

PROFIdrive Parameter Jenny Science

Date 31/01/2024

Function Block Parameter Datatype of Input-/Output-Parameter:

DWORD (DEC+/-)
REAL (floating point)Unsigned32 and Integer32
otherwiseValueRead2/ValueWrite2
ValueRead1/ValueWrite1

| Parameter Nr. | Name | Description | Default Value | Low Limit | High Limit | Data Length (Byte) | Data Type | Read only | Additional Notes |
|---------------|----------------------|---|---------------|------------|------------|--------------------|-------------------------|-----------|-----------------------------|
| 922 | Telegram Select | Telegram selection | | 0x0000 | 0x0009 | 2 | Unsigned 16 | x | |
| 923 | Signal List | List of all parameters for signals | | 0x0000 | 0xFFFF | 72 | Array[n] Unsigned 16 | | |
| 924 | Status Bit | Status word bit Pulses Enabled | | - | - | 4 | Array[2] Unsigned 16 | x | |
| 925 | Sign-Of-Life | Number of Controller Sign-Of-Life failures which may be tolerated | | 0x0000 | 0xFFFF | 2 | Unsigned 16 | | |
| 930 | Operation Mode | Operating mode | | 0x0001 | 0x0003 | 2 | Unsigned 16 | x | |
| 944 | Fault Counter | Fault message counter | | 0x0000 | 0xFFFF | 2 | Unsigned 16 | x | not supported yet |
| 945 | Fault Code | Fault code | | 0x0000 | 0xFFFF | 128 | Array[n] Unsigned 16 | x | not supported yet |
| 946 | Fault Code List | Fault code list | | 0x0000 | 0xFFFF | 18 | Array[n] Unsigned 16 | x | not supported yet |
| 947 | Fault Number | Fault number | | 0x0000 | 0xFFFF | 128 | Array[n] Unsigned 16 | x | not supported yet |
| 948 | Fault Time | Fault time | | - | - | - | Array[n] TimeDifference | x | not supported yet |
| 949 | Fault Value | Fault value | | 0x0000 | 0xFFFF | 128 | Array[n] | x | not supported yet |
| 950 | Buffer Scaling | Scaling of the fault buffer | | 0x0000 | 0xFFFF | 4 | Array[2] Unsigned 16 | x | not supported yet |
| 951 | Fault List | Fault number list with text | | 0x0000 | 0xFFFF | 18 | Array[n] Unsigned 16 | x | not supported yet |
| 952 | Situation_Sum | Fault situation counter | | 0x0000 | 0xFFFF | 2 | Unsigned 16 | | not supported yet |
| 964 | Drive Unit ID | Drive Unit identification | | 0x0000 | 0xFFFF | 12 | Array[n] Unsigned 16 | x | |
| 965 | Profile ID | Profile identification number | | 0x0000 | 0x03FF | 2 | OctetString 2 | x | |
| 974 | Mode-Access ID | Base Mode Parameter Access service identification | | 0x0000 | 0xFFFF | 6 | Array[n] Unsigned 16 | x | |
| 975 | DO_ID | DO identification | | 0x0000 | 0xFFFF | 16 | Array[n] Unsigned 16 | x | |
| 978 | DO_ID List | list of all DO-Ids | | 0x0000 | 0xFF | 6 | Array[n] Unsigned 8 | x | |
| 979 | Sensor format | Sensor format | | 0x0000 | 0xFFFFFFFF | 12 | Array[n] Unsigned 32 | x | |
| 980 - 989 | Parameter List1..10 | Number list of defined parameter | | 0x0000 | 0xF9FFF | 40 | Array[n] Unsigned 16 | x | |
| 2000 | v_Bezug | Reference Velocity | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Unsigned32 | | value in inc/s |
| 2007 | a_Bezug | Reference Acceleration | 0x989680 | 0x7D0 | 0x7FFFFFFF | 4 | Unsigned32 | | value in inc/s ² |
| 2100 | S-Curve | | 0x14 | 0x1 | 0x64 | 4 | Unsigned32 | | |
| 2105 | I_Force Actual | Filtered motor current | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 2106 | Status Register | Process Status Register XENAX | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 2107 | Cycle Time | PROFINET Bus Cycle Time | 0x3E8 | 0x64 | 0x2710 | 2 | Unsigned 16 | x | |
| 2108 | Motor Type | rotative | | | | 10 | Visible_String | x | |
