

Modbus User Manual



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Modbus User Manual

Covers the following Modbus® RTU enabled drives:

<i>ST5-Q-NE</i>	<i>STM23Q-2AE</i>	<i>TSM11Q-1RM</i>
<i>ST5-Q-NF</i>	<i>STM23Q-2AN</i>	<i>TSM11Q-2RM</i>
<i>ST5-Q-NN</i>	<i>STM23Q-2RE</i>	<i>TSM11Q-3RM</i>
<i>ST5-Q-RE</i>	<i>STM23Q-2RN</i>	
<i>ST5-Q-RN</i>	<i>STM23Q-3AE</i>	<i>TSM17Q-1AG</i>
	<i>STM23Q-3AN</i>	<i>TSM17Q-1RG</i>
<i>ST10-Q-NE</i>	<i>STM23Q-3RE</i>	<i>TSM17Q-2AG</i>
<i>ST10-Q-NF</i>	<i>STM23Q-3RN</i>	<i>TSM17Q-2RG</i>
<i>ST10-Q-NN</i>		<i>TSM17Q-3AG</i>
<i>ST10-Q-RE</i>	<i>STM24QF-3AE</i>	<i>TSM17Q-3RG</i>
<i>ST10-Q-RN</i>	<i>STM24QF-3AN</i>	<i>TSM23Q-2AG</i>
	<i>STM24QF-3RE</i>	<i>TSM23Q-2RG</i>
<i>STM17Q-3AE</i>	<i>STM24QF-3RN</i>	<i>TSM23Q-3AG</i>
<i>STM17Q-3AN</i>		<i>TSM23Q-3RG</i>
<i>STM17Q-3RE</i>	<i>SV2A3-Q-RE</i>	
<i>STM17Q-3RN</i>	<i>SV2A3-Q-RE</i>	<i>TXM24Q-1AG</i>
	<i>SV2A5-Q-RE</i>	<i>TXM24Q-1RG</i>
	<i>SV2A5-Q-RE</i>	<i>TXM24Q-3AG</i>
		<i>TXM24Q-3RG</i>
	<i>SWM24QF-3AE</i>	
	<i>SWM24QF-3AN</i>	

What is Modbus?

Modbus, originally created by Modicon, is a fieldbus that allows a master and one or more slave devices to share data. These data are organized into 16-bit registers, which can also be used to share information single-bit I/O points.

It is a popular protocol with PLC vendors due to its simplicity and the inherent ease of sending PLC register data (often 16-bits in width) over a fieldbus protocol optimized for 16-bit data.

The master may initiate read and write operations on single registers or blocks of registers. While there is no rule to this effect, it is common for the master to read and write on a periodic time base (polling), rather than sending and requesting data only when it is needed. In this manner, PLC register data is ensured to be valid and consistent as a representation of the slave device's status.

Wiring

Modbus/RTU:

Modbus RTU uses the standard RS-232 or RS-485 physical layer.

RS-232 is a point-to-point communications scheme, and as such the largest possible network would consist of a single slave drive. Please note that even though it will be the only device on the "network", it will still require an address. This address may be an integer value from 1-32, and is set through the *ST Configurator™* software during initial configuration.

For drives with RS-485 communications, there are a few things to consider.

It is possible to use 2-wire RS-485 for operational communication over Modbus, however 4-wire RS-485 is required for use with all Applied Motion configuration and programming software (i.e., *ST Configurator™* and *Q Programmer™*). As such, we recommend that all RS-485 networks be constructed using the 4-wire method.

Be sure to consult your drive's hardware manual for specific wiring details.

Drive configuration

Modbus/RTU Drive Configuration:

First, download and install the most recent version of the appropriate software from the Applied Motion Products website (www.applied-motion.com). For the ST, STAC, and STM series, use *ST Configurator™* software. For the TSM series, use *Step-Servo Quick Tuner™*. For SV2 models, use *SVX Servo Suite™*. For RS-485 drives you will also need a USB-to-RS-485 converter, such as the USB-COMi-M module available from AMP. Consult your drive's manual for wiring and general communication instructions.

