

SIEMENS

SIMATIC

S7-1200
Easy Book

Manual

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flexible S7-1200

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Warning notice system

This manual contains notices you have to observe in order to ensure your personal safety, as well as to prevent damage to property. The notices referring to your personal safety are highlighted in the manual by a safety alert symbol, notices referring only to property damage have no safety alert symbol. These notices shown below are graded according to the degree of danger.

DANGER

indicates that death or severe personal injury **will** result if proper precautions are not taken.

WARNING

indicates that death or severe personal injury **may** result if proper precautions are not taken.

CAUTION

with a safety alert symbol, indicates that minor personal injury can result if proper precautions are not taken.

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without a safety alert symbol, indicates that property damage can result if proper precautions are not taken.

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indicates that an unintended result or situation can occur if the corresponding information is not taken into account.

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Qualified Personnel

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We have reviewed the contents of this publication to ensure consistency with the hardware and software described. Since variance cannot be precluded entirely, we cannot guarantee full consistency. However, the information in this publication is reviewed regularly and any necessary corrections are included in subsequent editions.

Preface

Welcome to the world of S7-1200, the latest in a line of the Siemens SIMATIC controllers. The SIMATIC S7-1200 compact controller is the modular, space-saving controller for small automation systems that require either simple or advanced functionality for logic, HMI and networking. The compact design, low cost, and powerful features make the S7-1200 a perfect solution for controlling small applications.

As part of the SIMATIC commitment to "totally integrated automation" (TIA), the S7-1200 product family and the STEP 7 Basic programming tool give you the flexibility you need to solve your automation needs.

The S7-1200 helps to make the most challenging tasks easy!

The SIMATIC S7-1200 controller solution, designed for the "compact" controller class, is comprised of the SIMATIC S7-1200 controller and SIMATIC HMI Basic panels that can both be programmed with SIMATIC STEP 7 Basic engineering software. The ability to program both devices using the same engineering software significantly reduces development costs.



The S7-1200 compact controller includes:

- Built-in PROFINET
- High-speed I/O capable of motion control, onboard analog inputs to minimize space requirements and the need for additional I/O, 2 pulse generators for pulse-width applications (Page 84), and up to 6 high-speed counters (Page 80)
- On-board I/O points built into the CPU modules provide from 6 to 14 input points and from 4 to 10 output points



Signal modules for DC, relay, or analog I/O expand the number of I/O points, and innovative signal boards snap onto the front of the CPU to provide additional I/O (Page 9).

The SIMATIC HMI Basic panels (Page 10) were designed specifically for the S7-1200. This Easy Book provides an introduction to the S7-1200 PLC. The following pages offer an overview of the many features and capabilities of the devices.

For additional information, refer to the *S7-1200 programmable controller system manual*. You can also use the following web site to search for specific information about products or to contact technical support representatives:

<http://www.siemens.com/automation/support-request>

For information about UL and FM certification, CE labeling, C-Tick and other standards, refer to the Technical specifications (Page 95).

Contact your Siemens distributor or sales office for assistance in answering any technical questions, for training, or for ordering S7 products. Because your sales representatives are technically trained and have the most specific knowledge about your operations, process and industry, as well as about the individual Siemens products that you are using, they can provide the fastest and most efficient answers to any problems you might encounter.

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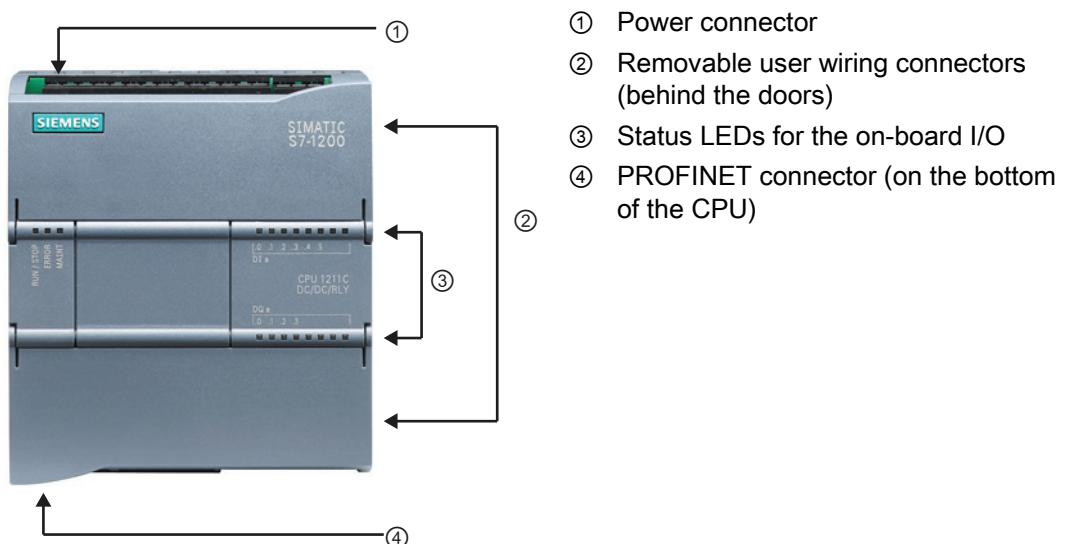
Introducing the powerful and flexible S7-1200

The S7-1200 controller provides the flexibility and power to control a wide variety of devices in support of your automation needs. The compact design, flexible configuration, and powerful instruction set combine to make S7-1200 a perfect solution for controlling a wide variety of applications.

The CPU combines a microprocessor, an integrated power supply, input and output circuits, built-in PROFINET, high-speed motion control I/O, and on-board analog inputs in a compact housing to create a powerful controller. After you download your program, the CPU contains the logic required to monitor and control the devices in your application. The CPU monitors the inputs and changes the outputs according to the logic of your user program, which can include Boolean logic, counting, timing, complex math operations, and communications with other intelligent devices.

To communicate with a programming device, the CPU provides a built-in PROFINET port. With the PROFINET network, the CPU can communicate with HMI panels or another CPU.

To provide security for your application, every S7-1200 CPU provides password protection that allows you to configure access to the CPU functions.



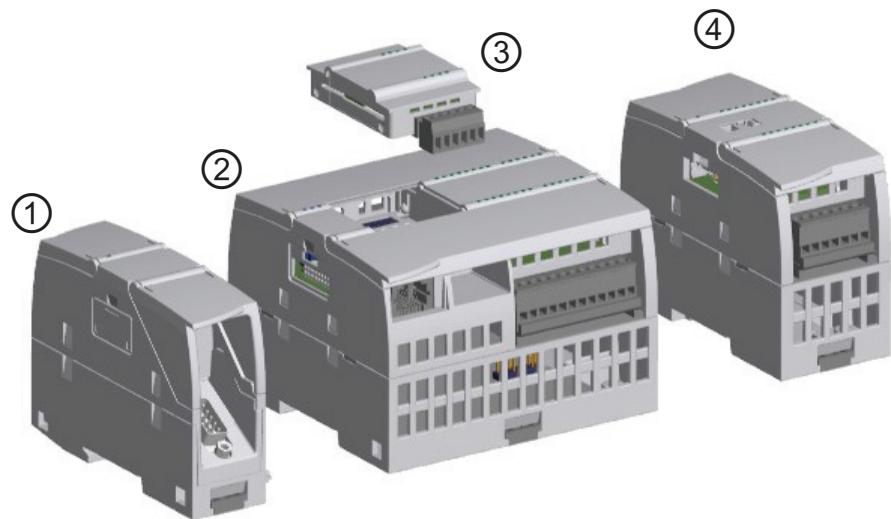
Feature	CPU 1211C	CPU 1212C	CPU 1214C
Physical size (mm)	90 x 100 x 75	90 x 100 x 75	110 x 100 x 75
User memory			
• Work memory	• 25 Kbytes	• 25 Kbytes	• 50 Kbytes
• Load memory	• 1 Mbyte	• 1 Mbyte	• 2 Mbytes
• Retentive memory	• 2 Kbytes	• 2 Kbytes	• 2 Kbytes
Local on-board I/O			
• Digital	• 6 inputs 4 outputs	• 8 inputs 6 outputs	• 14 inputs 10 outputs
• Analog	• 2 inputs	• 2 inputs	• 2 inputs
Process image size			
• Inputs	• 1024 bytes	• 1024 bytes	• 1024 bytes
• Outputs	• 1024 bytes	• 1024 bytes	• 1024 bytes
Bit memory (M)	4096 bytes	4096 bytes	8192 bytes
Signal modules expansion	None	2	8
Signal board	1	1	1
Communication modules	3	3	3
High-speed counters	3	4	6
• Single phase	• 3 at 100 kHz 1 at 30 kHz	• 3 at 100 kHz 1 at 30 kHz	• 3 at 100 kHz 3 at 30 kHz
• Quadrature phase	• 3 at 80 kHz	• 3 at 80 kHz 1 at 20 kHz	• 3 at 80 kHz 3 at 20 kHz
Pulse outputs ¹	2	2	2
Memory card (optional)	Yes	Yes	Yes
Real time clock retention time	10 days, typical / 6 day minimum at 40 degrees C		
Real math execution speed	18 µs/instruction		
Boolean execution speed	0.1 µs/instruction		

¹ Only the DC output (non-relay) CPUs support the pulse outputs.

