# Drive moves into parking position

Translation of the "Original Dokumentation"
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|---|---|
| **Name:** | FKT_Fahre_in_Parkposition_en |

**Version:**

| Version: 2019/45 | |
|---|---|
| **Change** | **Letter symbol** |
| Controller card KW-R27 added | STL |

**Previous version:** 2018/44

**Product version:**

| Product AMK part no. | Firmware Version (AMK part no.) |
|---|---|
| KW-R06 (O835)<br>KW-R07 (O807)<br>KW-R16 (O872)<br>KW-R17 (O873) | AE-R5-6 V1.13 2015/21 (205700) |
| KW-R24-R (O954) | AE-R24-R V2.11 2016/46 (206643) |
| KW-R25 (O902) | AE-R25 V2.03 2015/40 (205898) |
| KW-R26 (O903) | AE-R26 V2.03 2015/40 (205899) |
| KW-R27 (O957) | AE-R26 V2.12 2018/40 (207284) |
| iX / iC / iDT5 / | iX V1.06 2014/48 (205326) |
| iX(-R3) / iC(-R3) /<br>iDT5(-R3) / | iX V2.08 2015/46 (206017) |
| ihX | ihX V1.01 2015/46 (205697) |

# 1 Drive moves into parking position

| Supported Hardware: | KW-R06 / KW-R16 / KW-R07 / KW-R17 / iX / iC / iDT5 / iX(-R3) / iC(-R3) / iDT5(-R3) / ihXT / KW-R24-R / KW-R25 / KW-R26 / KW-R27 / |
|---|---|

The function 'Drive into parking position' can be activated in response to a bus failure. If an error occurs the drive is moved with a configurable velocity to a configurable end position (parking position).

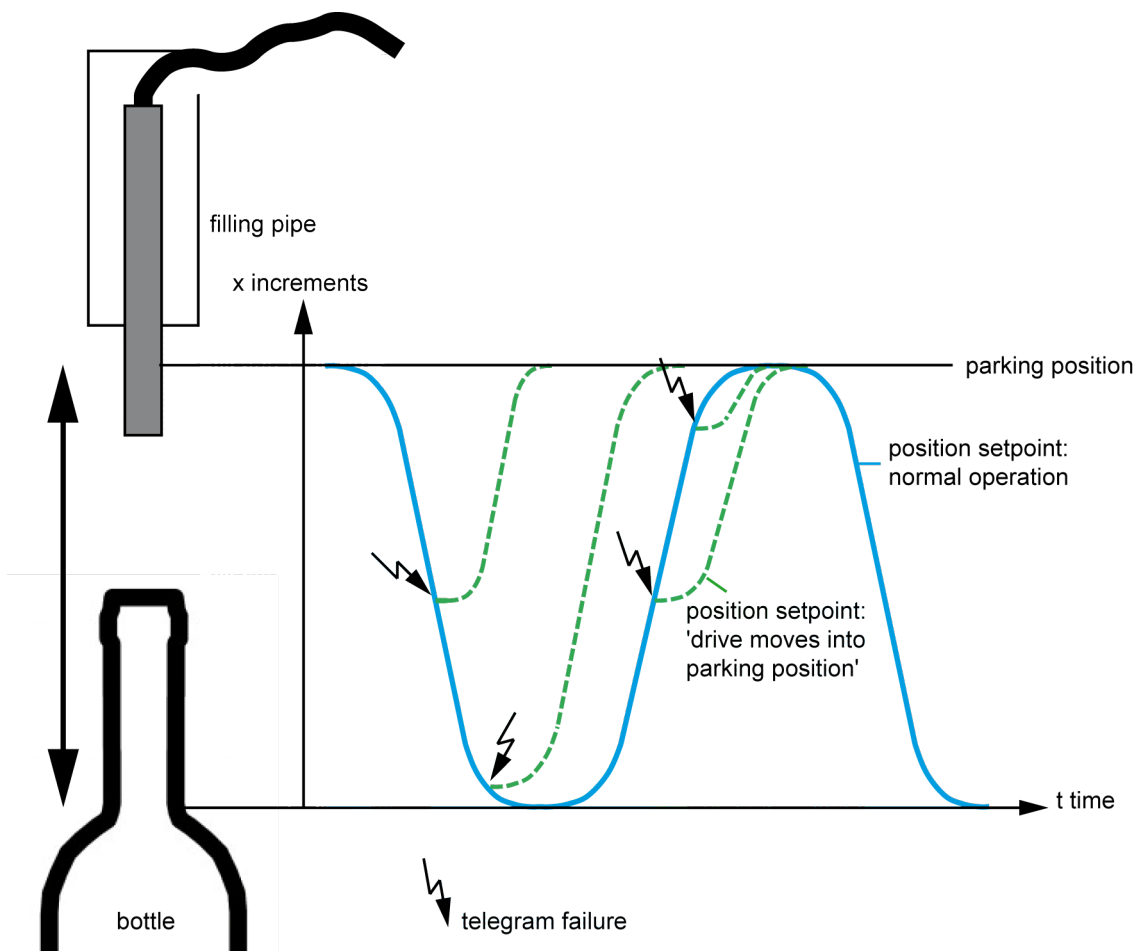Speed setpoints and braking/acceleration ramps can be parameterized.