1. Launch software and select the appropriate COM port.
2. Apply power to the drive. Note, perform this step with only a single drive on the network. Each drive must be configured individually before it may be used on a network.
3. The Software will automatically identify the drive, but will not upload all parameters. Click "Upload from Drive". This will ensure that the software accurately reflects the current state of the drive's configuration parameters.
4. Click "Motion & I/O" in *ST Configurator™*. In *Step-Servo Quick Tuner™* and *SVX Servo Suite™* use the *Configuration panel*.
5. Specify the drive's node address and baud rate.

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6. For drives with Flex/IO, confirm the desired I/O settings. Click OK to return to the main screen.
7. Set any desired motor and encoder configurations your application may require.
8. Click Download to Drive to save the settings.
9. Optionally, use *Q Programmer™* to write and download a program for this axis. The drive may be configured to launch the program automatically upon powerup, or to wait for the QX command to be sent from the Modbus master.
10. Remove power from the drive and install into the main machine network.
11. Repeat for all other slave nodes, taking care to ensure each has a unique node address.

Note, the drive must be rebooted to switch between Modbus and configuration modes.

Drive Behavior

An extensive list of registers has been made available, allowing the user to monitor or change every detail of the drive's status. It is also possible to send commands to a specific register, mimicking the behavior of our proprietary SCL command set. The capability allows a PLC to have unparalleled control over the drive's behavior at runtime.

The drive will respond to the following Modbus function codes:

- | | |
|----|--------------------------|
| 3 | Read Holding Registers |
| 4 | Read Input Registers |
| 6 | Write Single Register |
| 16 | Write Multiple Registers |

Monitoring

See the Register Map table for details on specific data that can be monitored and written in this manner.

Sending Commands

The Command Opcode register, 40125, is designated to receive encoded SCL commands via Modbus. Many SCL commands have been made available in this manner, and will allow the user full control over the motion capabilities of the drive.

SCL command encoding details can be found in the Modbus Register Table.

Please refer to the Host Command Reference for details of the functionality of these registers and commands.

Examples

Point-to-Point Moves

Four pieces of data are required to fully define a point-to-point move. Acceleration, Deceleration, Distance, and Velocity. Followed of course by the move command itself. To command such a move over Modbus, we must first write to the aforementioned control registers, then send the command.

Function	Register	Value	Notes
Acceleration	40028	100	Units: 10 RPM/sec
Deceleration	40029	100	Units: 10 RPM/sec
Velocity	40030	240	Units: 0.25 RPM
Distance	40031..32	20000	This register is affected by Endianness setting

Now it's time for the command itself. The most common point-to-point move is the Feed to Length which uses the SCL command FL. In Modbus we do the following:

The drive will execute the move command immediately, pulling the relevant parameter data from the above registers. It is immediately ready to accept another command. Note, it is not necessary to send parameter data with each command, unless this data changes between moves. For example, to repeat a move simply send the command again, leaving the relevant parameter data unchanged.

Function	Register	Value	Notes
FL Command	40125	102	0x66 (Hexadecimal) is equal to 102

Launch a Q Program

It is possible to execute a stored Q program over Modbus using the QX command (opcode 0x78). This command requires a value to be written to Parameter 1, the first of 5 registers set aside for command-dependant parameter data.

To launch the program at segment 1, we would use the SCL command QX1. Over Modbus, the following procedure applies.

First, configure the parameter data (only Parameter 1 is used by this command).

Function	Register	Value	Notes
Parameter 1	40126	1	Q segment to execute. Integer: 1..12

Now we can send the QX command itself.

Function	Register	Value	Notes
QX Command	40125	120	0x78 (Hexadecimal) is equal to 120 decimal

Note, to stop a command or interrupt a Q program, either the SK or SKD commands may be used.