The different CPU models provide a diversity of features and capabilities that help you create effective solutions for your varied applications. For detailed information about a specific CPU, see the technical specifications (Page 99).

1.1 Expanding the capability of the CPU

The S7-1200 family provides a variety of signal modules and signal boards for expanding the capabilities of the CPU. You can also install additional communication modules to support other communication protocols. For detailed information about a specific module, see the technical specifications (Page 95).



- | | |
|-----------------------------|----------------------|
| ① Communication module (CM) | ③ Signal board (SB) |
| ② CPU | ④ Signal module (SM) |

Module		Input only	Output only	Combination in/out
Signal module (SM)	Digital	8 x DC In	8 x DC Out 8 x Relay Out	8 x DC In/8 x DC Out 8 x DC In/8 x Relay Out
		16 x DC In	16 x DC Out 16 x Relay Out	16 x DC In/16 x DC Out 16 x DC In/16 x Relay Out
	Analog	4 x Analog In 8 x Analog In	2 x Analog Out 4 x Analog Out	4 x Analog In/2 x Analog Out
Signal board (SB)	Digital	-	-	2 x DC In/2 x DC Out
	Analog	-	1 x Analog Out	-
Communication module (CM)				
<ul style="list-style-type: none"> • RS485 • RS232 				

1.2 HMI Basic panels

As visualization becomes a standard component for most machine designs, the SIMATIC HMI Basic Panels provide touch-screen devices for basic operator control and monitoring tasks. All panels are have a protection rating for IP65 and have CE, UL, cULus, and NEMA 4x certification.



KTP 400 Basic PN

- Mono (STN, gray scale)
- 4" touch screen with 4 tactile keys
- Portrait or landscape
- Size: 3.8"
- Resolution: 320 x 240

- 128 tags
- 50 process screens
- 200 alarms
- 25 curves
- 32 KB recipe memory
- 5 recipes, 20 data records, 20 entries



KTP 600 Basic PN

- Color (TFT, 256 colors) or Mono (STN, gray scales)
- 6" touch screen with 6 tactile keys
- Portrait or landscape
- Size: 5.7"
- Resolution: 320 x 240

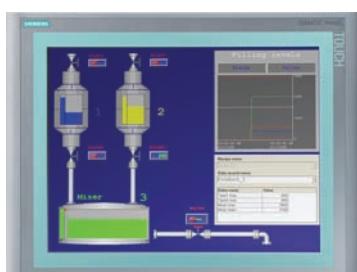
- 128 tags
- 50 process screens
- 200 alarms
- 25 curves
- 32 KB recipe memory
- 5 recipes, 20 data records, 20 entries



KTP1000 Basic PN

- Color (TFT, 256 colors)
- 10" touch screen with 8 tactile keys
- Size: 10.4"
- Resolution: 640 x 480

- 256 tags
- 50 process screens
- 200 alarms
- 25 curves
- 32 KB recipe memory
- 5 recipes, 20 data records, 20 entries



TP1500 Basic PN

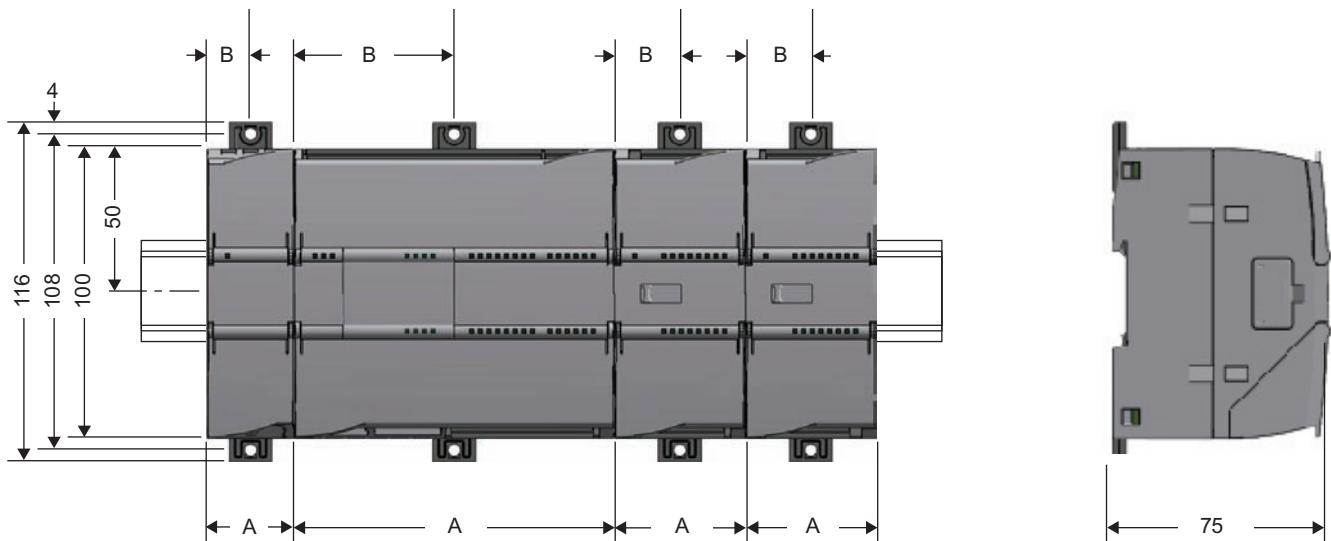
- Color (TFT, 256 colors)
- 15" touch screen
- Size: 15.1"
- Resolution: 1024 x 768

- 256 tags
- 50 process screens
- 200 alarms
- 25 curves
- 32 KB recipe memory (integrated flash)
- 5 recipes, 20 data records, 20 entries

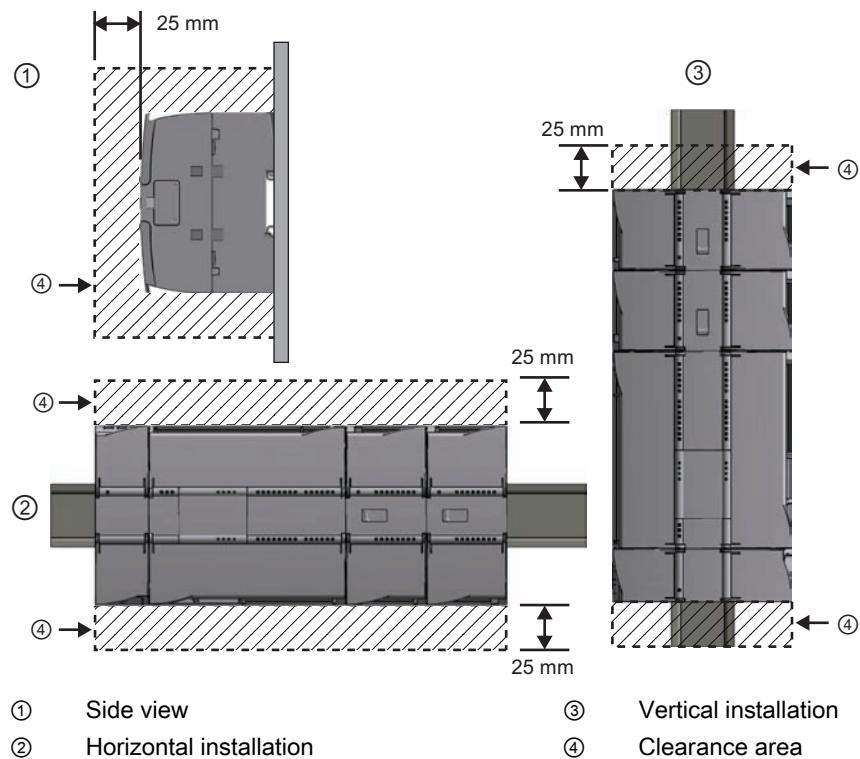
1.3 Mounting dimensions and clearance requirements

The S7-1200 PLC is designed to be easy to install. Whether mounted on a panel or on a standard DIN rail, the compact size makes efficient use of space.

The CPUs, SMs and CMs support DIN rail mounting and panel mounting. Use the DIN rail clips on the module to secure the device on the rail. These clips also snap into an extended position to provide screw mounting positions to mount the unit directly on a panel. The interior dimension of the hole for the DIN clips on the device is 4.3 mm.



S7-1200 Devices		Width A	Width B
CPU	CPU 1211C and CPU 1212C	90 mm	45 mm
	CPU 1214C	110 mm	55 mm
Signal module (SM)	8- and 16-point DC and Relay (8I, 16I, 8Q, 16Q, 8I/8Q) Analog (4AI, 8AI, 4AI/4AQ, 2AQ, 4AQ)	45 mm	22.5 mm
	16I/16Q Relay (16I/16Q)	70 mm	35 mm
	Communication module (CM)	30 mm	15 mm



Always consider the following guidelines when planning your installation:

- Separate the devices from heat, high voltage, and electrical noise.
- Provide adequate clearance for cooling and wiring. A 25 mm thermal zone must be provided above and below the unit for free air circulation.

Refer to the *S7-1200 System Manual* for specific requirements and guidelines for installation.