| 2109 | LF Limit Force | Limit Force | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 2110 | TF Tell Force Actual | Filtered sensor force | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 2572 | a_Max | Max. Acceleration (für Tipp-Betr.) | 0x989680 | 0x7D0 | 0x3B9ACA00 | 4 | Unsigned32 | | |
| 2585 | Tippen 1 v_Soll | Jog 1 Demand Velocity | 0x00 | 0xFA0A1F00 | 0x05F5E100 | 4 | Integer 32 | | |
| 2586 | Tippen 2 v_Soll | Jog 2 Demand Velocity | 0x00 | 0xFA0A1F00 | 0x05F5E100 | 4 | Integer 32 | | |
| 2587 | Tippen 1 Weg | Jog 1 Way | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Unsigned32 | | |
| 2588 | Tippen 2 Weg | Jog 2 Way | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Unsigned32 | | |
| 2591 | Tippen ink | Jog incremental | 0x00 | 0x00 | 0x01 | 4 | Unsigned32 | | |
| 3068 | PWT | Position Window Time | 0x00 | 0x00 | 0x3E8 | 4 | Unsigned32 | | |
| 3073 | LIF Limit IForce | Limit IForce | 0x00 | 0x00 | 0x7D0 | 4 | Unsigned 16 | | |
| 3550 | Webseite Jenny | | | | | 26 | Visible_String | x | |
| 3991 | Home-Speed ex | Home Speed for external Home sensor | 0x3E8 | 0x00 | 0x3D090 | 4 | Unsigned 32 | | |
| 3992 | Home-Speed Z | Z-Speed for internal encoder Z-mark | 0x1F4 | 0x00 | 0x186A0 | 4 | Unsigned 32 | | |

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| 5000 | Direct Commands | Possible values see last page | 0x00 | 0x00 | 0xFFFFFFFF | 4 | Unsigned 32 | | |
| 5101 | TS Tell Status | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5102 | TE Tell Error | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5103 | TP Tell Position | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5104 | TT Tell Temp. | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5105 | TOX Tell Out Hex | Tell Output Hex | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5106 | TIX Tell In Hex | Tell Input Hex | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5107 | TMC Motor Cur | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5108 | TMT Motion Time | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5109 | TCP Pos 1 | TCP Tell Captured Position 1 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5110 | TCP Pos 2 | TCP Tell Captured Position 2 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5111 | TCP Pos 3 | TCP Tell Captured Position 3 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5112 | TCP Pos 4 | TCP Tell Captured Position 4 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5113 | TCP Pos 5 | TCP Tell Captured Position 5 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5114 | TCP Pos 6 | TCP Tell Captured Position 6 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5115 | TCP Pos 7 | TCP Tell Captured Position 7 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5116 | TCP Pos 8 | TCP Tell Captured Position 8 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5117 | TH Ref State | TH Tell Reference State | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5118 | VER of Firmware | Version of Servocontroller Firmware | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5119 | ACV AC Variation | ACV Acceleration Variation | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5120 | I2TM Limit Value | I2T Limit Value | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5121 | I2T Calc Value | I2T Calculated Value | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5122 | IFPK FPK | I_Force Peak (FTM = 0) Force Peak (FTM = 1,2) | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5123 | TESM Tell SMU E | SMU Error Number | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5124 | DGMSO | Detected Gantry Master