Function	Register	Value	Notes
SK Command	40125	225	0xE1 (Hexadecimal) is equal to 225

Function	Register	Value	Notes
SKD Command	40125	226	0xE2 (Hexadecimal) is equal to 226

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Modbus Register Table				
Register	Access	Data Type	Description	SCL Register
40001	Read Only	SHORT	Alarm Code (AL)	f
40002	Read Only	SHORT	Status Code (SC)	s
40003	Read Only	SHORT	Immediate Expanded Inputs (IS) Output Status (Only for SV200)	y
40004	Read Only	SHORT	Input Status	i
40005..6	Read Only	LONG	Encoder Position (IE, EP)	e
40007..8	Read Only	LONG	Immediate Absolute Position	l
40009..10	Write	LONG	Absolute Position Command	P
40011	Read Only	SHORT	Immediate Actual Velocity (IV0)	v
40012	Read Only	SHORT	Immediate Target Velocity (IV1)	w
40013	Read Only	SHORT	Immediate Drive Temperature (IT)	t
40014	Read Only	SHORT	Immediate Bus Voltage (IU)	u
40015..16	Read Only	LONG	Immediate Position Error (IX)	x
40017	Read Only	SHORT	Immediate Analog Input Value (IA)	a
40018	Read Only	SHORT	Q Program Line Number	b
40019	Read Only	SHORT	Immediate Current Command (IC)	c
40020..21	Read Only	LONG	Relative Distance (ID)	d
40022..23	Read Only	LONG	Sensor Position	g
40024	Read Only	SHORT	Condition Code	h
40025	Read Only	SHORT	Analog Input 1 (IA1)	j
40026	Read Only	SHORT	Analog Input 2 (IA2)	k
40027	Read Only	SHORT	Command Mode (CM)	m
40028	R/W	SHORT	Point-to-Point Acceleration (AC)	A
40029	R/W	SHORT	Point-to-Point Deceleration (DE)	B
40030	R/W	SHORT	Velocity (VE)	V
40031..32	R/W	LONG	Point-to-Point Distance (DI)	D
40033..34	R/W	LONG	Change Distance (DC)	C
40035	R/W	SHORT	Change Velocity (VC)	U
40036	Read Only	SHORT	Velocity Move State	n
40037	Read Only	SHORT	Point-to-Point Move State	o
40038	Read Only	SHORT	Q Program Segment Number	p
40039	Read Only	SHORT	Average Clamp Power (regen) *	r
40040	Read Only	SHORT	Phase Error	z
40041..42	R/W	LONG	Position Offset	E
40043	R/W	SHORT	Miscellaneous Flags	F
40044	R/W	SHORT	Current Command (GC)	G

*Not applicable to SV200 series

¹ For SV200 drives: Max. Velocity Limit

² For SV200 series, Firmware Version (ASCII value)

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40045..46	R/W	LONG	Input Counter	I
40047	R/W	SHORT	Jog Accel (JA)	
40048	R/W	SHORT	Jog Decel (JL)	
40049	R/W	SHORT	Jog Velocity (JS)	J
40050	R/W	SHORT	Accel/Decel Current (CA) ¹	
40051	R/W	SHORT	Running Current (CC) for stepper, Continuous Current for servo	N
40052	R/W	SHORT	Idle Current (CI) for stepper Peak Current (CP) for servo	O
40053	R/W	SHORT	Steps per Revolution *	R
40054~40055	R/W	LONG	Pulse Counter	S
40056	R/W	SHORT	Analog Position Gain (AP)	X
40057	R/W	SHORT	Analog Threshold (AT)	Y
40058	R/W	SHORT	Analog Offset (AV)	Z
40059..60	R/W	LONG	Accumulator	0
40061..62	R/W	LONG	User Defined Register	1
40063..64	R/W	LONG	User Defined Register	2
40065..66	R/W	LONG	User Defined Register	3
40067..68	R/W	LONG	User Defined Register	4
40069..70	R/W	LONG	User Defined Register	5
40071..72	R/W	LONG	User Defined Register	6
40073..74	R/W	LONG	User Defined Register	7
40075..76	R/W	LONG	User Defined Register	8
40077..78	R/W	LONG	User Defined Register	9
40079..80	R/W	LONG	User Defined Register	:
40081..82	R/W	LONG	User Defined Register	;
40083..84	R/W	LONG	User Defined Register	<
40085..86	R/W	LONG	User Defined Register	=
40087..88	R/W	LONG	User Defined Register	>
40089..90	R/W	LONG	User Defined Register	?
40091..92	R/W	LONG	User Defined Register	@
40093..94	R/W	LONG	User Defined Register	[
40095..96	R/W	LONG	User Defined Register	\
40097..98	R/W	LONG	User Defined Register]
40099..100	R/W	LONG	User Defined Register	^
40101..102	R/W	LONG	User Defined Register	_
400103..104	R/W	LONG	User Defined Register	`
40105	R/W	SHORT	Brake Release Delay	