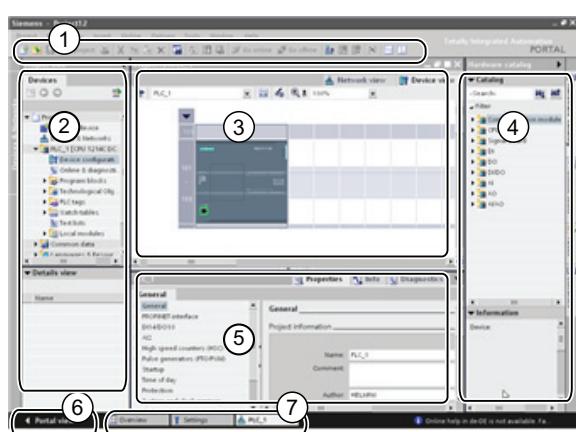
STEP 7 Basic makes the work easy

STEP 7 Basic provides a user-friendly environment to develop controller logic, configure HMI visualization, and setup network communication. To help increase your productivity, STEP 7 Basic provides two different views of the project: a task-oriented set of portals that are organized on the functionality of the tools (Portal view), or a project-oriented view of the elements within the project (Project view). Choose which view helps you work most efficiently. With a single click, you can toggle between the Portal view and the Project view.



The Portal view provides a functional view of the project tasks and organizes the tools according to the tasks to be accomplished. You can easily determine how to proceed and which task to choose.

- ① Portals for the different tasks
- ② Tasks for the selected portal
- ③ Selection panel for the selected action
- ④ Changes to the Project view



The Project view provides access to all of the components within a project.

- ① Menus and toolbar
- ② Project navigator
- ③ Work area
- ④ Task cards
- ⑤ Inspector window
- ⑥ Changes to the Portal view
- ⑦ Editor bar

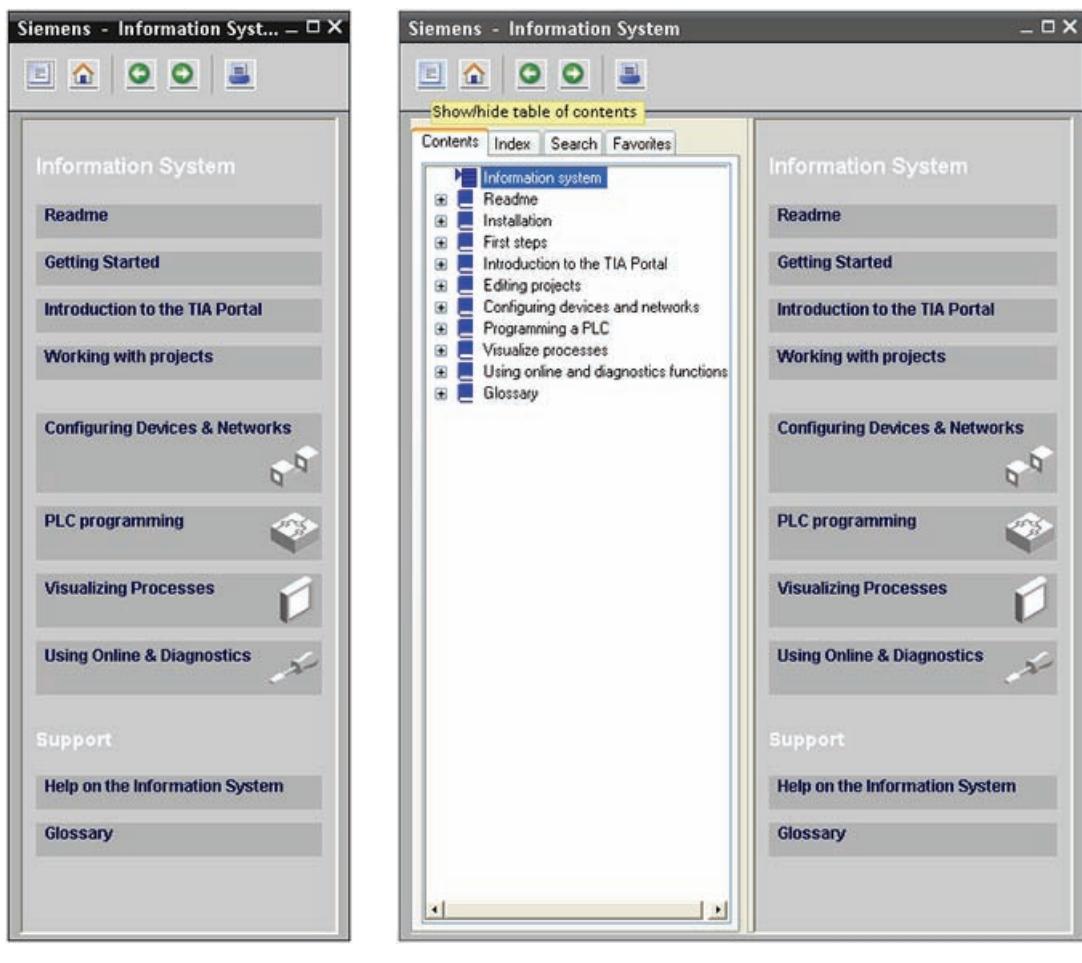
With all of these components in one place, you have easy access to every aspect of your project. For example, the inspector window shows the properties and information for the object that you have selected in the work area. As you select different objects, the inspector window displays the properties that you can configure. The inspector window includes tabs that allow you to see diagnostic information and other messages.

By showing all of the editors that are open, the editor bar helps you work more quickly and efficiently. To toggle between the open editors, simply click the different editor. You can also arrange two editors to appear together, arranged either vertically or horizontally. This feature allows you to drag and drop between editors.

2.1 Help when you need it

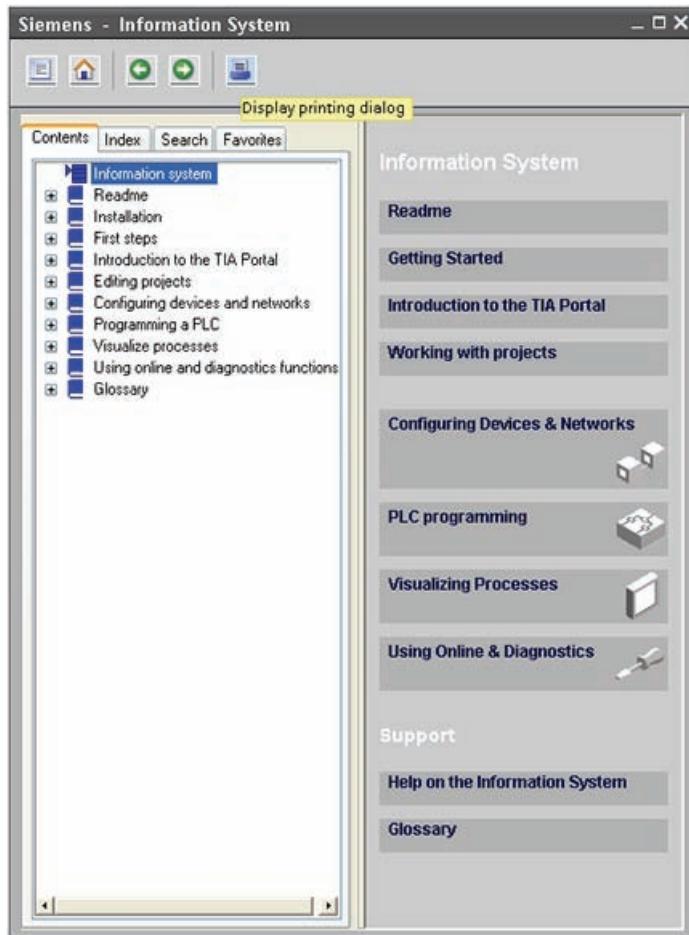
To help you to find more information or to resolve issues quickly and efficiently, STEP 7 Basic provides intelligent point-of-need assistance. For example, some of the tool tips in the interface (such as for the instructions) "cascade" to provide additional information. A black triangle alongside the tool tip signifies that more information is available.

STEP 7 Basic provides a comprehensive online information and help system that describes all of the SIMATIC TIA products that you have installed. The information system opens in a window that does not obscure the work areas. Click the "Show/hide contents" button on the information system to display the contents and undock the help window. You can then resize the help window.

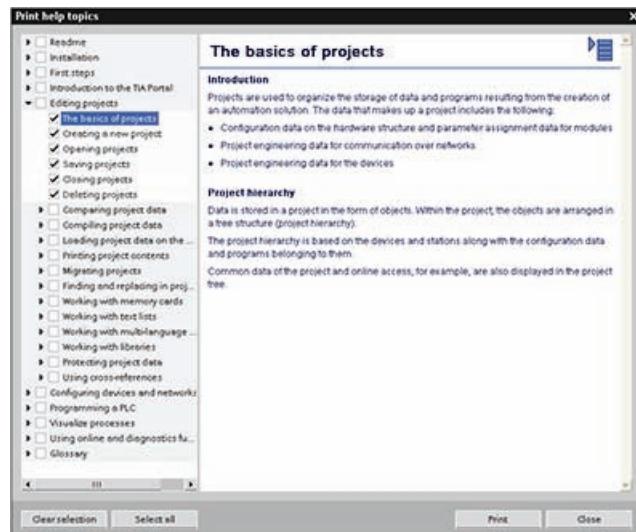


If STEP 7 Basic is maximized, clicking the "Show/hide contents" button does not undock the help window. Click the "Restore down" button on STEP 7 Basic to undock the help window. You can then move and resize the help window.

