg_Get_Attr_kW	Create DeviceName_BEOmsg_Get_Attr_kW
Errors/Warnings	🖞DeviceName_BEOmsg_Get_Attr_kWh	Create 🗋 _DeviceName_BEOmsg_Get_Attr_kWh
	🖞DeviceName_FP	Create DeviceName_FP
	🖞DeviceName_MSG	Create 🗋 _DeviceName_MSG
	🖞DeviceName_MSG_DATA	CreateDeviceName_MSG_DATA

11. Click Other Components within the Import Content organizer.

The Configure Component References dialog box opens.

Imp	ort Content:							
	🚭 MainTask	C	onfigure e Componen	t References				
		Γ	Import Name	Operation	Final Name	Δ	Class Name	
	🖉 Program Tags		🚺 _DeviceName	Undefined	_DeviceName	T	Module	
٣	🧖 Tags							
-6	Add-On Instructions							
	Data Types							
ľ	Errors/Warnings	1						

- 12. Replace the Final Name (\_DeviceName) with the name of your SMC-50 device.
- 13. Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.

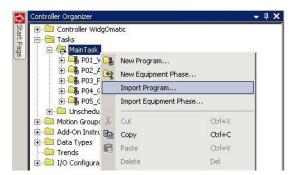


If a device module with energy support was selected, the program will contain an additional routine named R05\_Energy. Refer to Set MSG Path in the E3 Plus Energy Monitoring Routine on page 81, for more information.

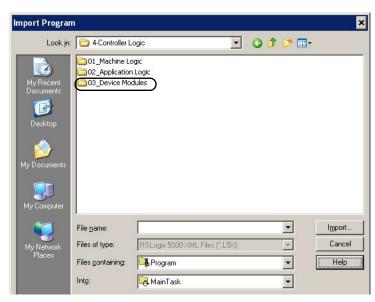
### Import and Configure ArmorStart Distributed Motor Controller Device Modules

Follow these steps to add preconfigured ArmorStart distributed motor controller device logic modules to your Logix Designer project.

1. Expand the Tasks folder in your Controller Organizer and right-click the Main Task folder.



- 2. Choose Import Program.
- 3. Navigate to the 4-Controller Logic folder within the toolkit's files folder and open the 03\_Device Modules folder.



Your personal computer's harddrive path is

 $C:\Program Files\RA\_Simplification\DMAT\B-Files\4-Controller \ Logic.$ 

4. Select AS294E\_woIPS\_Module.L5X per application requirements.

This example uses the ArmorStart LT 294E motor controller (without internal power supply).

Look in:	🛛 👪 03_Device M	lodules 👻	G 🤌 📂 🛄 🕶			
(And	Name	*	Date modified	Туре	Size	
-	🚯 AS280E_Mo	dule.L5X	4/7/2015 9:27 PM	Logix Designer X	87 KB	
Recent Places	AS281E_Mo	dule.L5X	4/7/2015 9:35 PM	Logix Designer X	87 KB	
	AS284E_Mo	dule.L5X	4/7/2015 9:33 PM	Logix Designer X	96 KB	
	AS290E_wIP	S_Module.L5X	4/7/2015 9:38 PM	Logix Designer X	81 KB	
Desktop	AS290E_woI	PS_Module.L5X	4/7/2015 9:39 PM	Logix Designer X	81 KB	
	AS291E_wIP	S_Module.L5X	4/7/2015 9:41 PM	Logix Designer X	83 KB	
6778	AS291E_woI	PS_Module.L5X	4/7/2015 9:43 PM	Logix Designer X	83 KB	
Libraries	AS294E_w/IP	S_Module.L5X	4/7/2015 9:47 PM	Logix Designer X	93 KB	
	🚯 AS294E_woI	PS_Module.L5X	4/7/2015 9:48 PM	Logix Designer X	93 KB	
	🚯 CIPMotion_	Drive_Module.L5X	4/11/2013 2:43 PM	Logix Designer X	225 KB	
Computer	🚯 CIPMotion_	FdbkOnly_Module.L5X	9/29/2010 10:45 AM	Logix Designer X	151 KB	
-	🗿 CIPMotion_	XYCoordMotion_Module.L5X	9/23/2011 9:55 AM	Logix Designer X	315 KB	
	🗿 CIPMotion_	XYZCoordMotion_Module.L5X	9/23/2011 11:10 AM	Logix Designer X	339 KB	
Network	🚯 E3Plus_Mod	lule.L5X	5/21/2013 4:19 PM	Logix Designer X	92 KB	
	E3Plus_Mod	lule_Energy.L5X	7/2/2013 3:25 PM	Logix Designer X	119 KB	
	K300_Drive_	Module.L5X	9/29/2010 11:25 AM	Logix Designer X	279 KB	
	File name:	AS294E_woIPS_Module			- (	Import.
	Files of type:	RSLogix 5000 XML Files (*.L5X)			-	Cance
	Files containing:	🕞 Program			-	Help
	Into:	🕞 MainTask			-	

