

Description of TGZ main parameters

Name	Axis	Basic Group	Index (ETH)	Group Index	Item Index	Access	Unit	Size	Description [EN]
C-Type1		Common	0x2000	0	0	read-only	chars	32 bits	Servo drive hw type 1/5
C-Type2		Common	0x2001	0	1	read-only	chars	32 bits	Servo drive hw type 2/5
C-Type3		Common	0x2002	0	2	read-only	chars	32 bits	Servo drive hw type 3/5
C-Type4		Common	0x2003	0	3	read-only	chars	32 bits	Servo drive hw type 4/5
C-Type5		Common	0x2004	0	4	read-only	chars	32 bits	Servo drive hw type 5/5
C-HWVer		Common	0x2005	0	5	read-only	chars	32 bits	HW version
C-FWVer		Common	0x2006	0	6	read-only	chars	32 bits	Firmware version
C-FWBuild1		Common	0x2007	0	7	read-only	chars	32 bits	Firmware build 1/5
C-FWBuild2		Common	0x2008	0	8	read-only	chars	32 bits	Firmware build 2/5
C-FWBuild3		Common	0x2009	0	9	read-only	chars	32 bits	Firmware build 3/5
C-FWBuild4		Common	0x200A	0	10	read-only	chars	32 bits	Firmware build 4/5
C-FWBuild5		Common	0x200B	0	11	read-only	chars	32 bits	Firmware build 5/5
C-IPAddress		Common	0x200C	0	12	read-write	-	32 bits	IP address X11 service UDP channel
C-ID		Common	0x200D	0	13	read-write	-	32 bits	ID fieldbus
C-SyncTime		Common	0x200E	0	14	read-only	-	32 bits	Measured time between synchronization pulses (only for DC functionality)
C-Enable_1G		Common	0x200F	0	15	read-write	-	32 bits	Enable 1G speed fieldbus (preparing)
C-SetCycleTime		Common	0x2010	0	16	read-write	us	32 bits	Desired cycle time (used only without DC functionality)
C-UserProgStart		Common	0x2011	0	17	read-write	-	32 bits	Enable autostart of user program : 0 .. no autostart, 1 .. autostart from flash memory, (2 .. autostart from SD .. preparing)
M-Name1	Axis 1	Motor	0x2100	1	0	read-write	chars	32 bits	Motor name 1 1/6
M-Name1	Axis 2	Motor	0x2200	2	0	read-write	chars	32 bits	Motor name 2 1/6
M-Name2	Axis 1	Motor	0x2101	1	1	read-write	chars	32 bits	Motor name 1 2/6
M-Name2	Axis 2	Motor	0x2201	2	1	read-write	chars	32 bits	Motor name 2 2/6
M-Name3	Axis 1	Motor	0x2102	1	2	read-write	chars	32 bits	Motor name 1 3/6
M-Name3	Axis 2	Motor	0x2202	2	2	read-write	chars	32 bits	Motor name 2 3/6
M-Name4	Axis 1	Motor	0x2103	1	3	read-write	chars	32 bits	Motor name 1 4/6
M-Name4	Axis 2	Motor	0x2203	2	3	read-write	chars	32 bits	Motor name 2 4/6
M-Name5	Axis 1	Motor	0x2104	1	4	read-write	chars	32 bits	Motor name 1 5/6
M-Name5	Axis 2	Motor	0x2204	2	4	read-write	chars	32 bits	Motor name 2 5/6
M-Name6	Axis 1	Motor	0x2105	1	5	read-write	chars	32 bits	Motor name 1 6/6
M-Name6	Axis 2	Motor	0x2205	2	5	read-write	chars	32 bits	Motor name 2 6/6
M-Inull	Axis 1	Motor	0x2106	1	6	read-write	mA(rms)	32 bits	Allowed stall rms current of motor 1
M-Inull	Axis 2	Motor	0x2206	2	6	read-write	mA(rms)	32 bits	Allowed stall rms current of motor 2
M-Ipeak	Axis 1	Motor	0x2107	1	7	read-write	mA	32 bits	Allowed peak current amplitude of motor 1 (Iamp = 1.41 * Irms)
M-Ipeak	Axis 2	Motor	0x2207	2	7	read-write	mA	32 bits	Allowed peak current amplitude of motor 2 (Iamp = 1.41 * Irms)
M-Nmax	Axis 1	Motor	0x2108	1	8	read-write	rpm	32 bits	Maximal mechanical speed of motor 1 - error limit