Slave Offset | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5125 | SIFF SFF | Sector I_Force Curve Failed (FTM = 0) Sector Force Curve Failed (FTM = 1,2) | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5126 | IFPKn | IFPKn I_Force Peak Sector | 0x01 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5127 | FCV | FCV Force Calibration Valid | 0x02 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5128 | TV Tell Velocity | TV Tell Velocity | 0x03 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5129 | TPT | TPT Tell Process Time | 0x04 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5130 | VERL | Version of Bootloader | 0x05 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5131 | TCPB Pos 1 | TCP Tell Captured Position Buffer 1 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5132 | TCPB Pos 2 | TCP Tell Captured Position Buffer 2 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5133 | TCPB Pos 3 | TCP Tell Captured Position Buffer 3 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5134 | TCPB Pos 4 | TCP Tell Captured Position Buffer 4 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5135 | TCPB Pos 5 | TCP Tell Captured Position Buffer 5 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5136 | TCPB Pos 6 | TCP Tell Captured Position Buffer 6 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5137 | TCPB Pos 7 | TCP Tell Captured Position Buffer 7 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5138 | TCPB Pos 8 | TCP Tell Captured Position Buffer 8 | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5139 | TESMH | SMU Error Number History | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5140 | GR | Gear Ratio | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5141 | TTPS | Tell Temperature Power Stage (Xvi 75V8S) | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5142 | TVPSM | Tell Voltage Power Supply Motor (Xvi 75V8S, returns 0 for o | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5143 | LARES | linear axis resolution in [inc/m] | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5144 | LAST | linear axis stroke in [inc] | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5201 | CO Clear Output | | 0x01 | 0x01 | 0x08 | 4 | Integer 32 | | |
| 5202 | EVT Event Activ | Event Activation | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |

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| 5203 | G Go Immediately | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5204 | IX Index number | Start Index Number | 0x01 | 0x01 | 0x32 | 4 | Integer 32 | | |
| 5205 | PG Program no. | Start Program Number | 0x01 | 0x01 | 0x3F | 4 | Integer 32 | | |
| 5206 | SO Set Output | Set Output Number | 0x01 | 0x01 | 0x08 | 4 | Integer 32 | | |
| 5207 | SOX Set Output | Set Output Hex Mask | 0x00 | 0x00 | 0xFF | 4 | Integer 32 | | |
| 5208 | TGD | Set Trigger Position Downward | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5209 | TGU | Set Trigger Position Upward | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5210 | ETI | Event Track Input | 0x00 | 0x00 | 0x0C | 4 | Integer 32 | | |
| 5211 | DTI | Disable Track Input | 0x00 | 0x00 | 0x0C | 4 | Integer 32 | | |
| 5212 | PRF | Start Profile Number | 0x01 | 0x01 | 0x05 | 4 | Integer 32 | | |
| 5213 | CRDA | Cogging Reference Drive Automatic | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5214 | DIF | Drive I Force | 0x01 | 0x01 | 0x0A | 4 | Integer 32 | | |
| 5215 | CLIF | Change Limit I Force | 0x00 | 0x00 | 0x7D0 | 4 | Integer 32 | | |