- 5. Click Import.
- 6. The Import Configuration dialog box opens.

🖄 Find:	- AB AB	Find/Replace		
Find Within: Final Name				
ort Content:				
- 🙀 MainTask	Configure Progra	am Properties		
PXX_ModuleName PXX_ModuleName Program Tags	Import Name:	PXX_ModuleName		
	Operation:	Overwrite	-	
References		(i) References will be imported as configured in the References I	olders	
- 🔄 Add-On Instructions	Final Name:	PXX_ModuleName	•	Collision Details
Other Components     Other Components     Errors/Warnings	Description:	ArmorStart294E Module v01	~	
- 🛃 Errors/warnings			-	
	Schedule In:	MainTask	•	
	🔲 Inhibit Progra	m		
	Assigned Rout	ines		
	Main:	R00_Main		
	Fault:	<none></none>		

7. Enter the desired name for your initial Device in Final Name field.

2 <u>2</u>	Find: Find Within: Final Name	- 40 40	Find/Replace			
nport Co	ontent:					
	MainTask	Configure Progra	am Properties			
Ľ,	PO3_A5294E Program Tags	Import Name:	PXX_ModuleName			
	Routines	Operation:	Create	-	2	
6	References		(i) References will be imported a configured in the References	s folders		
	🔄 Add-On Instruction 🐻 Data Types	Final Name:	P03_A5294E	•	Properties	
- 🛛	Other Components Errors/Warnings	Description:	ArmorStart294E Module v01	*		
		Schedule In:	RainTask	•		
		🔲 Inhibit Progra	m			
		Assigned Rout	ines			
		Main:	R00_Main			
		Fault:	<none></none>			
		rauk:	<none></none>			
					ОК	Cancel Help

In this example, the Final Name is P03\_AS294E.

- 8. Click Tags within the Import Content organizer.
- 9. The Configure Tag References dialog box opens.

🗋 🖾 Find:	•	Find/Replace	]					
Find Within: Final Name								
port Content:								
ainTask MainTask	Configu	ire Tag References						
		Import Name	Operation		Final Name		Alias For	1
- Program Tags	1	_DeviceName:I	Use Existing	1	_DeviceName:I	- A		I
References	1	_DeviceName:0	Use Existing	G	_DeviceName:0			1
🖥 🦳 🌌 Tags	1	_DeviceName_Fault_Msg	Use Existing		_DeviceName_Fault_Msg			1
	9	_DeviceName_FaultCode	Use Existing		_DeviceName_FaultCode			1
Data Types     Other Components	1	_DeviceName_FP	Use Existing		_DeviceName_FP			1
Other Components     Errors/Warnings	1	_DeviceName_Warning	Use Existing		_DeviceName_Warning_Msg			
Circles warmings	1	_DeviceName_Warning	Use Existing		_DeviceName_WarningCode			1
	1	_MachineName	Use Existing (		_MachineName	$\supset$		
	D	_ModuleName	Use Existing (		_ModuleName			Ī
	1	ArmorStartAlarmHandsha	Use Existing		ArmorStartAlarmHandshake			
	1	ArmorStartAlarmInProcess	Use Existing		ArmorStartAlarmInProcess			Ī
	1	ArmorStartAlarmName	Use Existing		ArmorStartAlarmName			Ī
	A 1	A			A		+	I