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40106	R/W	SHORT	Brake Engage Delay	
40107	R/W	SHORT	Idle Current Delay *	
40108	R/W	SHORT	Hyperbolic Smoothing Gain *	
40109	Read Only	SHORT	Hyperbolic Smoothing Phase ²	
40110	R/W	SHORT	Analog Filter Gain	
40111	Read Only	SHORT	(reserved)	
40112	Read Only	SHORT	Alarm Code High bits	
40113	R/W	SHORT	Jog Change Speed1 (JC1)	
40114	R/W	SHORT	Jog Change Speed2 (JC2)	
40115	R/W	SHORT	Jog Change Speed3 (JC3)	
40116	R/W	SHORT	Jog Change Speed4 (JC4)	
40117	R/W	SHORT	Jog Change Speed5 (JC5)	
40118	R/W	SHORT	Jog Change Speed6 (JC6)	
40119	R/W	SHORT	Jog Change Speed7 (JC7)	
40120	R/W	SHORT	Jog Change Speed8 (JC8)	
40121	R/W	SHORT	X9 Input Filter	
40122	R/W	SHORT	X10 Input Filter	
40123	R/W	SHORT	X11 Input Filter	
40124	R/W	SHORT	X12 Input Filter	
40125	R/W	SHORT	Command Opcode	
40126	R/W	SHORT	Parameter 1	
40127	R/W	SHORT	Parameter 2	
40128	R/W	SHORT	Parameter 3	
40129	R/W	SHORT	Parameter 4	
40130	R/W	SHORT	Parameter 5	
40131	R/W	SHORT	Global Gain	
40132	R/W	SHORT	Global Gain1	
40133	R/W	SHORT	Proportional Gain (KF) Position Loop	
40134	R/W	SHORT	Differential Gain (KD) "Damping" Gain	
40135	R/W	SHORT	Velocity Feedback Gain (KV)	
40136	R/W	SHORT	Integral Gain (KI)	
40137	R/W	SHORT	Inertia Feedforward Gain (KK)	
40138	R/W	SHORT	Jerk Filter (KJ) "Smoothing" Filter	
40139	R/W	SHORT	Velocity Loop Proportional Gain (VP)	
40140	R/W	SHORT	Velocity Loop Integral Gain (VI)	
40141	R/W	SHORT	Damping Filter Gain (KE)	
40142	R/W	SHORT	Current Filter Gain (KC)	
40143	R/W	SHORT	Control Mode (CM)	