| 5216 | DF | Drive Force | 0x01 | 0x01 | 0x0A | 4 | Integer 32 | | |
| 5301 | AC Acceleration | | 0xF4240 | 0x7D0 | 0x3B9ACA00 | 4 | Integer 32 | | |
| 5302 | SCRV S-Curve | | 0x14 | 0x01 | 0x64 | 4 | Integer 32 | | |
| 5303 | SP Speed | | 0x186A0 | 0x0A | 0x05F5E100 | 4 | Integer 32 | | |
| 5304 | PO Position | Position (absolute) | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5305 | WA Way | Way (relative) | 0x4E20 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5306 | DP Deviation Pos | Deviation Position | 0x7D0 | 0x01 | 0x000F4240 | 4 | Integer 32 | | |
| 5307 | DRHR Direc. Ref | Direction Reference | 0x00 | 0x00 | 0x05 | 4 | Integer 32 | | |
| 5308 | DTP | Deviation Target Position | 0x64 | 0x01 | 0x2710 | 4 | Integer 32 | | |
| 5309 | ED Emerg. Dec. | Emergency Deceleration | 0x989680 | 0x2710 | 0x3B9ACA00 | 4 | Integer 32 | | |
| 5310 | ILAS | Input Low Active Selective | 0x00 | 0x00 | 0x0FFF | 4 | Integer 32 | | |
| 5311 | ILA | Input Low Active | 0x00 | 0x00 | 0x02 | 4 | Integer 32 | | |
| 5312 | IS | Stop Current | 0x258 | 0x0A | 0x7D0 | 4 | Integer 32 | | |
| 5313 | SLPP | Software Limit Position Positive | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5314 | SLPN | Software Limit Position Negative | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5315 | MD Mode | | 0x00 | 0x00 | 0x0D | 4 | Integer 32 | | |
| 5316 | ML Mass load | | 0x00 | 0x00 | 0x5F5E100 | 4 | Integer 32 | | |
| 5317 | BWS Bandw. Cur | Bandwidth Current Controller | 0x5DC | 0x05 | 0x1388 | 4 | Integer 32 | | |
| 5318 | BWP Bandw. Pos | Bandwidth Position Controller | 0x32 | 0x01 | 0x1388 | 4 | Integer 32 | | |
| 5319 | IR | Run Current | 0x4B0 | 0x0A | 0x7D0 | 4 | Integer 32 | | |
| 5320 | NIX Pre. Index N | Preselected Index Number | 0x01 | 0x01 | 0x32 | 4 | Integer 32 | | |
| 5321 | AIX | Acceleration of selected Index | 0x3E8 | 0x2 | 0xF4240 | 4 | Integer 32 | | |
| 5322 | SIX | Speed of selected Index | 0x186A0 | 0x0A | 0x05F5E100 | 4 | Integer 32 | | |
| 5323 | DIX | Distance of selected Index | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5324 | CI Card ID | Card Identifier | 0x00 | 0x00 | 0xFF | 4 | Integer 32 | | |
| 5325 | GSID | Gantry Slave Identifier | 0x00 | 0x00 | 0x04 | 4 | Integer 32 | | |
| 5326 | BWF1 | Bandwidth Filter 1 | 0x1388 | 0x1F4 | 0x186A0 | 4 | Integer 32 | | |
| 5327 | FQF1 | Frequency Filter 1 | 0x00 | 0x00 | 0x7D0 | 4 | Integer 32 | | |
| 5328 | ICP | Increments per Pulse | 0x00 | 0x00 | 0x32 | 4 | Integer 32 | | |
| 5329 | INH | Input Home Sensor | 0x01 | 0x01 | 0x08 | 4 | Integer 32 | | |
| 5330 | OVRD | Speed Override | 0x64 | 0x00 | 0x64 | 4 | Integer 32 | | |
| 5331 | PWRT | Phasing Rotative without HALL | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |
| 5332 | SOA Out Activity | Set Output Activity | 0xFF | 0x00 | 0xFF | 4 | Integer 32 | | |
| 5333 | SOT Out Type | Set Output Type | 0x5555 | 0x00 | 0xFFFF | 4 | Integer 32 | | |
| 5334 | SR | Synchronous Ratio | 0x00 | 0xFFFFFC18 | 0x3E8 | 4 | Integer 32 | | |
| 5335 | CAB CAN Baud | CAN Baud Rate | 0x7A120 | 0x2710 | 0xF4240 | 4 | Integer 32 | | |

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| 5336 | ROID | Rotative Motor Identifier | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5337 | Reserviert | | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5338 | Reserviert | | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5339 | SIFS SFS | Sector I_Force Start (FTM = 0) Sector Force Start (FTM = 1,2) | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5340 | SIFE SFE | Sector I_Force End (FTM = 0) Sector Force End (FTM = 1,2) | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5341 | IFL I_Force Low | | 0x00 | 0xFFFFF830 | 0x7D0 | 4 | Integer 32 | | |