- 10. Replace Final Tag Names with the associated drive and machine names you have already configured.
  - a. Replace\_DeviceName of \_DeviceName:I, \_DeviceName:O, \_DeviceName\_Fault\_Msg, \_DeviceName\_FaultCode, \_DeviceName\_FP, \_DeviceName\_Warning\_Msg and DeviceName WarningCode tags with the name of your ArmorStart device.
  - b. Replace \_MachineName of \_MachineName tag with the machine name of your project.
  - c. Replace \_ModuleName of \_ModuleName tag with the device name of your ArmorStart device.
  - d. Replace \_DeviceName in all of these tags with the name of your ArmorStart device.
- 11. Click Other Components within the Import Content organizer.

The Configure Component References dialog box opens.

Import Configuration	
Find: Find Within: Final Name	Find/Replace
Import Content:	
Manī tak Porgan Tags Porgan Tags Paterences Tags Paterences Data Spes Other Components Const/Varnings	Configure Component References Import Name Operation Configure Component References Final Name Configure Component References DeviceName DeviceName DeviceName DeviceName
Module '. DeviceName' is not defined in imp	OK Cancel Help

- 12. Replace the Final Name (\_DeviceName) with the name of your ArmorStart device.
- 13. Click OK.

The new Device Module Program appears in the Controller Organizer within the Main Task folder.



If a device module with energy support was selected, the program will contain an additional routine named R05\_Energy. Refer to Set MSG Path in the E3 Plus Energy Monitoring Routine on <u>page 81</u>, for more information.

### How to Change the AOI Input and Output Data Type

Follow these steps to change the ArmorStart LT AOI input and output data type. This example shows the ArmorStart LT 294E motor controller without IPS (internal power supply).

- 1. Under I/O Configuration in the Controller Organizer, right-click your ArmorStart motor controller and choose Properties.
- 2. Click Change in the Module Definition area

Module Properties: EN2TR (294	E-FD4P2Z 1.1)		
General	General		
Connection     Motor Protection & Control     Speed Control     Speed Control     User 1/0     Posit Configuration     DeviceLogix     Status     Internet Protocol     Pot Configuration     Network	Vendor: Allen-Bradley Parent: EN2TR Name:DeviceName Description: Module Definition Series: Revision: Electronic Keying: Connection: Configured By: Hand-Off-Auto (HOA) Keypad: Source Brake:	her.	Ethernet Address Private Network: 192.168.1. 21 IP Address Host Name:
Status: Offline			OK Cancel Apply Help

The Module Definition dialog box appears.

I Module Propertie	Module Definition*				
General Connection Module Info Motor Protection Speed Control User I/O Fault Configure DeviceLogix Status I - Fault Status I - Fault Status	Series: Revision: Electronic Keying: Connection: Configured By: User I/O	A V 1 V Compatible Module V Data V This Controller V	Options Hand-Off-Auto (HOA) Keypad: Source Brake:	Yes •	
- Port Configurati	0 Input v	lippat v	Inpu	2	
	3	(input *	Inpu	5	
Status: Offline		ОК	Cancel	Help	Help

- **3.** Configure the User I/O settings per application requirements. In this example, all the User I/O settings are configured as inputs.
- 4. Click OK to save and close the Module Definition dialog box.

- 23 Module Propertie Module Definition\* - - X General Connection Module Info Motor Protect Options • Hand-Off-Auto (HOA) Keypad Series A Yes -1 • 1 🌲 Revision: - Motor Protectio - Speed Control - User I/O - Fault Configura - DeviceLogix - Status - Fault Status Electronic Keying: Compatible Module -Yes • Source Brake Data • Connection: Configured By: This Controller X RSLogix 5000 - Internet Protoci - Port Configurati - Network These changes will cause module data types and properties to change. Data will be set to default values unless it can be recovered from the existing module properties. Verify module properties before Applying changes. Change module definition? Yes No **9**5 **3 3**4 Input 👻 Input 👻 Input 🔻 OK Cancel Help Status: Offline Help
- 5. Click Yes to acknowledge the Change module definition warning.