2.1.1 Printing a topic from the online help



To print from the information system, click the "Print" button on the help window.



The "Print" dialog allows you to select the topics to print. Make certain that the panel displays a topic. You can then select any other topic to print. Click the "Print" button to send the selected topics to your printer.

2.2 Providing easy-to-use tools

2.2.1 Easy to insert instructions into your user program

STEP 7 Basic provides task cards that contain the instructions for your program. The instructions are grouped according to function.

To create your program, you drag instructions from the task card onto a network.



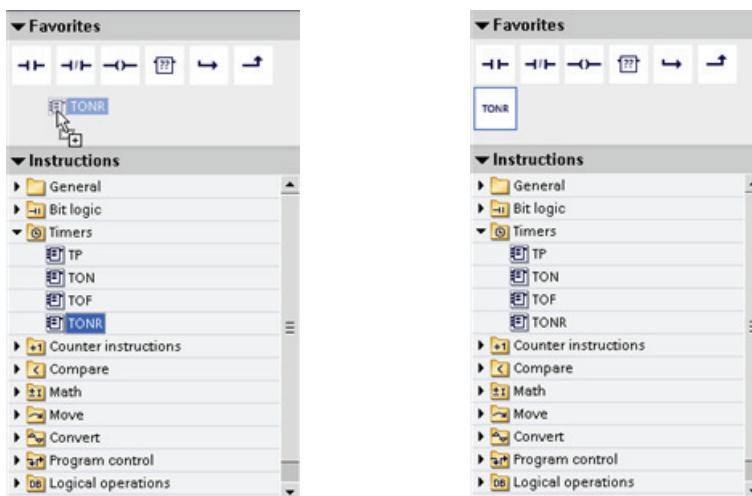
2.2.2 Easy access to your favorite instructions from a toolbar



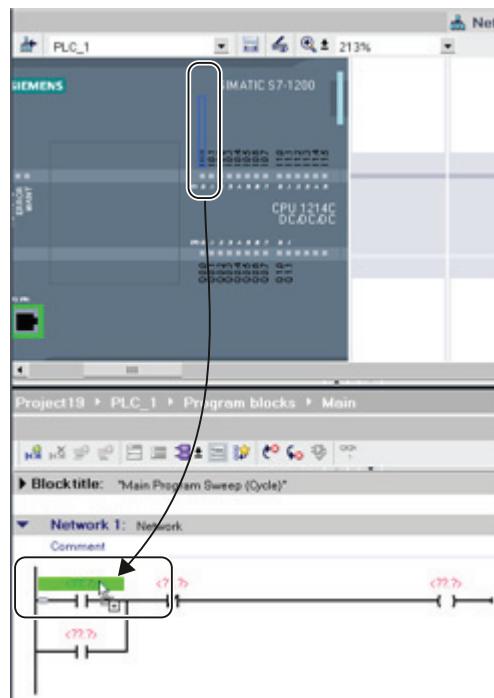
STEP 7 Basic provides a "Favorites" toolbar to give you quick access to the instructions that you frequently use.

Simply click the icon for the instruction to insert it into your network!

You can easily customize the "Favorites" by adding new instruction. Simply drag and drop an instruction to the "Favorites". The instruction is now just a click away!



2.2.3 Easy to drag and drop between editors



To help you perform tasks quickly and easily, STEP 7 Basic allows you to drag and drop elements from one editor to another. For example, you can drag an input from the CPU to the address of an instruction in your user program. (You must zoom in at least 200% to select the I/O of the CPU.)

Notice that the tag names are displayed not only in the PLC tag table, but also are displayed on the CPU.

To display two editors at one time, use the "Split editor" menu commands or buttons in the toolbar.



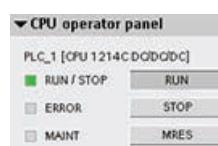
To toggle between the editors that have been opened, click the icons in the editor bar.



2.2.4 Easy to change the operating mode of the CPU

The CPU does not have a physical switch for changing the operating modes (STOP or RUN). When you configure the CPU in the device configuration, you configure the start-up behavior in the properties of the CPU (Page 46). The Online and Diagnostics portal provides an operator panel for changing the operating mode of the online CPU.

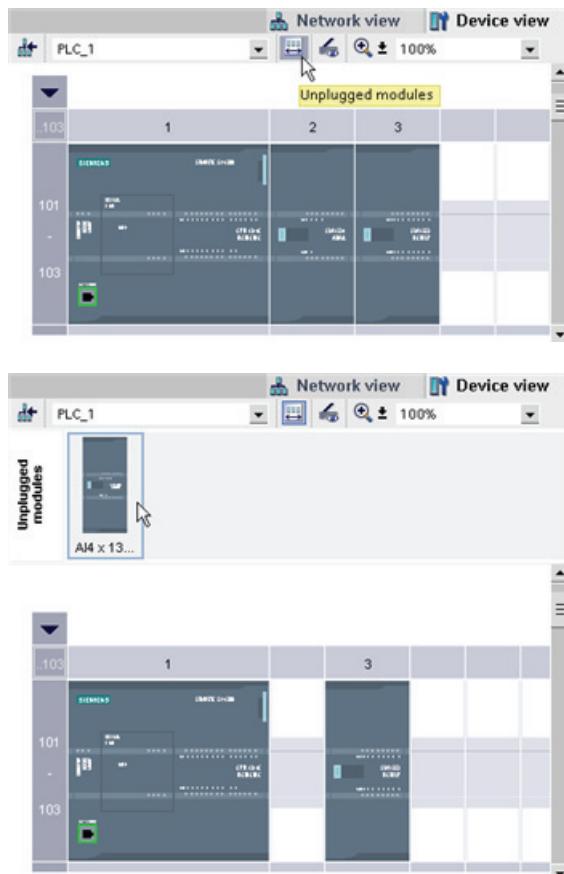
To use the CPU operator panel, you must be connected online to the CPU. The "Online tools" task card displays an operator panel that shows the operating mode of the online CPU. The operator panel also allows you to change the operating mode of the online CPU.



Use the button on the operator panel to change the operating mode (STOP or RUN). The operator panel also provides an MRES button for resetting the memory.

The color of the RUN/STOP indicator shows the current operating mode of the CPU. Yellow indicates STOP mode, and green indicates RUN mode.

2.2.5 Easy to virtually "unplug" modules without losing the configuration

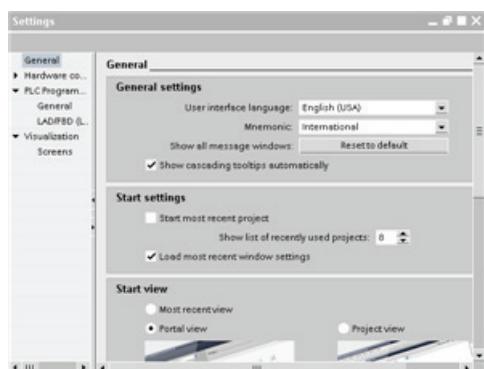


STEP 7 Basic provides a storage area for "unplugged" modules. You can drag a module from the rack to save the configuration of that module. These unplugged modules are saved with your project, allowing you to reinsert the module in the future without having to reconfigure the parameters.

One use of this feature is for temporary maintenance. Consider a scenario where you might be waiting for a replacement module and plan to temporarily use a different module as a short-term replacement. You could drag the configured module from the rack to the "Unplugged modules" and then insert the temporary module.

Replacing a module does not affect the PLC tags, as long as the module has the same basic addressing. For example, you can replace an 8-input digital SM with either an 8X8 combination digital SM or a 16-input digital SM.

2.2.6 Easy to modify the appearance and configuration of STEP 7 Basic



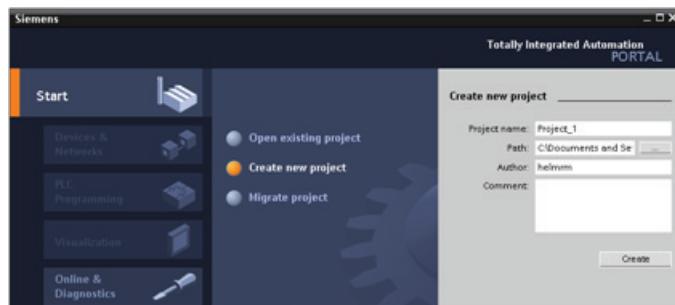
You can select a variety of settings, such as the appearance of the interface, language, or the directory for saving your work.

Select the "Settings" command from the "Options" menu to change these settings.

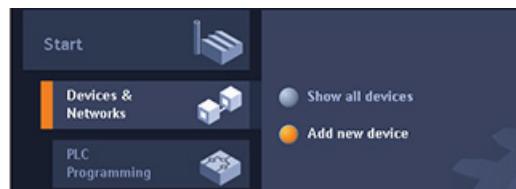
3

Getting started

Working with STEP 7 Basic is easy! In the next few pages, you can see how quickly you can get started with creating a project.



In the Start portal, click the "Create new project" task.
Enter a project name and click the "Create" button.