| 5342 | IFH I_Force High | | 0x00 | 0xFFFFF830 | 0x7D0 | 4 | Integer 32 | | |
| 5343 | MLPN | Mechanical limit position negative | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5344 | MLPP | Mechanical limit position positive | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5345 | PGMSO | Preset Gantry Master Slave Offset | 0x00 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5346 | BRKD | Break delay | 0x64 | 0x01 | 0x3E8 | 4 | Integer 32 | | |
| 5347 | Reserviert | | 0x00 | 0x00 | 0x02 | 4 | Integer 32 | | |
| 5348 | LIF | Limit I_Force | 0x00 | 0x00 | 0x7D0 | 4 | Integer 32 | | |
| 5349 | TYIX | Type of Index | 0x01 | 0x01 | 0x02 | 4 | Integer 32 | | |
| 5350 | NSEC | Preselected Sector Number | 0x01 | 0x01 | 0x0A | 4 | Integer 32 | | |
| 5351 | STCX | Sector Transition Configuration | 0x00 | 0x00 | 0xFFFF | 4 | Integer 32 | | |
| 5352 | NDIF NDF | Preselected Drive I_Force Number (FTM = 0) Preselected Drive Force Number (FTM = 1,2) | 0x01 | 0x01 | 0x0A | 4 | Integer 32 | | |
| 5353 | ADIF ADF | Acceleration of selected Drive I_Force (FTM = 0) Acceleration of selected Drive Force (FTM = 1,2) | 0x3E8 | 0x02 | 0xF4240 | 4 | Integer 32 | | |
| 5354 | SDIF SDF | Speed of selected Drive I_Force (FTM = 0) Speed of selected Drive Force (FTM = 1,2) | 0x186A0 | 0x0A | 0x5F5E100 | 4 | Integer 32 | | |
| 5355 | IDIF FDF | I_Force Limit of selected Drive I_Force (FTM = 0) Force of selected Drive Force (FTM = 1,2) | 0x01 | 0x01 | 0x30D40 | 4 | Integer 32 | | |
| 5356 | DDIF DDF | Direction of selected Drive I_Force (FTM = 0) Direction of selected Drive Force (FTM = 1,2) | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |
| 5357 | SSEC | Selected Sectors (binary notation) | 0x01 | 0x00 | 0x3FF | 4 | Integer 32 | | |
| 5358 | SSO | Set Sector Offset | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5359 | ENCPD | ENCPD Encoder Plausibility Checking | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |
| 5360 | SPAD | Set Point ACK disable | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |
| 5361 | RXZP | Rotax Z-Mark Position | 0x00 | 0x00 | 0x00 | 4 | Integer 32 | | |
| 5362 | DRH | Dir. Home | 0x01 | 0x01 | 0x02 | 4 | Integer 32 | | |
| 5363 | DRZ | Dir. Z-Mark | 0x01 | 0x01 | 0x03 | 4 | Integer 32 | | |
| 5364 | FQS | Filter Quality Speed | 0x1388 | 0x1F4 | 0x186A0 | 4 | Integer 32 | | |
| 5365 | FFS | Filter Frequency Speed | 0x00 | 0x00 | 0x7D0 | 4 | Integer 32 | | |
| 5366 | EBMD | Enhanced Bandwidth Mode Disable | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |
| 5367 | ACB | Reserved | 0x0 | 0x0 | 0x3E8 | 4 | Integer 32 | | |
| 5368 | AIXD | Acceleration of selected dynamically Index | 0x3E8 | 0x2 | 0xF4240 | 4 | Integer 32 | | |
| 5369 | SIXD | Speed of selected dynamically Index | 0x186A0 | 0xA | 0x5F5E100 | 4 | Integer 32 | | |
| 5370 | DIXD | Distance of selected dynamically Index | 0x0 | 0x88CA6C00 | 0x77359400 | 4 | Integer 32 | | |
| 5371 | TYIXD | Type of dynamically Index | 0x1 | 0x1 | 0x2 | 4 | Integer 32 | | |
| 5372 | PPSD | Pole Placement Stability Dynamics | 0x0 | 0xFFFFFCE | 0x32 | 4 | Integer 32 | | |
| 5373 | IFDCS | I_Force Drift Compensation Setting | 0x3 | 0x0 | 0x7 | 4 | Integer 32 | | |
| 5374 | PIFDC | Reserved | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5375 | SORF | Swing Out Reduction Frequency | 0x0 | 0x0 | 0x3E8 | 4 | Integer 32 | | |
| 5376 | SORD | Swing Out Reduction Damping | 0x0 | 0x0 | 0x32 | 4 | Integer 32 | | |