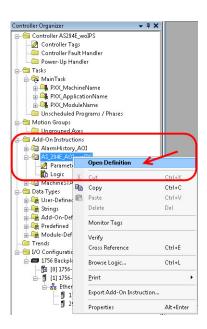
6. Click OK to close the Module Properties dialog box.

Connection Module Info				
— Module Info — Motor Protection & Control — Speed Control — User I/O — Fault Configuration	Type: Vendor: Parent: Name:	294E-FD4P2ZArr Allen-Bradley EN2TR DeviceName	norStart LT, 2HP, 480V AC,	Motor Starter, VFD Ethernet Address
Paulo Collegia DeviceUgia Status ⊢Fault Satus –Internet Protocol Port Configuration Network	Name: _Dev Description:		*	IP Address:     Ide Name:
	Source Brak You r consi	sying: ly: to (HOA) Keypad: e: nust go online with t stent with each othe	i.	e the controller and AmorStart LT configurations are al of module outputs from the controller.

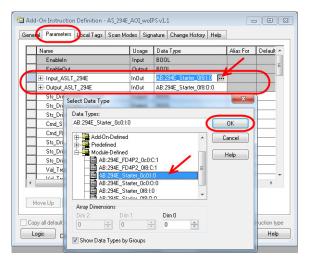
7. Under your ArmorStart controller in the Controller Organizer, double-click your ArmorStart motor controller and observe the new Data Type information.

Controller Organizer - 🗣 🗙	Scope: 🛐 AS294E_wolPS 👻 Show:	All Tags			▼ T. Enter Name Filter
Controller AS294E swoIPS	Name == △	Value 🔶	Forc 🕈	Style	Data Type
Controller Fault Handler	+ ApplicationName	{}	1 }		LIDT AnnStatus
Power-Up Handler	+ _DeviceName:C	{}	{}		AB:294E_FD4P2_0c0:C:1
E Tasks	+ _DeviceName:I	{}	{}		AB:294E_Starter_0c0:1:0
🔓 🛱 MainTask	± _DeviceName:0	{}	{}		AB:294E_Starter_0c0:0:0
🖶 🕞 POC_MachineName	+ _UeviceName_Fault_Msg	{}	{}		MESSAGE
💮 🕞 PXX_ApplicationName	+ _DeviceName_FaultCode	25		Decimal	DINT
😠 🕞 PXX_ModuleName	+ _DeviceName_FP	()	{}		AS_294E_A0I_woIPS
- Unscheduled Programs / Phases		()	{}		MESSAGE
🖨 😂 Motion Groups	+ _DeviceName_WarningCode	0		Decimal	INT
- 🗀 Ungrouped Axes	+ _MachineName	{}	{}		UDT_MachCtrl
🖨 😂 Add-On Instructions	±ModuleName	{}	{}		UDT_ModuleStatus
🗑 🕼 AlarmHistory_AOI	+ BlankAlarmName		{}		STRING
AS 294F AOI woTPS		-	(S	n · .	000

8. Under the Add-On-Instruction folder in the Controller Organizer, right-click the ArmorStart AOI (AS\_2XXE\_AOI\_...) and choose Open Definition.



The Add-On Instruction Definition dialog box appears.

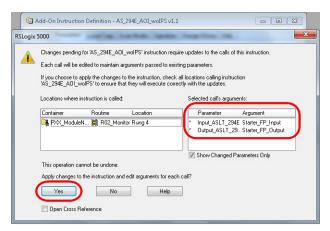


- 9. Click the Parameters tab.
- Search for the Input and Output tags and click the ellipses under the Data Type column for the Input tags. The Select Data Type dialog box appears.
- 11. Select the new Data Type previously identified in step 7.
- **12.** Repeat  $\underline{\text{step 10}}$  for the output tags.
- 13. Click OK to close the Select Data Type dialog box.

