

Title: How to control SigmaLogic7 Modbus with Siemens PLC

Product(s): SigmaLogic7 Modbus, Siemens Simatic S7-1200

Doc. No. AN.MTN.09

Application Overview

This document explains how to configure and make a basic program to control a SigmaLogic7 Modbus Servopack with a Siemens PLC Simatic S7-1200. The PLC code is given only as a basic example purpose. More code and validation will have to be done to be used on a real application.

Before going forward reading this application note, it is strongly recommended to look the following e-Learning to have a basic knowledge of the Sigmalogic functionalities and setup:

- <u>https://www.yaskawa.com/downloads/search-</u> index/details?showType=details&docnum=eLV.SigmaLogic.01.Quickstart_Cnfg
- <u>https://www.yaskawa.com/links?type=documents&docnum=eLM.SigmaLogic7.01.SL</u>
 <u>7 Modbus</u>

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|-----------|---|
| Component | Product and Model Number |
| PLC | Siemens Simatic S7-1200 Cpu 1212c (6ES7 212-1BE40-0XB0) |
| Servopack | SigmaLogic7 Modbus (Firmware 3.3, Software 2.0.0) |
| Motor | Sigma-5 and Sigma-7 Series |
| Software | LogicWorks version 2.0.0 |

STEP 7 Pro version V14 SP1

Products Used & Application Requirements

PLC Software



Ethernet IP Setup

Set the IP address for each device. In this configuration example the following addresses are used:

- SigmaLogic 1 192.168.1.4
- SigmaLogic 2 192.168.1.5
- Siemens PLC 192.168.1.3

Configuration Example:



SigmaLogic Configuration

For this example, the default configuration was used in the SigmaLogic drives. The IP address for each SigmaLogic is only setup parameter that was changed. The user units are in motor turns. Make sure to update your IP address in the DB MB_Client data. (See page6)

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Siemens PLC - Project Tree Layout

| Project tree | |
|---|--|
| Devices | |
| | |
| | |
| | |
| ▼ [] PLC_1 [CPU 1212C AC/DC/Rly] | |
| Device configuration | |
| S Online & diagnostics | |
| Program blocks | |
| Add new block | |
| The Main [OB1] Main Program | |
| YAS_AXIS_CTRL [FB2] Function to Control the SigmaLogic (Convert, read & write data in the communication data) | |
| Modbus Read1 [DB3] | |
| Modbus Read2 [DB7] DB with the setup variable for the communication (one per MB_Client function) | |
| Modbus Write1 [DB2] | |
| Modbus Write 2 [DB6] | |
| ReadData1 [DB4] DB with Read Data information - array of 60x UINT (one per SigmaLogic) | |
| ReadData2 [DB8] | |
| SERVO_DATA1 [DB10] DB with the setup variable for the communication (MB_Client function) | |
| SERVO_DATA2 [DB11] | |
| WriteData1 [DB5] DB with Write Data information - array of 60x UINT (one per SigmaLogic) | |
| WriteData2 [DB9] | |
| YAS_AXIS_CTRL_DB1 [DB20] DB for YAS_AXIS_CTRL function (one per SigmaLogic) | |
| YAS_AXIS_CTRL_DB2 [DB21] | |
| System blocks | |
| Program resources | |
| MB_CLIENT[FB1084] Function to communicate as a Modbus TCP client via the PROFINET connection | |
| EC_Timer_0 (DB50) | |
| EC_Timer_1 [DB51] | |
| EC_Timer_2 (DB52) | |
| IEC_Timer_3 [DB53] | |
| EC_Timer_4 [DB54] | |
| MB_CLIENT_OB_1 [DB40] DB for the MB_Client function (one per SigmaLogic) | |
| MB_CLIENT_DB_2 [DB41] | |

Siemens PLC - MB_CLIENT function

The main function that has to be used is MB_CLIENT from the communication instruction library (Please see screen shot below). This instruction communicates as a Modbus TCP client via the PROFINET connection. With the "MB_CLIENT" instruction, a connection is established between the client and the server. It send Modbus requests and receive responses, it is also controlling the connection termination of the Modbus TCP client.

- Each "MB_CLIENT" connection must use a unique instance DB.
- For each "MB_CLIENT" connection, a unique server IP address must be specified.
- Each "MB_CLIENT" connection requires a unique connection ID.