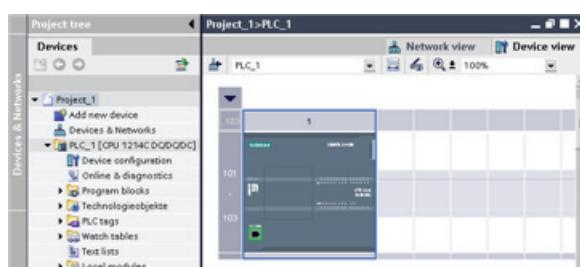


After creating the project, select the Devices & Networks portal.
Click the "Add new device" task.



Select the CPU to add to the project:
1. In the "Add new device" dialog, click the "SIMATIC PLC" button.
2. Select a CPU from the list.
3. To add the selected CPU to the project, click the "Add" button

Note that the "Open device view" option is selected. Clicking "Add" with this option selected opens the "Device configuration" of the Project view.

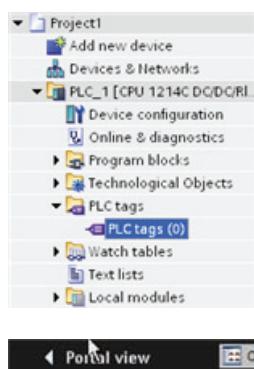


The Device view displays the CPU that you added.

Create tags for the I/O of the CPU

Note

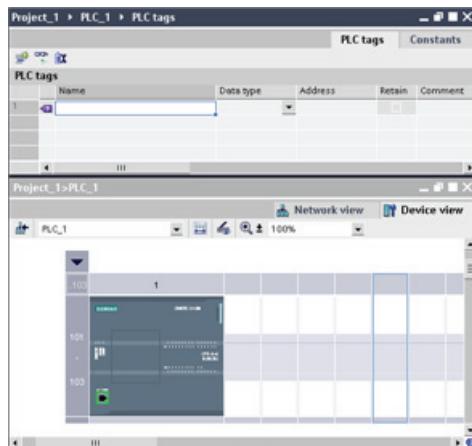
"PLC tags" are the symbolic names for I/O and addresses. After you create a PLC tag, STEP 7 Basic stores the tag in a tag table. All of the editors in your project (such as the program editor, the device editor, the visualization editor, and the watch table editor) can access the tag table.



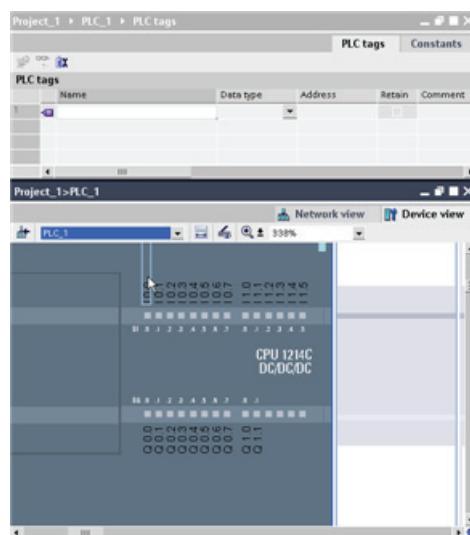
With the device editor open, you can open a tag table. You can see the open editors displayed in the editor bar.



In the tool bar, click the "Split editor space horizontally" button.

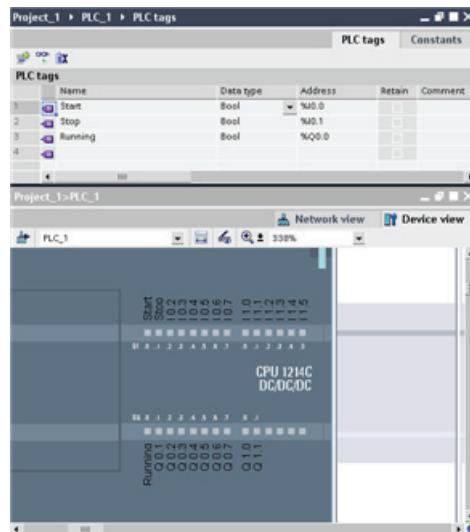


STEP 7 Basic displays both the tag table and the device editor together.



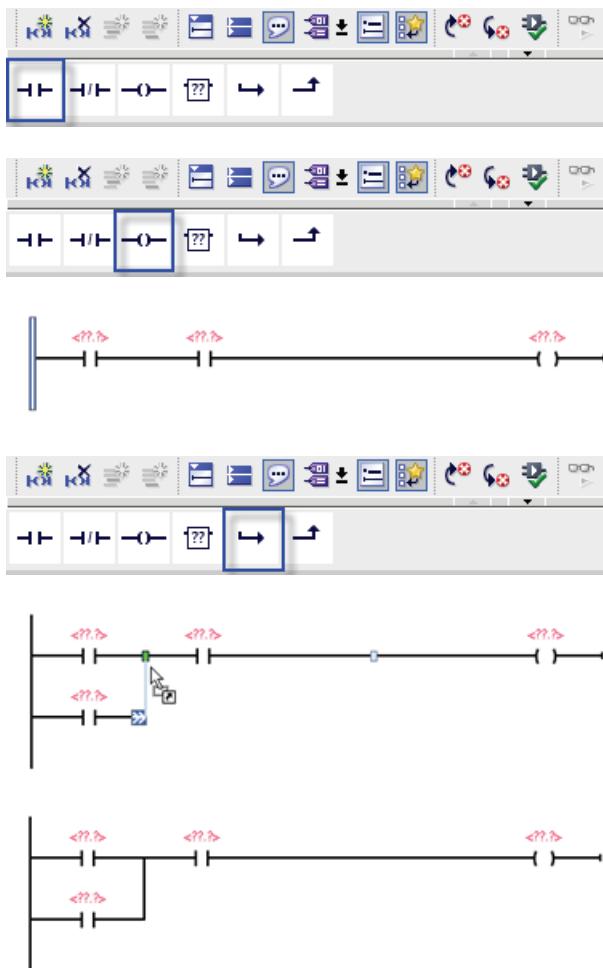
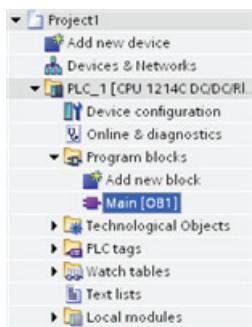
Zoom the device configuration to over 200% so that the I/O points of the CPU are legible and selectable.

1. Select I0.0 and drag it to the first row of the tag table.
2. Change the tag name from "I0.0" to "Start".
3. Drag I0.1 to the tag table and change the name to "Stop".
4. Drag Q0.0 (on the bottom of the CPU) to the tag table and change the name to "Running".



With the PLC tags entered into the tag table, the tags are available to your user program.

Create a simple network in your user program



Your program code consists of instructions that the PLC executes in sequence. For this example, use ladder logic (LAD) to create the program code. The LAD program is a sequence of networks that resemble the rungs of a ladder.

To open the program editor, follow these steps:

1. Expand the "Program blocks" folder in the Project tree to display the "Main [OB1]" block.
2. Double-click the "Main [OB1]" block.

The program editor opens the program block (OB1). Use the buttons on the "Favorites" to insert contacts and coils onto the network:

1. Click the "Normally open contact" button on the "Favorites" to add a contact to the network.
2. For this example, add second contact.
3. Click the "Output coil" button to insert a coil.

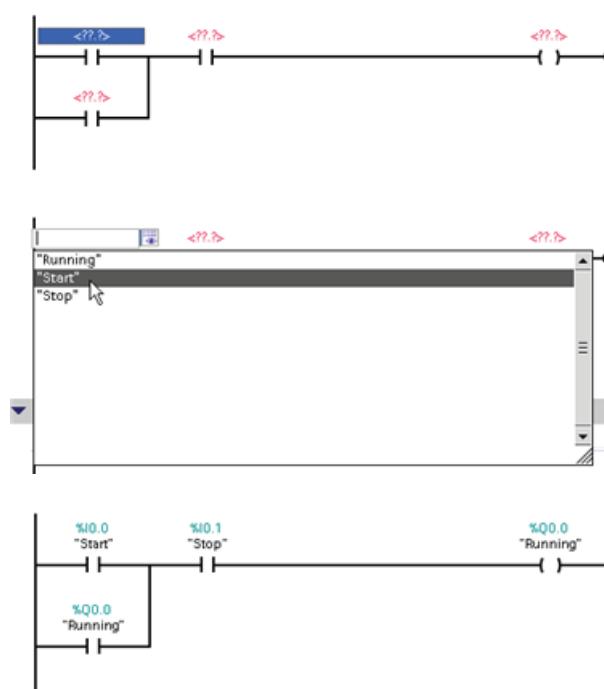
The "Favorites" also provides a button for creating a branch:

1. Click the "Open branch" icon to add a branch to the rail of the network.
2. Insert another normally open contact to the open branch.
3. Drag the double-headed arrow to a connection point (the green square on the rung) between the open and closed contacts on the first rung.

To save the project, click the "Save project" button in the toolbar. Notice that you do not have to finish editing the rung before saving.