M-Nmax	Axis 2	Motor	0x2208	2	8	read-write	rpm	32 bits	Maximal mechanical speed of motor 2 - error limit
M-Polepairs	Axis 1	Motor	0x2109	1	9	read-write	-	32 bits	Number of motor 1 polepairs (polepairs = poles / 2)
M-Polepairs	Axis 2	Motor	0x2209	2	9	read-write	-	32 bits	Number of motor 2 polepairs (polepairs = poles / 2)
M-CommutOffset	Axis 1	Motor	0x210A	1	10	read-write	-	32 bits	Angle offset between zero of feedback encoder and stator of motor 1
M-CommutOffset	Axis 2	Motor	0x220A	2	10	read-write	-	32 bits	Angle offset between zero of feedback encoder and stator of motor 2
M-MinResTerm	Axis 1	Motor	0x210B	1	11	read-write	Ohm	32 bits	Limit for overtemperature error - Minimal resistivity of motor 1 thermal sensor (used only for digital feedback with connected thermal sensor)
M-MinResTerm	Axis 2	Motor	0x220B	2	11	read-write	Ohm	32 bits	Limit for overtemperature error - Minimal resistivity of motor 2 thermal sensor (used only for digital feedback with connected thermal sensor)
M-MaxResTerm	Axis 1	Motor	0x210C	1	12	read-write	Ohm	32 bits	Limit for overtemperature error - Maximal resistivity of motor 1 thermal sensor (used only for digital feedback with connected thermal sensor)
M-MaxResTerm	Axis 2	Motor	0x220C	2	12	read-write	Ohm	32 bits	Limit for overtemperature error - Maximal resistivity of motor 2 thermal sensor (used only for digital feedback with connected thermal sensor)
M-StaticBrake	Axis 1	Motor	0x210D	1	13	read-write	-	32 bits	Motor 1 static brake: 1 = yes , 0 = no
M-StaticBrake	Axis 2	Motor	0x220D	2	13	read-write	-	32 bits	Motor 2 static brake: 1 = yes , 0 = no
M-ThermTimeConst	Axis 1	Motor	0x210E	1	14	read-write	s	32 bits	ThermalTimeConstant of motor 1
M-ThermTimeConst	Axis 2	Motor	0x220E	2	14	read-write	s	32 bits	ThermalTimeConstant of motor 2
D-Name1	Axis 1	Drive	0x2300	3	0	read-write	chars	32 bits	Drive 1 name 1/3
D-Name1	Axis 2	Drive	0x2400	4	0	read-write	chars	32 bits	Drive 2 name 1/3
D-Name2	Axis 1	Drive	0x2301	3	1	read-write	chars	32 bits	Drive 1 name 2/3
D-Name2	Axis 2	Drive	0x2401	4	1	read-write	chars	32 bits	Drive 2 name 2/3
D-Name3	Axis 1	Drive	0x2302	3	2	read-write	chars	32 bits	Drive 1 name 3/3
D-Name3	Axis 2	Drive	0x2402	4	2	read-write	chars	32 bits	Drive 2 name 3/3

D-Mode	Axis 1	Drive	0x2303	3	3	read-write	-	32 bits	Mode of drive 1 - see manual
D-Mode	Axis 2	Drive	0x2403	4	3	read-write	-	32 bits	Mode of drive 2 - see manual
D-DelayEnable_Hwen	Axis 1	Drive	0x230A	3	10	read-write	0.1ms	32 bits	Delay enable drive 1 after HW enable signal rising edge X1
D-DelayEnable_Hwen	Axis 2	Drive	0x240A	4	10	read-write	0.1ms	32 bits	Delay enable drive 2 after HW enable signal rising edge X1
D-DelayUnbrake_Enable	Axis 1	Drive	0x230B	3	11	read-write	0.1ms	32 bits	Delay release brake of motor 1 after enable drive
D-DelayUnbrake_Enable	Axis 2	Drive	0x240B	4	11	read-write	0.1ms	32 bits	Delay release brake of motor 2 after enable drive
D-DelayDisable_Brake	Axis 1	Drive	0x230C	3	12	read-write	0.1ms	32 bits	Delay disable drive 1 after activating brake