For this configuration example, a DB with variables was created to generate the variable for the input and output data of each MB_Client function. For each SigmaLogic there is a ModbusRead DB and ModbusWriteDB.

| SigmaLogic1 | SigmaLogic2 |
|--------------------|--------------------|
| ModbusRead1 (DB3) | ModbusRead2 (DB3) |
| ModbusWrite1 (DB2) | ModbusWrite2 (DB2) |
| ReadData1 (DB4) | ReadData2 (DB4) |
| WriteData1 (DB5) | WriteData2 (DB5) |

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Modbus Read DB

| | Mo | odb | usRe | ad1 | | | | | | | | | |
|----|-----|-----|------|---------|---------------|-------------------|-------------|--------|--------------|---|---|----------|---|
| | | Na | me | | | Data type | Start value | Retain | Accessible f | Writa | Visible in | Setpoint | Comment |
| 1 | - | - | Stat | ic | | | | | | | | | |
| 2 | - | | 1 | REQ | | Bool | false | | | | | | |
| 3 | - | = | 1 | DISC | | Bool | false | | | | | | |
| 4 | -0 | | 1 | Done | | Bool | false | | | | | | |
| 5 | -0 | | 1 | Busy | | Bool | false | | | | | | |
| 6 | - | - | 1 | rror | | Bool | false | | | | | | |
| 7 | | | - | status | | Word | 16#0 | | | | | | |
| 8 | | | 1 | statuss | ave | Word | 16#0 | | | | | | |
| 9 | | | 1 | Mode | | USInt | 0 | | | | | | |
| 10 | - | | 1 | Data Ad | dr | UDInt | 30045 | | | | | | |
| 11 | - | | 1 | DataLe | n | Int | 60 | | | | | | |
| 12 | | | • (| ONNE | ст | TCON_IP_v4 | | | | | | | |
| 13 | - | 1 | | Inte | rfaceId | HW_ANY | 64 | | ¥ | Image: A start of the start of | | | HW-identifier of IE-interface submodule |
| 14 | - | | | ID | | CONN_OUC | 1 | | V | | | | connection reference / identifier |
| 15 | -00 | 1 | | Con | nectionType | Byte | 11 | | V | | | | type of connection: 11=TCP/IP, 19=UDP (17=TCP |
| 16 | - | | | Acti | veEstablished | Bool | true | | V | | V | | active/passive connection establishment |
| 17 | - | 1 | | Rem | oteAddress | IP_V4 | | | V | Image: A start of the start of | V | | remote IP address (IPv4) |
| 18 | - | 1 | | - / | ADDR | Array[14] of Byte | | | V | | Image: A start of the start of | | IPv4 address |
| 19 | - | t | | | ADDR[1] | Byte | 192 | | V | | \checkmark | | IPv4 address |
| 20 | - | | | | ADDR[2] | Byte | 168 | | V | | | | IPv4 address |
| 21 | - | | | | ADDR[3] | Byte | 1 | | V | | V | | IPv4 address |
| 22 | -0 | 1 | | | ADDR[4] | Byte | 5 | | V | | Image: A start of the start of | | IPv4 address |
| 23 | - | | | Rem | otePort | UInt | 502 | | V | | Image: A start of the start of | | remote UDP/TCP port number |
| 24 | - | | | Loci | Port | UInt | 0 | | | | | | local UDP/TCP port number |