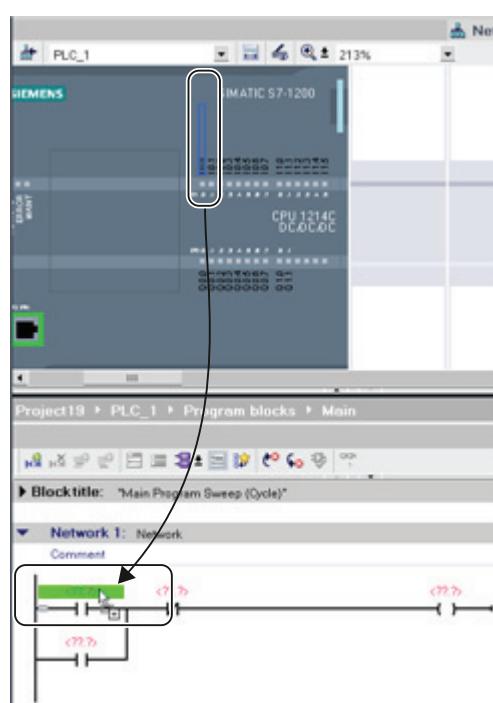
You have created a network of LAD instructions. You can now associate the tag names with these instructions.

Use the PLC tags in the tag table for addressing the instructions



Using the tag table, you can quickly enter the PLC tags for the addresses of the contacts and coils.

1. Double-click the default address <??,?> above the first normally open contact.
2. Click the selector icon to the right of the address to open the tags in the tag table.
3. From the drop-down list, select "Start" for the first contact.
4. For the second contact, repeat the preceding steps and select the tag "Stop".
5. For the coil and the latching contact, select the tag "Running".



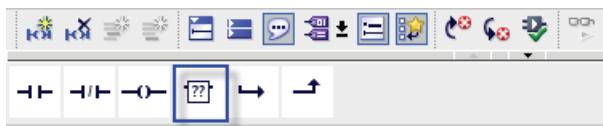
You can also drag the I/O addresses directly from the CPU. Simply split the work area of the Project view (Page 17).

You must zoom the CPU to over 200% in order to select the I/O points.

You can drag the I/O on the CPU in the "Device configuration" to the LAD instruction in the program editor to create not only the address for the instruction, but also to create an entry in the PLC tag table.

Add a Math instruction to the second network

The program editor features a generic "box" instruction. After inserting this box instruction, you then select the type of instruction, such as an ADD instruction, from a drop-down list.

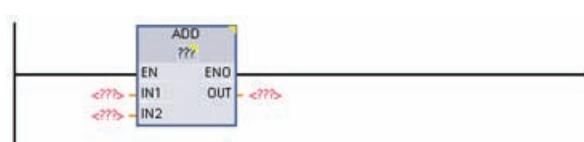
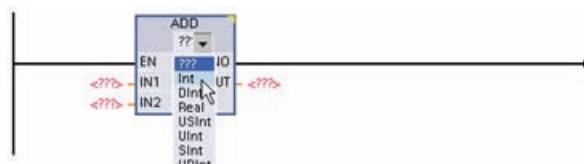


Click the generic "box" instruction in the "Favorites" tool bar.

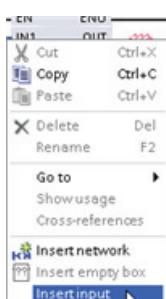


The generic "box" instruction supports a variety of instructions. For this example, create an ADD instruction:

1. Click the yellow corner of the box instruction to display the drop-down list of instructions.
2. Scroll down the list and select the ADD instruction.
3. Click the yellow corner by the "?" to select the data type for the inputs and output.



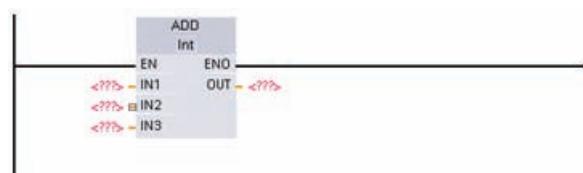
You can now enter the tags (or memory addresses) for the values to use with the ADD instruction.



You can also create additional inputs for certain instructions:

1. Click one of the inputs.
2. Right-click to display the context menu and select the "Insert input" command.

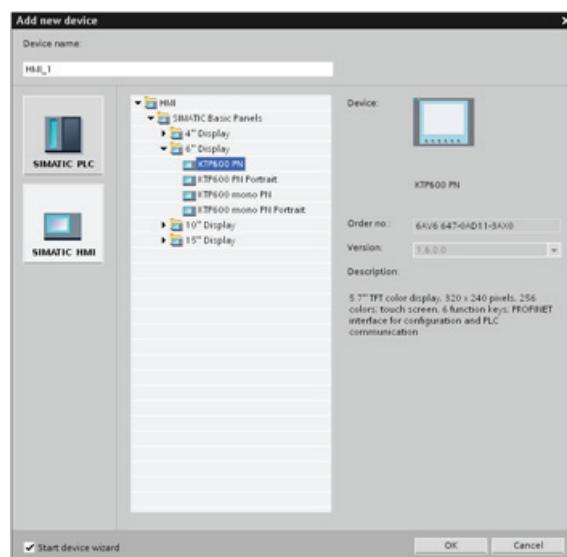
The ADD instruction now uses three inputs.



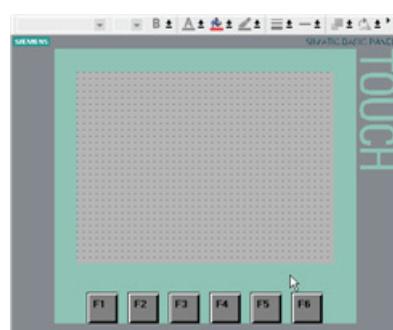
Adding an HMI device to the project



Adding an HMI device to your project is easy!



1. Double-click the "Add new device" icon.
 2. Click the "SIMATIC HMI" button in the "Add new device" dialog.
 3. Select the specific HMI device from the list.
- You can choose to run the HMI wizard to help you configure the screens for the HMI device.
4. Click "OK" to add the HMI device to your project.

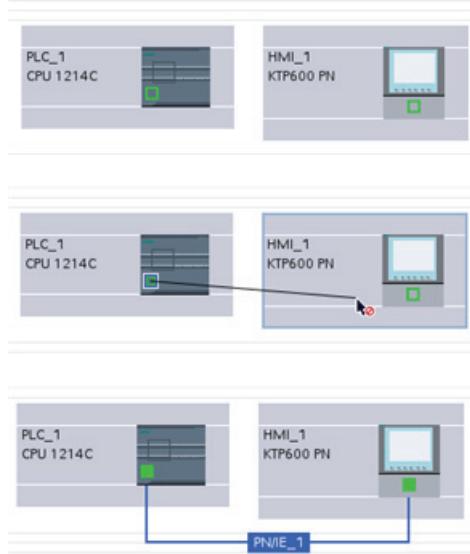


The HMI device is added to the project.

STEP 7 Basic provides an HMI wizard that helps you configure all of the screens and structure for your HMI device.

If you do not run the HMI wizard, STEP 7 Basic creates a simple default HMI screen.

Creating a network connection between the CPU and HMI device



Creating a network is easy!

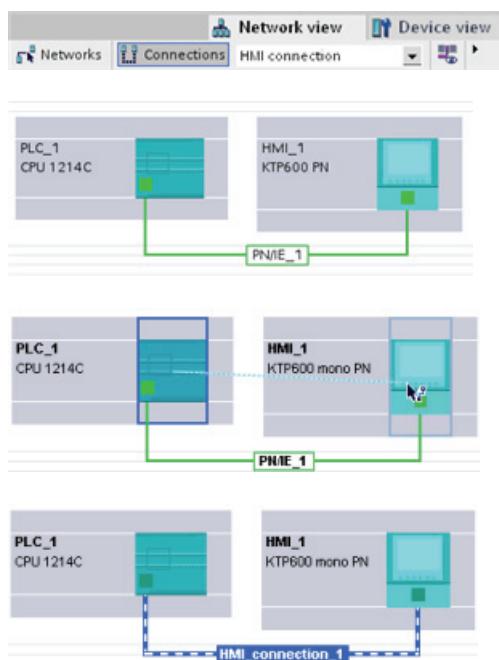
Go to "Devices and Networks" and select the Network view to display the CPU and HMI device.

To create a PROFINET network, drag a line from the green box (Ethernet port) on one device to the green box on the other device.

A network connection is created for the two devices.

Creating an HMI connection for sharing the tags

By creating an HMI connection between the two devices, you can easily share the tags between the two devices.



With the network connection selected, click the "HMI connection" button.

The HMI connection turns the two devices blue.

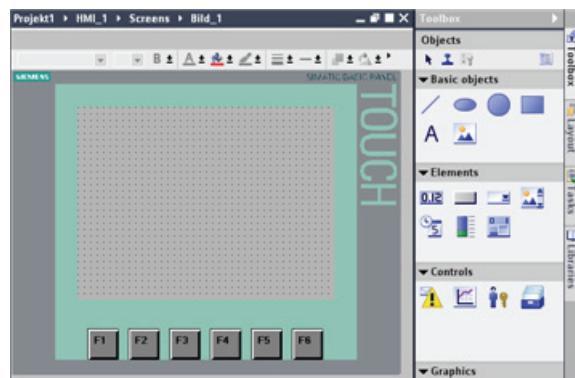
Select the CPU device and drag the line to the HMI device.

The HMI connection allows you to configure the HMI tags by selecting a list of PLC tags.