D-DelayDisable_Brake	Axis 2	Drive	0x240C	4	12	read-write	0.1ms	32 bits	Delay disable drive 2 after activating brake
D-VoltDCLinkMinErrLim		Drive	0x230D	3	13	read-write	V	32 bits	Minimal DC link voltage - low voltage error level
D-VoltDCLinkMaxErrLim		Drive	0x230E	3	14	read-write	V	32 bits	Maximal DC link voltage - high voltage error level
C-K	Axis 1	Currentcontroller	0x2500	5	0	read-write	mV/A	32 bits	Current controller Q gain
C-K	Axis 2	Currentcontroller	0x2600	6	0	read-write	mV/A	32 bits	Current controller Q gain
C-Ti	Axis 1	Currentcontroller	0x2501	5	1	read-write	µs	32 bits	Current controller integral time
C-Ti	Axis 2	Currentcontroller	0x2601	6	1	read-write	µs	32 bits	Current controller integral time
C-KDr	Axis 1	Currentcontroller	0x2502	5	2	read-write	%	32 bits	Current controller D relative gain to K
C-KDr	Axis 2	Currentcontroller	0x2602	6	2	read-write	%	32 bits	Current controller D relative gain to K
C-Tc	Axis 1	Currentcontroller	0x2503	5	3	read-write	µs	32 bits	Time constant of current command filter (not used)
C-Tc	Axis 2	Currentcontroller	0x2603	6	3	read-write	µs	32 bits	Time constant of current command filter (not used)
C-Filt	Axis 1	Currentcontroller	0x2504	5	4	read-write	%	32 bits	Percentable value of current command (100 = 100% goes via filter) (not used)
C-Filt	Axis 2	Currentcontroller	0x2604	6	4	read-write	%	32 bits	Percentable value of current command (100 = 100% goes via filter) (not used)
C-LimN	Axis 1	Currentcontroller	0x2505	5	5	read-write	0.1%	32 bits	Current amplitude negative limit relatively to M-Inull (limiting output of speed controller)
C-LimN	Axis 2	Currentcontroller	0x2605	6	5	read-write	0.1%	32 bits	Current amplitude negative limit relatively to M-Inull (limiting output of speed controller)
C-LimP	Axis 1	Currentcontroller	0x2506	5	6	read-write	0.1%	32 bits	Current amplitude positive limit relatively to M-Inull (limiting output of speed controller)
C-LimP	Axis 2	Currentcontroller	0x2606	6	6	read-write	0.1%	32 bits	Current amplitude positive limit relatively to M-Inull (limiting output of speed controller)
C-VoltLimMin	Axis 1	Currentcontroller	0x2507	5	7	read-write	%	32 bits	Negative voltage limit (output of current controller)
C-VoltLimMin	Axis 2	Currentcontroller	0x2607	6	7	read-write	%	32 bits	Negative voltage limit (output of current controller)
C-VoltLimMax	Axis 1	Currentcontroller	0x2508	5	8	read-write	%	32 bits	Positive voltage limit (output of current controller)
C-VoltLimMax	Axis 2	Currentcontroller	0x2608	6	8	read-write	%	32 bits	Positive voltage limit (output of current controller)
C-CogCompFac	Axis 1	Currentcontroller	0x2509	5	9	read-write	%	32 bits	Cogging compensation factor 0 .. Off (Before using function must be measured compensation data of motor)
C-CogCompFac	Axis 2	Currentcontroller	0x2609	6	9	read-write	%	32 bits	Cogging compensation factor 0 .. Off (Before using function must be measured compensation data of motor)
V-K	Axis 1	Velocitycontroller	0x2700	7	0	read-write	mA/1000rpm	32 bits	Velocity controller gain
V-K	Axis 2	Velocitycontroller	0x2800	8	0	read-write	mA/1000rpm	32 bits	Velocity controller gain