| 5377 | CFF | Reserved | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |
| 5378 | CEXD | Reserved | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |

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| 5379 | AVF | Filter Frequency for Current Shaper | 0x0 | 0x0 | 0x7D0 | 4 | Integer 32 | | |
| 5380 | AVD | Damping Ratio for Current Shaper | 0x1 | 0x1 | 0x32 | 4 | Integer 32 | | |
| 5381 | NOF | Preselected output function | 0x1 | 0x1 | 0x8 | 4 | Integer 32 | | |
| 5382 | TYOF | Type of output function | 0x0 | 0x0 | 0x15 | 4 | Integer 32 | | |
| 5383 | NIF | Preselected input function | 0x1 | 0x1 | 0x8 | 4 | Integer 32 | | |
| 5384 | TYIF | Type of input function | 0x0 | 0x0 | 0x16 | 4 | Integer 32 | | |
| 5385 | PAIF | Parameter A of input function | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5386 | PBIF | Parameter B of input function | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5387 | PCIF | Parameter C of input function | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5388 | CLF | Change Limit Force | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5389 | FDF | Force Of Selected Drive Force | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5390 | FH | Force High | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5391 | FL | Force Low | 0x0 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5392 | FTM | Forceteq Mode | 0x0 | 0x0 | 0x2 | 4 | Integer 32 | | |
| 5393 | SQBW | Signateq Bandwidth | 0x1F4 | 0x64 | 0x1388 | 4 | Integer 32 | | [100, 200, 300, 500, 1000, 2000, 3000, 5000] |
| 5394 | MM | Motor Manufacturer | 0x0 | 0x0 | 0x2 | 4 | Integer 32 | | |
| 5395 | AREF | Automatic Reference | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |
| 5396 | EGMSO | Enable user defined gantry Master/Slave offset | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |
| 5397 | VMTAE | Virtual multturn for rotative motors with absolute encoder | 0x0 | 0x0 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5398 | ENAR | Enable absolute reference | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |
| 5399 | CTAB | Correction Table State | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |
| 5401 | POL Pole Pairs | | 0x00 | 0x00 | 0x64 | 4 | Integer 32 | | |
| 5402 | ENC | Encoder Increments | 0x5DC0 | 0x0A | 0x989680 | 4 | Integer 32 | | |
| 5403 | PHD Phase Direc. | Phase Direction | 0x00 | 0x00 | 0x01 | 4 | Integer 32 | | |
| 5404 | PHO Phase Off. | Phase Offset | 0x00 | 0x00 | 0x167 | 4 | Integer 32 | | |
| 5405 | MAMO Mass Motor | Mass Motor (Linax) | 0x00 | 0x00 | 0x989680 | 4 | Integer 32 | | |
| 5406 | FCM | Force Constant of Motor | 0x00 | 0x00 | 0x5F5E100 | 4 | Integer 32 | | |
| 5407 | LPH Inductivity | Inductivity Phase-Phase | 0x00 | 0x00 | 0x186A0 | 4 | Integer 32 | | |
| 5408 | RPH Resistance | Resistance Phase-Phase | 0x00 | 0x00 | 0x186A0 | 4 | Integer 32 | | |
| 5409 | FFDY | Frictional Force Dynamic | 0x00 | 0x00 | 0x2710 | 4 | Integer 32 | | |
| 5410 | FFST | Frictional Force Static | 0x00 | 0x00 | 0x2710 | 4 | Integer 32 | | |