Modbus Write DB

| | Mo | dbus | Wri | te1 | | | | | | | | |
|----|----|------|-------|-------------------|-------------------|-------------|--------|--------------|---|--|----------|--|
| - | | Nam | e | | Data type | Start value | Retain | Accessible f | Writa | Visible in | Setpoint | Comment |
| 1 | - | • s | tatio | | | | | | | | | |
| 2 | - | | RE | Q | Bool | false | | | | | | |
| 3 | - | | DI | sc | Bool | false | | | | | | |
| 4 | | | D | one | Bool | false | | | | | | |
| 5 | - | | Bu | isy | Bool | false | | | | | | |
| 6 | - | | Er | ror | Bool | false | | | | | | |
| 7 | - | | St | atus | Word | 16#0 | | | | | | |
| 8 | | | St | atusSave | Word | 16#0 | | | | | | |
| 9 | - | | M | ode | USInt | 1 | | | | | | |
| 10 | - | | Da | ataAddr | UDInt | 40001 | | | | | | |
| 11 | - | | Da | ataLen | Int | 60 | | | | | | |
| 12 | | • • | · C(| ONNECT | TCON_IP_v4 | | | | | | | |
| 13 | - | | | InterfaceId | HW_ANY | 64 | | | Image: A start of the start of | Image: A start of the start | | HW-identifier of IE-interface submodule |
| 14 | | | | ID | CONN_OUC | 2 | | V | v | Image: A start and a start | | connection reference / identifier |
| 15 | - | | | ConnectionType | Byte | 11 | | ~ | Image: A start of the start of | | | type of connection: 11=TCP/IP, 19=UDP (17=TCP) |
| 16 | | | | ActiveEstablished | Bool | true | | V | Image: A start of the start of | | | active/passive connection establishment |
| 17 | - | | - | RemoteAddress | IP_V4 | | | ~ | Image: A start of the start of | | | remote IP address (IPv4) |
| 18 | | | | ▼ ADDR | Array[14] of Byte | | | ~ | Image: A start of the start of | Image: A start and a start | | IPv4 address |
| 19 | | | | ADDR[1] | Byte | 192 | | \checkmark | Image: A start of the start of | Image: A start and a start | | IPv4 address |
| 20 | - | | | ADDR[2] | Byte | 168 | | × | Image: A start of the start of | Image: A start of the start | | IPv4 address |
| 21 | | | | ADDR[3] | Byte | 1 | | > | V | V | | IPv4 address |
| 22 | - | | | ADDR[4] | Byte | 5 | | | Image: A start of the start of | | | IPv4 address |
| 23 | - | | | RemotePort | UInt | 502 | | > | V | Image: A start of the start | | remote UDP/TCP port number |
| 24 | - | | | LocalPort | UInt | 0 | | | V | ¥ | | local UDP/TCP port number |



All the data needed for the correct configuration is in the Start value (default value) of each variable in the ModbusRead & Modbus Write DB.

Below there is a Description of each parameter for the MB CLIENT function coming from the DB ModbusRead, ModbusWrite, ReadData and WriteData. **Make sure to update the IP address in the parameter (STOP and START CPU after to update the data)**:

- EN Function Enable (TRUE)
- REQ Communication Request (One shot)
- Disconnect Disconnect the communication connection (0=Connected)
- MB_MODE Modbus Request Mode (0=Read, 1= Write)
- MB_DATA_ADDR Data Starting Address (Read= 30045, Write= 40001)
- MB_DATA_LEN Data Length (60x UINT registers)
- MB_DATA_PTR Pointer to a data buffer for the data (ReadData or WriteData)
- CONNECT Connection information structure
 - Interfaced (64)
 - ID (unique for each MB Client)
 - \circ Connection Type (11= TCP)
 - ActiveEstablished (TRUE)
 - Remote Address (IP Addresse)
 - Remote Port (502)
- Done Modbus request completed without errors.
- Busy Modbus request being processed
- Error Error occurred. The cause of error is indicated by the STATUS parameter.
- Status Communication Status
 - 0000 Instruction executed without errors.
 - o 0001 Connection established.
 - 0003 Connection terminated.
 - 7000 No job active and no connection established (REQ=0, DISCONNECT=1).
 - o 7001 Connection establishment triggered.
 - o 7002 Intermediate call. Connection is being established.
 - 7003 Connection is being terminated.
 - o 7004 Connection established and monitored. No job processing active.
 - 7005 Data is being sent.
 - 7006 Data is being received.
 - 8xxx Error Status,

The Sigmalogic take aroud 20sec to start. A timeout timer was added in the code example to refresh the communication every 4 second if the communication is not established.



Siemens PLC - ReadData & WriteData

Reading data are stored in the ReadData DB (array of 60 UINT). Writing data are taken from the WriteData DB (Array of 60 UINT). The value can be directly changed in the WriteData DB to control the SigmaLogic. The Memory map can be found in the document *"SigmaLogic Modbus_TCP Memory Map.xlsx"*. In this configuration, the Data is written from register **40001** to **40060**. It is read from **30045** to **300104**.