V-Ti	Axis 1	Velocitycontroller	0x2701	7	1	read-write	µs	32 bits	Velocity controller integral time
V-Ti	Axis 2	Velocitycontroller	0x2801	8	1	read-write	µs	32 bits	Velocity controller integral time
V-LimN	Axis 1	Velocitycontroller	0x2702	7	2	read-write	rpm	32 bits	Velocity negative limit (limiting output of position controller)
V-LimN	Axis 2	Velocitycontroller	0x2802	8	2	read-write	rpm	32 bits	Velocity negative limit (limiting output of position controller)
V-LimP	Axis 1	Velocitycontroller	0x2703	7	3	read-write	rpm	32 bits	Velocity positive limit (limiting output of position controller)
V-LimP	Axis 2	Velocitycontroller	0x2803	8	3	read-write	rpm	32 bits	Velocity positive limit (limiting output of position controller)
V-Tfb	Axis 1	Velocitycontroller	0x2704	7	4	read-write	µs	32 bits	Time constant of velocity feedback lowpass filter (not used)
V-Tfb	Axis 2	Velocitycontroller	0x2804	8	4	read-write	µs	32 bits	Time constant of velocity feedback lowpass filter (not used)
V-Tv	Axis 1	Velocitycontroller	0x2705	7	5	read-write	µs	32 bits	Time constant of velocity command lowpass filter (not used)
V-Tv	Axis 2	Velocitycontroller	0x2805	8	5	read-write	µs	32 bits	Time constant of velocity command lowpass filter (not used)
V-FiFact	Axis 1	Velocitycontroller	0x2706	7	6	read-write	0.1%	32 bits	Velocity filter factor 0 .. not filtered (not used)
V-FiFact	Axis 2	Velocitycontroller	0x2806	8	6	read-write	0.1%	32 bits	Velocity filter factor 0 .. not filtered (not used)
P-K	Axis 1	Positioncontroller	0x2900	9	0	read-write	0.001 1/s	32 bits	Position controller gain
P-K	Axis 2	Positioncontroller	0x2A00	10	0	read-write	0.001 1/s	32 bits	Position controller gain
P-SFF	Axis 1	Positioncontroller	0x2901	9	1	read-write	0.1%	32 bits	Speed feed forward
P-SFF	Axis 2	Positioncontroller	0x2A01	10	1	read-write	0.1%	32 bits	Speed feed forward

P-MaxAngleError	Axis 1	Positioncontroller	0x2902	9	2	read-write	---	32 bits	maximal position error - angle part
P-MaxAngleError	Axis 2	Positioncontroller	0x2A02	10	2	read-write	---	32 bits	maximal position error - angle part
P-MaxRevolError	Axis 1	Positioncontroller	0x2903	9	3	read-write	---	32 bits	maximal position error - revolution part
P-MaxRevolError	Axis 2	Positioncontroller	0x2A03	10	3	read-write	---	32 bits	maximal position error - revolution part
F-Type	Axis 1	Feedback	0x2B00	11	0	read-write	-	32 bits	Feedback type : 1.. Hiperface DSL, 2.. Endat 2, 3..SSI, 4.. Incremental
F-Type	Axis 2	Feedback	0x2C00	12	0	read-write	-	32 bits	Feedback type : 1.. Hiperface DSL, 2.. Endat 2, 3..SSI, 4.. Incremental
F-Resolution	Axis 1	Feedback	0x2B01	11	1	read-write	-	32 bits	Feedback resolution per revolution(read only for digital feedbacks type 1 and 2)
F-Resolution	Axis 2	Feedback	0x2C01	12	1	read-write	-	32 bits	Feedback resolution per revolution(read only for digital feedbacks type 1 and 2)
F-IncrEnc	Axis 1	Feedback	0x2B02	11	2	read-write	pulses	32 bits	Incremental encoder feedback resolution
F-IncrEnc	Axis 2	Feedback	0x2C02	12	2	read-write	pulses	32 bits	Incremental encoder feedback resolution