| 5411 | DMLPP | Detected Mechanical Limit Position Pos. | 0x00 | 0x00 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5501 | VERS | Version SMU | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5502 | Timeout SLS | Timeout SLS | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5503 | Speed SLS | Speed Limit SLS | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5504 | Timeout Stop | Timeout Stop | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5505 | Postition window | Postition window | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5506 | SFTRD | SFTRD Input Configuration SMU | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5507 | TESM | Tell SMU Error | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5508 | Master Error Bit | SMU Master Error Bitfeld | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5509 | Slave Error Bit | SMU Slave Error Bitfeld | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5510 | Master Info Bit | SMU Master Info Bitfeld | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5511 | Slave Info Bit | SMU Slave Info Bitfeld | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5512 | SPC | Safety Parameter CRC | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5513 | SPMAC | Safety Parameter and Mac Address CRC | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5601 | EGW | EGW Set Gateway Address | 0xC0A80201 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5602 | EIP | EIP Set IP Address | 0xC0A80264 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |
| 5603 | ENM | ENM Set Net Mask | 0xFFFFC00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | | |

| Parameter Nr. | Name | Description | Default Value | Low Limit | High Limit | Data Length (Byte) | Data Type | Read only | Additional Notes |
|---------------|--------------------------|--|---------------|-------------|------------|--------------------|------------------|-----------|--|
| 5604 | EMAC 3 high Byte | EMAC Read MAC Address 3 high Bytes | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5605 | EMAC 3 low Byte | EMAC Read MAC Address 3 low Bytes | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5606 | EPRT | EPRT Set Port Number | 0x2711 | 0x01 | 0x0000FFFF | 4 | Integer 32 | | |
| 5607 | LICR | LICR Show Installed Licences | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5608 | SERB | SERB Set Baud Rate on Serial Interface | 0x1C200 | 0x2580 | 0x00054600 | 4 | Integer 32 | | |
| 5609 | WebMotion Vers. | WebMotion Version Application | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 5610 | WebMotion Boot | WebMotion Version Bootloader | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 6001 | SQVER | Signateq Firmware Version | 0x00 | 0x80000000 | 0x7FFFFFFF | 4 | Integer 32 | x | |
| 6002 | SQBW | Signateq Bandwidth | 0x1F4 | 0x64 | 0x1388 | 4 | Integer 32 | | [100, 200, 300, 500, 1000, 2000, 3000, 5000] |
| 6003 | SQSNF | Signateq Sensor Nominal Force | 0x00 | 0x00 | 0x30D40 | 4 | Integer 32 | | |
| 6004 | SQMRP | Signateq Measurement Range Positive | 0x00 | 0xFFFFCF2C0 | 0x30D40 | 4 | Integer 32 | | |
| 6005 | SQMNRN | Signateq Measurement Range Negative | 0x00 | 0xFFFFCF2C0 | 0x30D40 | 4 | Integer 32 | | |
| 6006 | SQSS | Signateq Sensor Sensitivity | 0x00 | 0x00 | 0x17D7840 | 4 | Integer 32 | | |
| 6007 | SQSFT | Signateq Sensor Force Type | 0x00 | 0x00 | 0x02 | 4 | Integer 32 | | |
| 6008 | SQOM | Signateq Operation Mode | 0x00 | 0x00 | 0x02 | 4 | Integer 32 | | |
| 6009 | SQFD | Signateq Force Direction | 0x00 | 0x00 | 0x02 | 4 | Integer 32 | | |
| 6010 | LFRMS | Limit Force Reached Maximum Speed | 0x00 | 0x00 | 0x895440 | 4 | Integer 32 | | |
| 6011 | CLFO | Clear Force Offset (Xvi 75V8S) | 0x0 | 0x0 | 0x1 | 4 | Integer 32 | | |
| 6012 | SQAC | Read Signateq Available Calibrations (Xvi 75V8S) | 0x0 | 0x0 | 0x7 | 4 | Integer 32 | x | |
| 6013 | BWFP | Bandwidth for forceteq pro controller | 0x32 | 0x1 | 0x3E8 | 4 | Integer 32 | | |
| 6014 | FTPES | Forcteq Pro Elastic Spring Constant | 0x3E8 | 0x1 | 0x989680 | 4 | Integer 32 | | |