You can use other options for creating an HMI connection:

- Dragging a PLC tag from the PLC tag table, the program editor or the device configuration editor to the HMI screen editor automatically creates an HMI connection.
- Using the HMI wizard to browse for the PLC automatically creates the HMI connection.

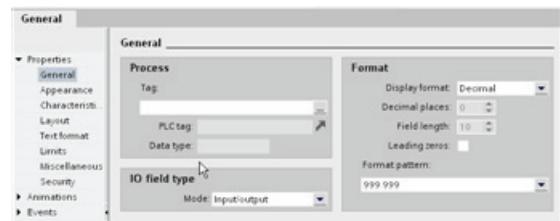
Creating an HMI screen



Even if you do not utilize the HMI wizard, configuring an HMI screen is easy.

STEP 7 Basic provides a standard set of libraries for inserting basic shapes, interactive elements, and even standard graphics.

To add an element, simply drag and drop one of the elements onto the screen.

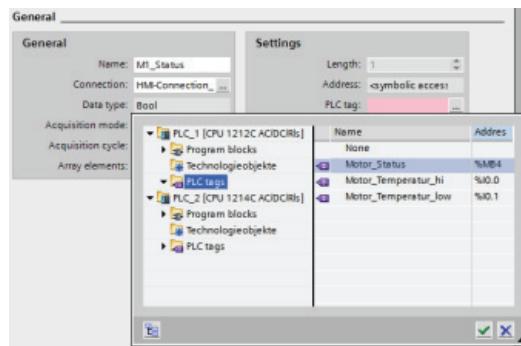


Use the properties for the element (in the Inspector window) to configure the appearance and behavior of the element.

You can also create elements on your screen by dragging and dropping PLC tags either from the Project tree or the program editor to the HMI screen. The PLC tag becomes an element on the screen. You can then use the properties to change the parameters for this element.

Selecting a PLC tag for an HMI element

After you create the element on your screen, use the properties of the element to select assign a PLC tag to the element. Clicking the button by the "Connections" field displays the PLC tags of the CPU.



You can also drag and drop PLC tags from the Project tree to the HMI screen. Display the PLC tags in the "Details" view of the project tree and then drag the tag to the HMI screen.

4

PLC concepts made easy

4.1 Tasks performed every scan cycle

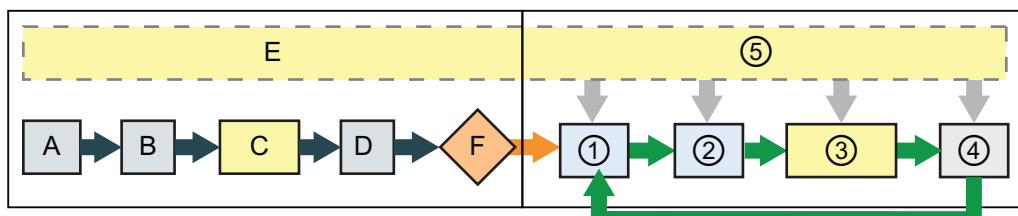
Each scan cycle includes writing the outputs, reading the inputs, executing the user program instructions, and performing system maintenance or background processing. The cycle is referred to as a scan cycle or scan. Under default conditions, all digital and analog I/O points are updated synchronously with the scan cycle using an internal memory area called the process image. The process image contains a snapshot of the physical inputs and outputs on the CPU, signal board, and signal modules.



The CPU reads the physical inputs just prior to the execution of the user program and stores the input values in the process image input area. This ensures that these values remain consistent throughout the execution of the user instructions.

The CPU executes the logic of the user instructions and updates the output values in the process image output area instead of writing to the actual physical outputs.

After executing the user program, the CPU writes the resulting outputs from the process image output area to the physical outputs.



STARTUP

- A Clears the input (or "I") memory
- B Initializes the outputs with either the last value or the substitute value
- C Executes the startup OBs
- D Copies the state of the physical inputs to I memory
- E Stores any interrupt events into the queue to be processed in RUN mode
- F Enables the writing of the output (or "Q") memory to the physical outputs

RUN

- ① Writes Q memory to the physical outputs
- ② Copies the state of the physical inputs to I memory
- ③ Executes the program cycle OBs
- ④ Performs self-test diagnostics
- ⑤ Processes interrupts and communications during any part of the scan cycle

This process provides consistent logic through the execution of the user instructions for a given cycle and prevents the flickering of physical output points that might change state multiple times in the process image output area.

You can change the default behavior for a module by removing it from this automatic update of I/O. You can also immediately read and write digital and analog I/O values to the modules when an instruction executes. Immediate reads of physical inputs do not update the process image input area. Immediate writes to physical outputs update both the process image output area and the physical output point.

4.2 Operating modes of the CPU

The CPU has three modes of operation: STOP mode, STARTUP mode, and RUN mode. Status LEDs on the front of the CPU indicate the current mode of operation.

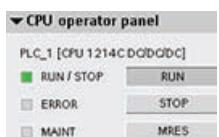
- In STOP mode, the CPU is not executing the program, and you can download a project.
- In STARTUP mode, the CPU executes any startup logic (if present). Interrupt events are not processed during the startup mode.
- In RUN mode, the scan cycle is executed repeatedly. Interrupt events can occur and be processed at any point within the program cycle phase.

Note

You cannot download a project while the CPU is in RUN mode. You can download your project **only** when the CPU is in STOP mode.

The CPU supports the warm restart method for entering the RUN mode. Warm restart does not include a memory reset, but a memory reset can be commanded from the programming software. A memory reset clears all work memory, clears retentive and non-retentive memory areas, and copies load memory to work memory. A memory reset does not clear the diagnostics buffer or the permanently saved IP address. All non-retentive system and user data are initialized at warm restart.

You can specify the power-up mode of the CPU complete with restart method using the programming software. This configuration item appears under the Device Configuration for the CPU under Startup. When power is applied, the CPU performs a sequence of power-up diagnostic checks and system initialization. The CPU then enters the appropriate power-up mode. Certain detected errors will prevent the CPU from entering the RUN mode. The CPU supports the following power-up modes: STOP mode, "Go to RUN mode after warm restart", and "Go to previous mode after warm restart".



The CPU does not provide a physical switch for changing the operating mode. Use the CPU operator panel in the online tools of STEP 7 Basic to change the operating mode (STOP or RUN).

You can also include a STP instruction in your program to change the CPU to STOP mode. This allows you to stop the execution of your program based on the program logic.

4.3 Memory areas, addressing and data types

The CPU provides the following memory areas to store the user program, data, and configuration:

- Load memory is non-volatile storage for the user program, data and configuration. When a project is downloaded to the CPU, it is first stored in the Load memory area. This area is located either in a memory card (if present) or in the CPU. This non-volatile memory area is maintained through a power loss. The memory card supports a larger storage space than that built-in to the CPU.
- Work memory is volatile storage for some elements of the user project while executing the user program. The CPU copies some elements of the project from load memory into work memory. This volatile area is lost when power is removed, and is restored by the CPU when power is restored.
- Retentive memory is non-volatile storage for a limited quantity of work memory values. The retentive memory area is used to store the values of selected user memory locations during power loss. When a power down occurs, the CPU has enough hold-up time to retain the values of a limited number of specified locations. These retentive values are then restored upon power up.

An optional SIMATIC memory card provides an alternative memory for storing your user program or a means for transferring your program. If you use the memory card, the CPU runs the program from the memory card and not from the memory in the CPU.



The CPU supports only a preformatted SIMATIC memory card.

To insert a memory card, open the top CPU door and insert the memory card in the slot. A push-push type connector allows for easy insertion and removal. The memory card is keyed for proper installation.

Check that the memory card is not write-protected. Slide the protection switch away from the "Lock" position.

Use the optional SIMATIC memory card either as a program card or as a transfer card:

- Use the transfer card to copy your project to multiple CPUs without using STEP 7 Basic. The transfer card copies a stored project from the card to the memory of the CPU. You must remove the transfer card after copying the program to the CPU.
- The program card takes the place of CPU memory; all of your CPU functions are controlled by the program card. Inserting the program card erases all of the internal load memory of the CPU (including the user program and any forced I/O). The CPU then executes the user program from the program card.

The program card **must** remain in the CPU. If you remove the program card, the CPU goes to STOP mode.

Data types supported by S7-1200



Data types are used to specify both the size of a data element as well as how the data are to be interpreted. Each instruction parameter supports at least one data type, and some parameters support multiple data types. Hold the cursor over the parameter field of an instruction to see which data types are supported for a given parameter.