F-ExtIncrEnc		Feedback	0x2B03	11	3	read-write	pulses	32 bits	External incremental encoder resolution
F-ResolverPoles	Axis 1	Feedback	0x2B04	11	4	read-write	-	32 bits	Number of resolver poles (not used - only for optional board)
F-ResolverPoles	Axis 2	Feedback	0x2C04	12	4	read-write	-	32 bits	Number of resolver poles (not used - only for optional board)
K-Command	Axis 1	Command	0x3100	17	0	read-write	-	32 bits	Command bits[1,0]=01 .. SW enable bit[3] = 1 .. Clear errors
K-Command	Axis 2	Command	0x3200	18	0	read-write	-	32 bits	Command bits[1,0]=01 .. SW enable bit[3] = 1 .. Clear errors
K-I	Axis 1	Command	0x3101	17	1	read-write	mA	32 bits	Required current (current mode = 1)
K-I	Axis 2	Command	0x3201	18	1	read-write	mA	32 bits	Required current (current mode = 1)
K-V	Axis 1	Command	0x3102	17	2	read-write	rpm	32 bits	Required velocity (velocity mode = 2)
K-V	Axis 2	Command	0x3202	18	2	read-write	rpm	32 bits	Required velocity (velocity mode = 2)
K-P_Angle	Axis 1	Command	0x3103	17	3	read-write	-	32 bits	Required position - angle (position mode = 3)
K-P_Angle	Axis 2	Command	0x3203	18	3	read-write	-	32 bits	Required position - angle (position mode = 3)
K-P_Revol	Axis 1	Command	0x3104	17	4	read-write	-	32 bits	Required position - revolutions (position mode = 3)
K-P_Revol	Axis 2	Command	0x3204	18	4	read-write	-	32 bits	Required position - revolutions (position mode = 3)
K-DigitalOutputForce_Set	Axis 1	Command	0x3109	17	9	read-write	-	32 bits	force outputs - set
K-DigitalOutputForce_Set	Axis 2	Command	0x3209	18	9	read-write	-	32 bits	force outputs - set
K-DigitalOutputForce_Clr	Axis 1	Command	0x310A	17	10	read-write	-	32 bits	force outputs - clear
K-DigitalOutputForce_Clr	Axis 2	Command	0x320A	18	10	read-write	-	32 bits	force outputs - clear
Monitor-Counter		Monitoring	0x3300	19	0	read-only	-	32 bits	Main counter
ala	Axis 1	Monitoring	0x3301	19	1	read-only	mA	32 bits	Actual current phase A
ala	Axis 2	Monitoring	0x3401	20	1	read-only	mA	32 bits	Actual current phase A
alb	Axis 1	Monitoring	0x3302	19	2	read-only	mA	32 bits	Actual current phase B
alb	Axis 2	Monitoring	0x3402	20	2	read-only	mA	32 bits	Actual current phase B
alc	Axis 1	Monitoring	0x3303	19	3	read-only	mA	32 bits	Actual current phase C
alc	Axis 2	Monitoring	0x3403	20	3	read-only	mA	32 bits	Actual current phase C
alq	Axis 1	Monitoring	0x3306	19	6	read-only	mA	32 bits	Actual current q
alq	Axis 2	Monitoring	0x3406	20	6	read-only	mA	32 bits	Actual current q
ald	Axis 1	Monitoring	0x3307	19	7	read-only	mA	32 bits	Actual current d
ald	Axis 2	Monitoring	0x3407	20	7	read-only	mA	32 bits	Actual current d
aAngle	Axis 1	Monitoring	0x3310	19	16	read-only	inc	32 bits	Actual position per revolution (resolution : 32bit per revolution)
aAngle	Axis 2	Monitoring	0x3410	20	16	read-only	inc	32 bits	Actual position per revolution (resolution : 32bit per revolution)
aRevol	Axis 1	Monitoring	0x3311	19	17	read-only		1 32 bits	Actual number of revolutions
aRevol	Axis 2	Monitoring	0x3411	20	17	read-only		1 32 bits	Actual number of revolutions