| 6100 | SQSMT | Signateq Sensor Model Type | none | | | 30 | Visible_String | | |
| 6200 | SQSSN | Signateq Sensor Serial Number | none | | | 30 | Visible_String | | |
| 6201 | APSN | number of the program to auto start | 0x0 | 0x0 | 0x3E | 4 | Integer 32 | | |
| 6202 | APSD | Automatic program start delay in ms | 0x0 | 0x0 | 0xFFFF | 4 | Integer 32 | | |
| 7000 | TES | Tell Error String | no error | | | 100 | Visible_String | x | |
| 7100 | SID | servo identification string | | | | 32 | Visible_String | | |
| 61000 | NameOfStation | PROFINET Device Name | - | - | - | 240 | OctetString[240] | | |
| 61001 | IpOfStation | PROFINET IP Adresse XENAX | - | - | - | 4 | Unsigned 32 | | |
| 61002 | MacOfStation | MAC Adresse PROFINET Busmodul | - | - | - | 6 | OctetString[6] | | |
| 61003 | StandardGatewayOfStation | PROFINET Standard Gateway XENAX | - | - | - | 4 | Unsigned 32 | | |
| 61004 | SubnetMaskOfStation | PROFINET Subnet Mask XENAX | - | - | - | 4 | Unsigned 32 | | |

| Parameter Nr. | Name | Description | Default Value | Low Limit | High Limit | Data Length (Byte) | Data Type | Read only | Additional Notes |
|---------------|------|-------------|---------------|-----------|------------|--------------------|-----------|-----------|------------------|
|---------------|------|-------------|---------------|-----------|------------|--------------------|-----------|-----------|------------------|

Direct commands values

| | |
|--------------------------|--|
| Ref/Power | |
| 0x1000 | Reference |
| 0x1020 | RSTO Limit stop, mechanical reference for Linux |
| 0x1030 | MLC Mechanical Limit Calibration |
| 0x1040 | reserved |
| 0x1050 | reserved |
| Power | |
| 0x2000 | PW Power On (for ROTAX® and third party motors only) |
| 0x2010 | PWC Power continues at actual position (linear motor axes, after error, or after PQ) |
| 0x2020 | PWR Power Reset (search electrical angle, phasing, for test only) |
| 0x2030 | PQ Power Quit |
| Motion | |
| 0x3000 | GP Go Position |
| 0x3010 | GW Go Way |
| 0x3020 | JP Jog Positive |
| 0x3030 | JP Jog Negative |
| 0x3040 | SM Stop Motion |
| 0x3050 | GZ Rotate to Z-Mark |
| 0x3060 | reserved |
| Force Calibration | |
| 0x4000 | FC Force Calibration (distance parameter is "WA" Parameter Nr. 5305) |
| 0x4001 | FCT1 Force Calibration Test Mode on (with activate compensation) |
| 0x4002 | FCT0 Force Calibration Test Mode off (position controller active) |
| 0x4003 | FCT2 Force Calibration Test Mode on (without active compensation) |
| 0x4010 | IFDCP Automatic I_Force Drift Compensation Drive in positive direction |
| 0x4011 | IFDCP Automatic I_Force Drift Compensation Drive in negative direction |
| Init | |
| 0x5000 | RES Reset |
| 0x5001 | RESM Reset Motor Specific Settings |
| 0x5010 | CLCP Clear all Captured Positions |
| 0x5015 | CP12 Captured Position Input 12 on (Xvi 75V8 or Xvi 75V8S / CP4 Captured Position Input 4 on (Xvi 48V8) |
| 0x5016 | CP12 Captured Position Input 12 off (Xvi 75V8 or Xvi 75V8S / CP4 Captured Position Input 4 off (Xvi 48V8) |
| 0x5020 | CLPO Clear position counter (only rotative motors) |
| 0x5030 | DMBUS Deactivate Motion Blocking by Unconfigured SMU |
| Force Control | |
| 0x6000 | Start force monitoring in cyclic synchronized position mode |
| 0x6001 | Finish force monitoring in cyclic synchronized position mode. Drive since last start command 0x6000 will be analysed, for example bit 7 in PSR (Force in Sector) gets valid value |
| 0x6002 | TPSO Take Position as Sector Offset |
| 0x6010 | CLFO Clear Force Offset |