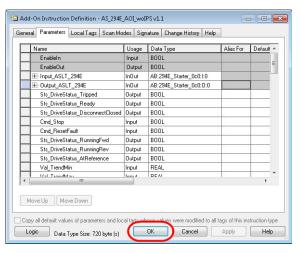
14. Review the new Data Type and click Apply.

	Name	Usage	Data Type	Alias For	Default #
	EnableIn	Input	BOOL		
	EnableOut	Output	BOOL		=
×		InOut	AB:294E_Starter_0c0:1:0		
×	⊕-Output_ASLT_294E	InOut	AB:294E_Starter_0c0:0:0		
	Sts_DriveStatus_Tripped	Output	BOOL	1	
	Sts_DriveStatus_Ready	Output	BOOL		
	Sts_DriveStatus_DisconnectClosed	Output	BOOL		
	Cmd_Stop	Input	BOOL		
	Cmd_ResetFault	Input	BOOL		
	Sts_DriveStatus_RunningFwd	Output	BOOL		
	Sts_DriveStatus_RunningRev	Output	BOOL		
	Sts_DriveStatus_AtReference	Output	BOOL		
	Val_TrendMin	Input	REAL		
	Wal Trandklau III	Innut	DEAL		
_	fove Up Move Down	al tags wh	ose values were modified to a	loge of this in	struction typ

15. Review the new parameters and click Yes to apply the edits.



16. Click OK.



The new AOI input and output Data Type changes are complete.

# Notes:

## **Rockwell Automation Support**

Rockwell Automation provides technical information on the Web to assist you in using its products. At <u>http://www.rockwellautomation.com/support</u> you can find technical and application notes, sample code, and links to software service packs. You can also visit our Support Center at <u>https://rockwellautomation.custhelp.com/</u> for software updates, support chats and forums, technical information, FAQs, and to sign up for product notification updates.

In addition, we offer multiple support programs for installation, configuration, and troubleshooting. For more information, contact your local distributor or Rockwell Automation representative, or visit <a href="http://www.rockwellautomation.com/services/online-phone">http://www.rockwellautomation.com/services/online-phone</a>.

### **Installation Assistance**

If you experience a problem within the first 24 hours of installation, review the information that is contained in this manual. You can contact Customer Support for initial help in getting your product up and running.

United States or Canada	1.440.646.3434
Outside United States or Canada	Use the <u>Worldwide Locator</u> at <u>http://www.rockwellautomation.com/rockwellautomation/support/overview.page</u> , or contact your local Rockwell Automation representative.

### **New Product Satisfaction Return**

Rockwell Automation tests all of its products to help ensure that they are fully operational when shipped from the manufacturing facility. However, if your product is not functioning and needs to be returned, follow these procedures.

	Contact your distributor. You must provide a Customer Support case number (call the phone number above to obtain one) to your distributor to complete the return process.
Outside United States	Please contact your local Rockwell Automation representative for the return procedure.

## **Documentation Feedback**

Your comments will help us serve your documentation needs better. If you have any suggestions on how to improve this document, complete this form, publication <u>RA-DU002</u>, available at <u>http://www.rockwellautomation.com/literature/</u>.

Rockwell Automation maintains current product environmental information on its website at <u>http://www.rockwellautomation.com/rockwellautomation/about-us/sustainability-ethics/product-environmental-compliance.page</u>.

#### www.rockwellautomation.com

#### Power, Control and Information Solutions Headquarters

Americas: Rockwell Automation, 1201 South Second Street, Milwaukee, WI 53204-2496 USA, Tel: (1) 414.382.2000, Fax: (1) 414.382.4444 Europe/Middle East/Africa: Rockwell Automation NV, Pegasus Park, De Kleetlaan 12a, 1831 Diegem, Belgium, Tel: (32) 2 663 0600, Fax: (32) 2 663 0640 Asia Pacific: Rockwell Automation, Level 14, Core F, Cyberport 3, 100 Cyberport Road, Hong Kong, Tel: (852) 2887 4788, Fax: (852) 2508 1846