aSpeed	Axis 1	Monitoring	0x3312	19	18	read-only	rpm	32 bits	Actual motor speed
aSpeed	Axis 2	Monitoring	0x3412	20	18	read-only	rpm	32 bits	Actual motor speed
aSpeedError	Axis 1	Monitoring	0x3314	19	20	read-only	rpm	32 bits	Actual speed error
aSpeedError	Axis 2	Monitoring	0x3414	20	20	read-only	rpm	32 bits	Actual speed error
aAngleError	Axis 1	Monitoring	0x331C	19	28	read-only	rpm	32 bits	Actual angle error
aAngleError	Axis 2	Monitoring	0x341C	20	28	read-only	rpm	32 bits	Actual angle error
aRevolError	Axis 1	Monitoring	0x331D	19	29	read-only	rpm	32 bits	Actual revol error
aRevolError	Axis 2	Monitoring	0x341D	20	29	read-only	rpm	32 bits	Actual revol error
aDriveStatus	Axis 1	Monitoring	0x3325	19	37	read-only	--	32 bits	Status of drive : bit[0] = 1 .. Enabled, bit[1] = 1 .. HW Enable signal, bit[2] = 1 .. Software enable, bit[3] = 1 .. Brake released, bit [4] = 1 .. No error, bit[5] = 1 .. Initialization finished, bit[6] = 1 ..fieldbus mode,
aDriveStatus	Axis 2	Monitoring	0x3425	20	37	read-only	--	32 bits	Status of drive : bit[0] = 1 .. Enabled, bit[1] = 1 .. HW Enable signal, bit[2] = 1 .. Software enable, bit[3] = 1 .. Brake released, bit [4] = 1 .. No error, bit[5] = 1 .. Initialization finished, bit[6] = 1 ..fieldbus mode,
aDriveError	Axis 1	Monitoring	0x3326	19	38	read-only	--	32 bits	Error of drive (see manual)
aDriveError	Axis 2	Monitoring	0x3426	20	38	read-only	--	32 bits	Error of drive (see manual)
aDriveWarning	Axis 1	Monitoring	0x3327	19	39	read-only	--	32 bits	Warning (not used)
aDriveWarning	Axis 2	Monitoring	0x3427	20	39	read-only	--	32 bits	Warning (not used)
AnInput	Axis 1	Monitoring	0x3328	19	40	read-only	0.1%	32 bits	Analogue input 1
AnInput	Axis 2	Monitoring	0x3428	20	40	read-only	0.1%	32 bits	Analogue input 2
VoltDCLink		Monitoring	0x3329	19	41	read-only	V	32 bits	DC-link voltage
OnChipTemp		Monitoring	0x332A	19	42	read-only	deg	32 bits	CPU temperature

ec_SetPointAngle	Axis 1	Monitoring	0x332B	19	43	read-only	inc	32 bits	Desired position per revolution (fieldbus)
ec_SetPointAngle	Axis 2	Monitoring	0x342B	20	43	read-only	inc	32 bits	Desired position per revolution (fieldbus)
ec_SetPointRevol	Axis 1	Monitoring	0x332C	19	44	read-only		1 32 bits	Desired number of revolutions (fieldbus)
ec_SetPointRevol	Axis 2	Monitoring	0x342C	20	44	read-only		1 32 bits	Desired number of revolutions (fieldbus)
ec_control	Axis 1	Monitoring	0x332D	19	45	read-only		1 32 bits	Fieldbus control register
ec_control	Axis 2	Monitoring	0x342D	20	45	read-only		1 32 bits	Fieldbus control register
ec_currentSetPoint	Axis 1	Monitoring	0x332E	19	46	read-only		1 32 bits	Fieldbus current setpoint
ec_currentSetPoint	Axis 2	Monitoring	0x342E	20	46	read-only		1 32 bits	Fieldbus current setpoint
ec_currentLimit	Axis 1	Monitoring	0x332F	19	47	read-only		1 32 bits	Fieldbus current limitation
ec_currentLimit	Axis 2	Monitoring	0x342F	20	47	read-only		1 32 bits	Fieldbus current limitation
Digital_Inputs	Axis 1	Monitoring	0x3330	19	48	read-only	-	32 bits	Digital inputs : bit[0] .. IN1,bit[1] .. IN3,bit[2] .. IN5,bit[3] .. IN7