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40144	R/W	SHORT	Control Mode 1	
40145	R/W	SHORT	Operating Mode "Power-up Mode"	
40146	R/W	SHORT	Jog Mode (JM)	
40147	R/W	SHORT	Hard-Stop Current Limit (HC)	
40148	R/W	SHORT	Max Acceleration (AM)	
40149	Read Only	SHORT	Encoder Resolution (quad counts divided by motor poles)	
40150	Read Only	SHORT	(Reserved)	
40151	Read Only	SHORT	½ Electronic Gearing value (Step Resolution)	
40152	R/W	SHORT	Electronic Ratio Numerator	
40153	R/W	SHORT	Electronic Ratio Denominator	
40154	R/W	SHORT	Step Input Pulse Type (lower bits) Step Input Noise Filter (upper bits)	
40155	R/W	SHORT	Position Fault limit (PF)	
40156	R/W	SHORT	In-Position Count	
40157	R/W	SHORT	Position Error Range	
40158	R/W	SHORT	In-Range Count	
40159	R/W	SHORT	Pulse Input Complete Time	
40160	R/W	SHORT	Analog Velocity Gain	
40161	R/W	SHORT	Analog Torque Gain	
40162	R/W	SHORT	Analog Offset 1	
40163	R/W	SHORT	Analog Offset 2	
40164	R/W	SHORT	Analog Type	
40165	R/W	SHORT	Analog Deadband 1	
40166	R/W	SHORT	Analog Deadband 2	
40167	R/W	SHORT	Differential Analog Deadband	
40168	R/W	SHORT	Analog Function	
40169	R/W	SHORT	Servo Enable Input Usage (SI)	
40170	R/W	SHORT	Alarm Reset Input (AI)	
40171	R/W	SHORT	Define Limits Input (DL)	
40172	R/W	SHORT	Motion Input X7 X8 X9 X10 inputs	
40173	R/W	SHORT	Alarm Output(AO)	
40174	R/W	SHORT	Brake Output (BO)	
40175	R/W	SHORT	Motion Output Y3 Y4 Y5 Y6 inputs	
40176		SHORT	(Reserved)	
40177	R/W	SHORT	Communication Protocol (PR)	
40178	R/W	SHORT	Transmit Delay (TD)	
40179	R/W	SHORT	Baud Rate (BR)	

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40180	R/W	SHORT	Communication Address (DA represented as ASCII value)	
40181	R/W	SHORT	Velocity Reached Value	
40182	R/W	SHORT	Tach-out Count setting	
40183	R/W	SHORT	Torque Reached Value (Units: 0.01A)	
40184	R/W	SHORT	Front Panel Parameters Lock	
40185	R/W	SHORT	Front Panel Default Display setting	
40186	R/W	SHORT	Mask Alarm setting	
40187	R/W	SHORT	Homing Acceleration 1	
40188	R/W	SHORT	Homing Acceleration 2	
40189	R/W	SHORT	Homing Acceleration 3	
40190	R/W	SHORT	Homing Deceleration 1	
40191	R/W	SHORT	Homing Deceleration 2	
40192	R/W	SHORT	Homing Deceleration 3	
40193	R/W	SHORT	Homing Velocity 1	
40194	R/W	SHORT	Homing Velocity 2	
40195	R/W	SHORT	Homing Velocity 3	
40196	R/W	SHORT	Clamp Resistance	
40197	R/W	SHORT	Clamp Count	
40198	R/W	SHORT	Clamp time	
40199	Read Only	SHORT	Drive Model ID Number	
40200	Read Only	SHORT	Drive Sub Model ID Number	