Prerequisite for a bus failure:

- The drive must be in the operation mode position control with external setpoint source (e. g. controller writes the setpoints in ID47 'Position command value')
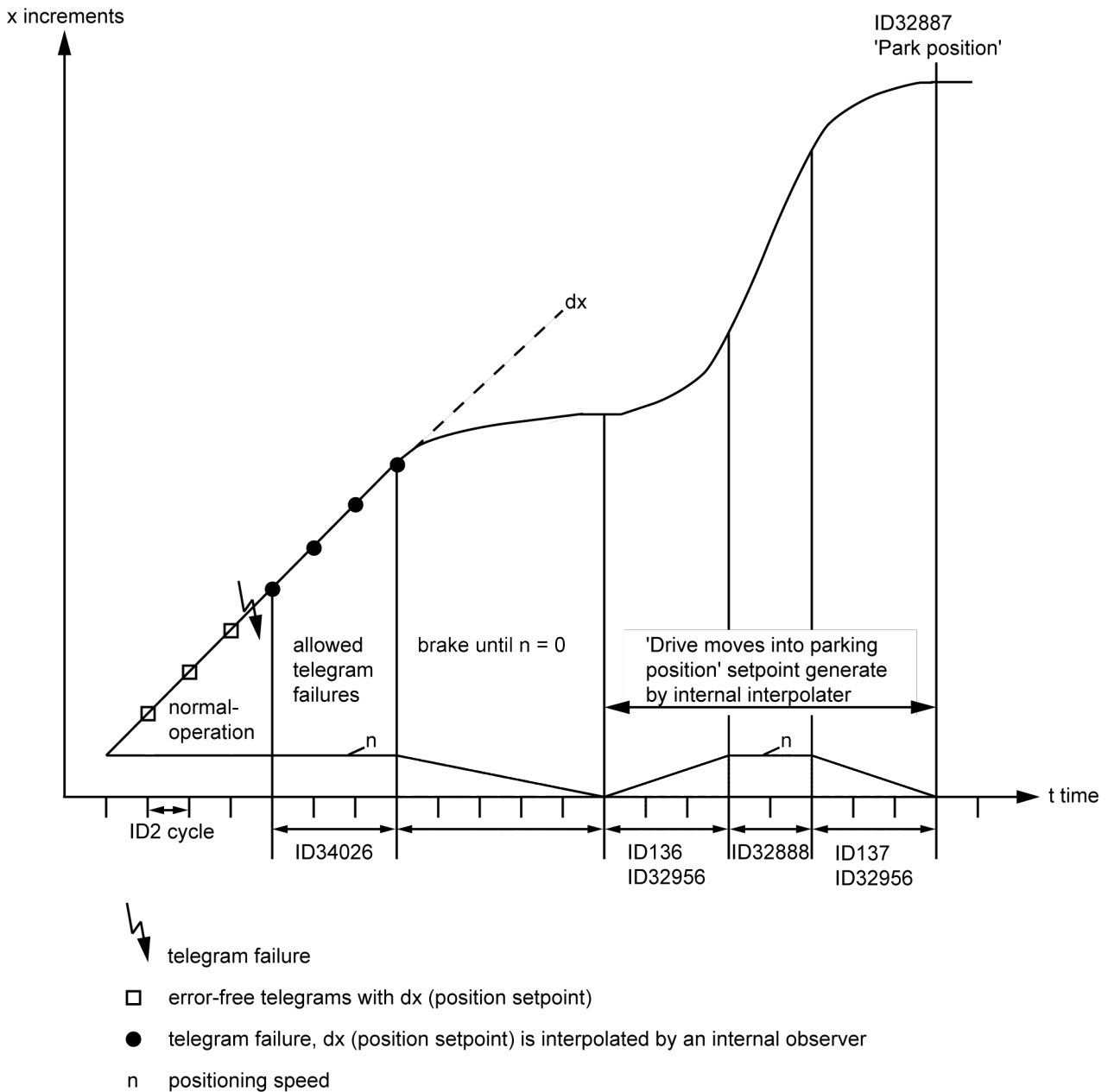- Controller enable active, QRF = 1 acknowledgement controller enable must be set

**Sequence using the example of a bottle filler**

The filling pipe moves cyclically in the bottle necks. The park position is the position of the filling pipe outside the bottle (top). In this position, the filling pipe is not damaged, when the bottle is moved.

After bus failure was recognized, the drive stops to standstill according ID137 'Negative acceleration'. Afterwards the drive starts moving to the park position controlled by the internal interpolator. After the parking position has been reached, the controller enable ( RF) is removed and the drive generates a warning message. SBM keeps active.

## 1.1 Execution during the transition



telegram failure

□   error-free telegrams with dx (position setpoint)

●   telegram failure, dx (position setpoint) is interpolated by an internal observer

n   positioning speed

## 1.2 Relevant parameters

| Parameter | Meaning / notes |
|---|---|
| ID2 'SERCOS cycle time' | The 'SERCOS cycle time' defines the intervals in which cyclical data is sent and received. |
| ID136 'Positive acceleration' | Input value is used by the internal drive interpolator. |
| ID137 'Negative acceleration' | Input value is used by the internal drive interpolator. |
| ID3280x 'AMK operating modes' | Operation mode position control with external setpoint source (e. g. setpoint via control) |
| ID32887 'Park position' | Park position where the drive will move to in case of bus failure, if ID34027 = 0x3 is parameterized. |
| ID32888 'Park velocity' | Velocity to drive into the park position in case of bus failure and ID34027 = 0x3 is parameterized. |
| ID32956 'Additional acceleration value' | Input value is used by the internal drive interpolator. |

| Parameter | Meaning / notes |
|---|---|
| ID34026 'BUS mode attribute' | Adjustable tolerance at fail telegrams in the bus. <br><br> Note during the parametrization the instance number of the used bus system. |
| ID34027 'BUS failure character' | Code 0x3 'Drive moves into parking position' <br><br> Note during the parametrization the instance number of the used bus system. |