Digital_Inputs	Axis 2	Monitoring	0x3430	20	48	read-only	-	32 bits	Digital inputs : bit[0] .. IN2,bit[1] .. IN4,bit[2] .. IN6,bit[3] .. IN8
Motor_temperature	Axis 1	Monitoring	0x3331	19	49	read-only	Ohm	32 bits	Resistivity of motor temperature sensor (only for digital feedback with connected temperature sensor)
Motor_temperature	Axis 2	Monitoring	0x3431	20	49	read-only	Ohm	32 bits	Resistivity of motor temperature sensor (only for digital feedback with connected temperature sensor)
rlq	Axis 1	Monitoring	0x3332	19	50	read-only	mA	32 bits	Required current (input - current controller)
rlq	Axis 2	Monitoring	0x3432	20	50	read-only	mA	32 bits	Required current (input - current controller)
la_rms	Axis 1	Monitoring	0x3333	19	51	read-only	mA	32 bits	Current la rms value
la_rms	Axis 2	Monitoring	0x3433	20	51	read-only	mA	32 bits	Current la rms value
lb_rms	Axis 1	Monitoring	0x3334	19	52	read-only	mA	32 bits	Current lb rms value
lb_rms	Axis 2	Monitoring	0x3434	20	52	read-only	mA	32 bits	Current lb rms value
lc_rms	Axis 1	Monitoring	0x3335	19	53	read-only	mA	32 bits	Current lc rms value
lc_rms	Axis 2	Monitoring	0x3435	20	53	read-only	mA	32 bits	Current lc rms value
al2t	Axis 1	Monitoring	0x3337	19	55	read-only	mA	32 bits	Integrated value l2t
al2t	Axis 2	Monitoring	0x3437	20	55	read-only	mA	32 bits	Integrated value l2t
rAngle	Axis 1	Monitoring	0x3338	19	56	read-only	inc	32 bits	Required position per revolution (input - position controller)
rAngle	Axis 2	Monitoring	0x3438	20	56	read-only	inc	32 bits	Required position per revolution (input - position controller)
rRevol	Axis 1	Monitoring	0x3339	19	57	read-only		1 32 bits	Required number of revolutions (input - position controller)
rRevol	Axis 2	Monitoring	0x3439	20	57	read-only		1 32 bits	Required number of revolutions (input - position controller)
rSpeed	Axis 1	Monitoring	0x333A	19	58	read-only	rpm	32 bits	Required speed (input - speed controller)
rSpeed	Axis 2	Monitoring	0x343A	20	58	read-only	rpm	32 bits	Required speed (input - speed controller)
DSL_status	Axis 1	Monitoring	0x333B	19	59	read-only	bit	32 bits	Status DSL fb encoder
DSL_status	Axis 2	Monitoring	0x343B	20	59	read-only	bit	32 bits	Status DSL fb encoder
DO	Axis 1	Monitoring	0x333C	19	60	read-write	bit	32 bits	Digital outputs: bit[0] .. Out1, bit[1] .. Out3, bit[2] .. Out5
DO	Axis 2	Monitoring	0x343C	20	60	read-write	bit	32 bits	Digital outputs: bit[0] .. Out2, bit[1] .. Out4, bit[2] .. Out6
C-PackeTime		Monitoring	0x3340	19	64	read-only	-	32 bits	Measured time between packets for fieldbus mode
Acc	Axis 1	PG	0x3900	25	0	read-write	pginc/s2	32 bits	Desired acceleration of movement [inc/s2] .. see functional manual
Acc	Axis 2	PG	0x3A00	26	0	read-write	pginc/s2	32 bits	Desired acceleration of movement [inc/s2] .. see functional manual
Dec	Axis 1	PG	0x3901	25	1	read-write	pginc/s2	32 bits	Desired deceleration of movement [inc/s2] .. see functional manual
Dec	Axis 2	PG	0x3A01	26	1	read-write	pginc/s2	32 bits	Desired deceleration of movement [inc/s2] .. see functional manual