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SCL Command Encoding Table							
Function	SCL	Opcode	Parameter 1	Parameter 2	Parameter 3	Parameter 4	Parameter 5
Alarm Reset	AX	0xBA	N/A	N/A	N/A	N/A	N/A
Start Jogging	CJ	0x96	N/A	N/A	N/A	N/A	N/A
Stop Jogging	SJ	0xD8	N/A	N/A	N/A	N/A	N/A
Encoder Function	EF	0xD6	0,1,2 or 6	N/A	N/A	N/A	N/A
Encoder Position	EP	0x98	Position	N/A	N/A	N/A	N/A
Feed to Double Sensor	FD	0x69	I/O Point 1	Condition 1	I/O Point 2	Condition 2	N/A
Follow Encoder	FE	0xCC	I/O Point	Condition	N/A	N/A	N/A
Feed to Length	FL	0x66	N/A	N/A	N/A	N/A	N/A
Feed to Sensor with Mask Distance	FM	0x6A	I/O Point	Condition	N/A	N/A	N/A
Feed and Set Output	FO	0x68	I/O Point	Condition	N/A	N/A	N/A
Feed to Position	FP	0x67	N/A	N/A	N/A	N/A	N/A
Feed to Sensor	FS	0x6B	I/O Point	Condition	N/A	N/A	N/A
Feed to Sensor with Safety Distance	FY	0x6C	I/O Point	Condition	N/A	N/A	N/A
Jog Disable	JD	0xA3	N/A	N/A	N/A	N/A	N/A
Jog Enable	JE	0xA2	N/A	N/A	N/A	N/A	N/A
Motor Disable	MD	0x9E	N/A	N/A	N/A	N/A	N/A
Motor Enable	ME	0x9F	N/A	N/A	N/A	N/A	N/A
Seek Home	SH	0x6E	I/O Point	Condition	N/A	N/A	N/A
Set Position	SP	0xA5	Position	N/A	N/A	N/A	N/A
Filter Input	FI	0xC0	I/O Point	Filter Time	N/A	N/A	N/A
Filter Select Inputs	FX	0xD3	N/A	N/A	N/A	N/A	N/A
Step Filter Freq	SF	0x06	Freq	N/A	N/A	N/A	N/A
Analog Deadband	AD	0xD2	0.001 V	N/A	N/A	N/A	N/A
Alarm Reset Input	AI	0x46	Function ('1'..'3')	I/O Point	N/A	N/A	N/A
Alarm Output	AO	0x47	Function ('1'..'3')	I/O Point	N/A	N/A	N/A
Analog Scaling	AS	0xD1	N/A	N/A	N/A	N/A	N/A
Define Limits	DL	0x42	1..3	N/A	N/A	N/A	N/A
Set Output	SO	0x8B	I/O Point	Condition	N/A	N/A	N/A
Wait for Input	WI	0x70	N/A	N/A	N/A	N/A	N/A
Queue Load & Execute	QX	0x78	1..12	N/A	N/A	N/A	N/A
Wait Time	WT	0x6F	0.01 sec	N/A	N/A	N/A	N/A
Stop Move, Kill Buffer	SK	0xE1	N/A	N/A	N/A	N/A	N/A
Stop Move, Kill Buffer, Normal Decel	SKD	0xE2	N/A	N/A	N/A	N/A	N/A

N/A = Not Applicable

Notes:

- 32-bit values may be either big-endian or little-endian. Endianness is determined by Bit 6 of the PR command word. It is recommended that this setting be configured with the configuration software.
- Consult the I/O Encoding Table for details on parameter data for commands referencing I/O.

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IO Encoding Table

Useful ASCII values for IO commands. Character values shown are taken from standard SCL command nomenclature. For example, a Feed to Sensor command example may utilize the falling edge of input 1 and appear as FS1F. To encode this command the user would select 0x31 for the character '1' and 0x46 for the character 'F'. These codes must be written to the appropriate parameter register before writing the desired command opcode to register 40125.

Character	hex code	
'0'	0x30	encoder index
'1'	0x31	input 1 or output 1
'2'	0x32	input 2 or output 2
'3'	0x33	input 3 or output 3
'4'	0x34	input 4 or output 4
'5'	0x35	input 5 or output 5
'6'	0x36	input 6 or output 6
'7'	0x37	input 7
'8'	0x38	input 8
'9'	0x39	input 9
':'	0x3A	input 10
';'	0x3B	input 11
'<'	0x3C	input 12
'L'	0x4C	low state (closed)
'H'	0x48	high state (open)
'R'	0x52	rising edge
'F'	0x46	falling edge



Applied Motion Products
404 Westridge Drive
Watsonville, CA 95076
USA

tel / 831-761-6555

fax / 831-761-6544

www.applied-motion.com