Siemens PLC - YAS_AXIS_CTRL

YAS_AXIS_CTRL function was created to simplify the data management from the communication (read and write data). This function is taking care of the data type conversion. It is taking 60 x UINT from the Read Data DB and converting them in usable data (BOOL, DINT etc). It is also converting usable data in 60 x UINT to store them in the WriteData DB.

A DB have to be created for each SigmaLogic (YAS_AXIS_CTRL_DBx). In the configuration example, a SERVO_DATAx DB was also created to create variable giving information to the Input and Ouput of YAS_AXIS_CTRL function.

| SigmaLogic1 | SigmaLogic2 |
|--------------------------|--------------------------|
| YAS_AXIS_CTRL_DB1 (DB20) | YAS_AXIS_CTRL_DB2 (DB21) |
| SERVO_DATA1 (DB10) | SERVO_DATA2 (DB11) |

To run the SigmaLogic, the user can open the SERVO _DATA DB and manually change the information:

- Motion Profile (accel, decel, speed, distance, position)
- ServoOn Rq
- Error Reset (Controller or drive)
- Homing
- Etc.

It can also be used to monitor information:

- Actual Position
- Actual Speed
- Error
- Status
- Etc.

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YAS_AXIS_CTRL Function:





Servo_DATA DB:

| | SE | RVO | _DATA1 | | | | | | | | |
|----|-----|------|--------------------|-----------|-------------|---------------|--------|--------------|-------|------------|----------|
| | | Name | | Data type | Start value | Monitor value | Retain | Accessible f | Writa | Visible in | Setpoint |
| 1 | | | Static | | | | | | | | |
| 2 | | | ServoON | Bool | false | FALSE | | | | | |
| 3 | | | ServoAlmReset | Bool | false | FALSE | | | | | |
| 4 | -00 | | ControllerAlmReset | Bool | false | FALSE | | | | | |
| 5 | - | | Reboot Controller | Bool | false | FALSE | | | | | |
| 6 | | | HomeType | Int | 1 | 1 | | | | | |
| 7 | | | Home | Bool | false | FALSE | | | | | |
| 8 | | | Start Move | Bool | false | FALSE | | | | | |
| 9 | -00 | | Abort Move | Bool | false | FALSE | | | | | |
| 10 | - | | HeartbeatAW | Bool | false | FALSE | | | | | |
| 11 | - | | Acc | Dint | 5000 | 5000 | | | | | |
| 12 | - | | Dec | Dint | 5000 | 5000 | | | | | |
| 13 | | | Velocity | Dint | 1000 | 1000 | | | | | |
| 14 | - | | Distance | Dint | 2000 | 2000 | | | | | |
| 15 | - | | Position | Dint | 0 | 0 | | | | | |
| 16 | | | Resolution | Int | 3 | 3 | | | | | |
| 17 | - | | MoveType | Int | 1 | 1 | lene l | | | | |
| 18 | - | | Alarm | Bool | false | FALSE | | | | | |
| 19 | | 1 = | Warning | Bool | false | FALSE | | | | | |
| 20 | - | | Ready | Bool | false | FALSE | | | | | |
| 21 | | | Enable | Bool | false | FALSE | | | | | |
| 22 | | | Stop Complete | Bool | false | FALSE | | | | | |
| 23 | | | Home Complete | Bool | false | FALSE | | | | | |
| 24 | | | Move Abs Complete | Bool | false | FALSE | | | | | |
| 25 | | | Move Abs Busy | Bool | false | FALSE | | | | | |
| 26 | | | Move Rel Complete | Bool | false | FALSE | | | | | |
| 27 | |] = | Move Rel Busy | Bool | false | FALSE | | | | | |
| 28 | | | Actual Position | DInt | 0 | 0 | | | | | |
| 29 | - | | Actual Speed | Dint | 0 | 0 | | | | | |
| 30 | - | | Actual Torque | Dint | 0 | 0 | | | | | |
| 31 | - | | Servo Alarm ID | UInt | 0 | 0 | | | | | |

More information on the SigmaLogic7 Modbus can be found in the SigmaLogic7 DirectControl User Guide:

https://www.yaskawa.com/downloads/searchindex/details?showType=details&docnum=TM.SigmaLogic7.01

It will describe in details each functions and other information about the interface needed for the programmer to enable the servo, execute motion operations and monitor axis feedback.