APosAngle	Axis 1	PG	0x3902	25	2	read-only	inc	32 bits	Actual position of movement[inc] .. see functional manual
APosAngle	Axis 2	PG	0x3A02	26	2	read-only	inc	32 bits	Actual position of movement[inc] .. see functional manual
APosRevol	Axis 1	PG	0x3903	25	3	read-only	inc	32 bits	Actual position of movement[inc] .. see functional manual
APosRevol	Axis 2	PG	0x3A03	26	3	read-only	inc	32 bits	Actual position of movement[inc] .. see functional manual
DPosAngle	Axis 1	PG	0x3904	25	4	read-write	inc	32 bits	Destination position of movement[inc] .. see functional manual
DPosAngle	Axis 2	PG	0x3A04	26	4	read-write	inc	32 bits	Destination position of movement[inc] .. see functional manual
DPosRevol	Axis 1	PG	0x3905	25	5	read-write	inc	32 bits	Destination position of movement[inc] .. see functional manual
DPosRevol	Axis 2	PG	0x3A05	26	5	read-write	inc	32 bits	Destination position of movement[inc] .. see functional manual
ASpeed	Axis 1	PG	0x3906	25	6	read-only	pginc/s	32 bits	Actual speed of movement[inc/s] .. see functional manual
ASpeed	Axis 2	PG	0x3A06	26	6	read-only	pginc/s	32 bits	Actual speed of movement[inc/s] .. see functional manual
PosSpeed	Axis 1	PG	0x3907	25	7	read-write	pginc/s	32 bits	Desired speed of movement in position mode[inc/s] .. see functional manual
PosSpeed	Axis 2	PG	0x3A07	26	7	read-write	pginc/s	32 bits	Desired speed of movement in position mode[inc/s] .. see functional manual
Speed	Axis 1	PG	0x3908	25	8	read-write	pginc/s	32 bits	Desired speed of movement in speed mode[inc/s] .. see functional manual

Speed	Axis 2	PG	0x3A08	26	8	read-write	pginc/s	32 bits	Desired speed of movement in speed mode [inc/s] .. see functional manual
Mode	Axis 1	PG	0x3909	25	9	read-write	-	32 bits	Mode of profile generator 0 = speed mode, 1 = position mode, 2 (only read) = signaling deceleration ramp in position mode .. see functional manual
Mode	Axis 2	PG	0x3A09	26	9	read-write	-	32 bits	Mode of profile generator 0 = speed mode, 1 = position mode, 2 (only read) = signaling deceleration ramp in position mode .. see functional manual
Rdy	Axis 1	PG	0x390A	25	10	read-write	-	32 bits	Flag end of movement 1 = Destination position is reached .. see functional manual
Rdy	Axis 2	PG	0x3A0A	26	10	read-write	-	32 bits	Flag end of movement 1 = Destination position is reached .. see functional manual
Type	Axis 1	PG	0x390B	25	11	read-write	-	32 bits	Type of speed profile 0 = harmonic non symmetric, 1 = harmonic symmetric, 2 = full harmonic, 3 = trapezoidal .. see functional manual
Type	Axis 2	PG	0x3A0B	26	11	read-write	-	32 bits	Type of speed profile 0 = harmonic non symmetric, 1 = harmonic symmetric, 2 = full harmonic, 3 = trapezoidal .. see functional manual
BitsPerRevol	Axis 1	PG	0x390C	25	12	read-write	-	32 bits	Number of bit per revolution for internal pg calculation. It take affect to resolution of speeds and accelerations (decelerations) .. see functional manual
BitsPerRevol	Axis 2	PG	0x3A0C	26	12	read-write	-	32 bits	Number of bit per revolution for internal pg calculation. It take affect to resolution of speeds and accelerations (decelerations) .. see functional manual