Data type	Size (bits)	Range	Constant Entry Examples
Bool	1	0 to 1	TRUE, FALSE, 0, 1
Byte	8	16#00 to 16#FF	16#12, 16#AB
Word	16	16#0000 to 16#FFFF	16#ABCD, 16#0001
DWord	32	16#00000000 to 16#FFFFFFFF	16#02468ACE
Char	8	16#00 to 16#FF	'A', 't', '@'
Sint	8	-128 to 127	123, -123
Int	16	-32,768 to 32,767	123, -123
Dint	32	-2,147,483,648 to 2,147,483,647	123, -123
USInt	8	0 to 255	123
UInt	16	0 to 65,535	123
UDInt	32	0 to 4,294,967,295	123
Real	32	+/-1.18 x 10 ⁻³⁸ to +/-.3.40 x 10 ³⁸	123.456, -3.4, -1.2E+12, 3.4E-3
LReal	64	+/-2.23 x 10 ⁻³⁰⁸ to +/-.1.79 x 10 ³⁰⁸	12345.123456789 -1.2E+40
Time	32	T#-24d_20h_31m_23s_648ms to T#24d_20h_31m_23s_647ms Stored as: -2,147,483,648 ms to +2,147,483,647 ms	T#5m_30s 5#-2d T#1d_2h_15m_30x_45ms
String	Variable	0 to 254 byte-size characters	'ABC'
DTL ¹	12 bytes	Minimum: DTL#1970-01-01:00:00:00.0 Maximum: DTL#2554-12-31:23:59:59.999 999 999	DTL#2008-12-16-20:30:20.250

¹ The DTL data type is a structure of 12 bytes that saves information on date and time in a predefined structure. You can define a DTL in either the Temp memory of the block or in a DB.

Although not available as data types, the following BCD numeric format is supported by the conversion instructions.

Format	Size (bits)	Numeric Range	Examples
BCD16	16	-999 to 999	123, -123
BCD32	32	-9999999 to 9999999	1234567, -1234567

Memory areas and addressing

STEP 7 Basic facilitates symbolic programming. You create symbolic names or "tags" for the addresses of the data, whether as PLC tags relating to memory addresses and I/O points or as local variables used within a code block. To use these tags in your user program, simply enter the tag name for the instruction parameter. For a better understanding of how the CPU structures and addresses the memory areas, the following paragraphs explain the "absolute" addressing that is referenced by the PLC tags. The CPU provides several options for storing data during the execution of the user program:

- Global memory: The CPU provides a variety of specialized memory areas, including inputs (I), outputs (Q) and bit memory (M). This memory is accessible by all code blocks without restriction
- Data block (DB): You can include DBs in your user program to store data for the code blocks. The data stored persists when the execution of the associated code block comes to an end. A "global" DB stores data that can be used by all code blocks, while an instance DB stores data for a specific FB and is structured by the parameters for the FB.
- Temp memory: Whenever a code block is called, the operating system of the CPU allocates the temporary, or local, memory (L) to be used during the execution of the block. When the execution of the code block finishes, the CPU reallocates the local memory for the execution of other code blocks.

Each different memory location has a unique address. Your user program uses these addresses to access the information in the memory location.

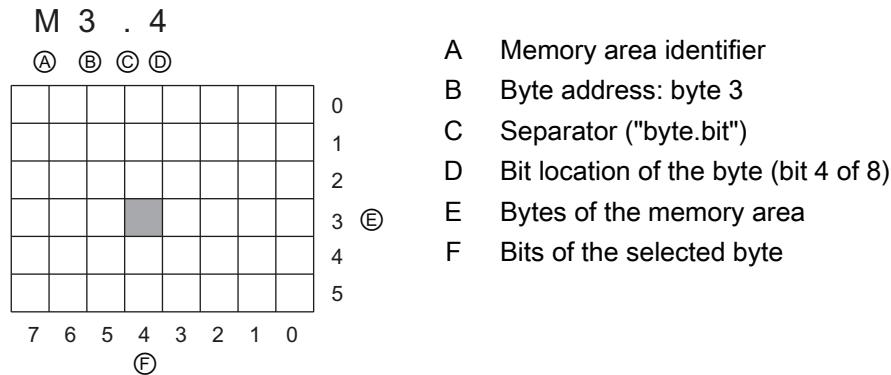
References to the input (I) or output (Q) memory areas, such as I0.3 or Q1.7, access the process image. To immediately access the physical input or output, append the reference with ":P" (such as I0.3:P, Q1.7:P, or "Stop:P").

Forcing writes a value to an input (I) or an output (Q) only. To force an input or output, append a ":P" to the PLC tag or the address. For more information, see "Forcing variables in the CPU" (Page 94).

Memory area	Description	Force	Retentive
I Process image input	Copied from physical inputs at the beginning of the scan cycle	No	No
I_:P ¹ (Physical input)	Immediate read of the physical input points on the CPU, SB, and SM	Yes	No
Q Process image output	Copied to physical outputs at the beginning of the scan cycle	No	No
Q_:P ¹ (Physical output)	Immediate write to the physical output points on the CPU, SB, and SM	Yes	No
M Bit memory	Control and data memory	No	Yes (optional)
L Temp memory	Temporary data for a block local to that block	No	No
DB Data block	Data memory and also parameter memory for FBs	No	Yes (optional)

¹ To immediately access (or to force) the physical inputs and physical outputs, append a ":P" to the address or tag (such as I0.3:P, Q1.7:P, or "Stop:P").

Each different memory location has a unique address. Your user program uses these addresses to access the information in the memory location. The figure shows how to access a bit (which is also called "byte.bit" addressing). In this example, the memory area and byte address (M = bit memory area, and 3 = byte 3) are followed by a period (".") to separate the bit address (bit 4).



Configuring the addresses for the I/O

Module	Slot	I address	Q address	Type	Order
RS485_1	101			OM 1241 (RS485)	6E57
PLC_1	1			CPU 1214C D/O/D	6E57
DI14/DO10	1.1	0..1	0..1	DI14/DO10	
AI2	1.2	64..67		AI2	
AO1 x 12bit	1.3		80..81	AO1 signal board	6E57
HSC_1	1.16	1000.....		High speed counter	
HSC_2	1.17			High speed counter	
HSC_3	1.18			High speed counter	
HSC_4	1.19			High speed counter	
HSC_5	1.20			High speed counter	
HSC_6	1.21			High speed counter	
Pulse_1	1.32			Pulse generator (P)	
Pulse_2	1.33			Pulse generator (P)	
PROFINET I.	X1			PROFINET Interface	
DIB x 24VDC	2			SM 1221 DIB x 24	6E57

When you add a CPU and I/O modules to your configuration screen, I and Q addresses are automatically assigned.

You can change the default addressing by selecting the address field in the configuration screen and typing new numbers. Digital inputs and outputs are assigned in complete 8 bit bytes, whether the module uses all the points or not. Analog inputs and outputs are assigned in groups of 2 points (4 bytes). In this example, you could change the address of the DI16 to 2..3 instead of 8..9. The tool will assist you by changing address ranges that are the wrong size or conflict with other addresses.

The figure shows an example of a CPU 1214C with two SMs.

4.4 Execution of the user program

The CPU supports the following types of code blocks that allow you to create an efficient structure for your user program:

- An organization block (OB) is a code block that typically contains the main program logic. The OB responds to a specific event in the CPU and can interrupt the execution of the user program. The default for the cyclic execution of the user program (OB 1) provides the base structure for your user program and is the only code block required for a user program. The other OBs perform specific functions, such as for startup tasks, for handling interrupts and errors, or for executing specific program code at specific time intervals.
- A function block (FB) is a subroutine that is executed when called from another code block (OB, FB, or FC). The calling block passes parameters to the FB and also identifies a specific data block (DB) that stores the data for the specific call or instance of that FB. Changing the instance DB allows a generic FB to control the operation of a set of devices. For example, one FB can control several pumps or valves, with different instance DBs containing the specific operational parameters for each pump or valve. The instance DB maintains the values of the FB between different or consecutive calls of that FB, such as to support asynchronous communication.
- A function (FC) is a subroutine that is executed when called from another code block (OB, FB, or FC). The FC does not have an associated instance DB. The calling block passes parameters to the FC. The output values from the FC must be written to a memory address or to a global DB if other components of your user program need to use these values.

The size of the user program, data, and configuration is limited by the available load memory and the work memory in the CPU. There is no limit to the number of blocks supported; the only limit is due to memory size.

Using OBs to handle events

The processing of the CPU scan is driven by events. The default event is a program cycle event that starts the execution of the program cycle OB. (You are not required to use a program cycle OB in your program. However, if you do not have a program cycle OB, normal I/O updates are not performed. You must then use the process image to read and write the I/O.) Other events can be enabled if required. Some events, such as the cyclic event, are enabled at configuration time. Other events, such as the time delay event, are enabled at runtime. When enabled, an event is attached to an associated OB. (The program cycle and startup events can each be attached to multiple OBs.) An occurrence of an event leads to the execution of its event service routine, which is the attached OB plus any functions called from the OB. Priorities, priority groups, and queues are used to determine the processing order for the event service routines.

The number of pending (queued) events from a single source is limited using a different queue for each event type. Upon reaching the limit of pending events for a given event type, the next event is lost. Each event has an associated priority, and the event priorities are classified into priority groups, as shown in the following table.

In general, events are serviced in order of priority (highest priority first). Events of the same priority are serviced on a "first-come, first-served" basis. After the execution of an OB has started, the processing of the OB cannot be interrupted by the occurrence of another event from the same or lower priority group. Such events are queued for later processing, which allows the CPU to complete the execution of the current OB.

4.4 Execution of the user program

An OB within a priority group does not interrupt another OB within the same priority group. However, an event in priority group 2 will interrupt the execution of an OB in priority group 1, and an event in priority group 3 will interrupt the execution of any OB in either priority group 1 or 2.

Event (OB)	Quantity	OB number	Queue depth	Priority group	Priority class
Program cycle	1 program cycle event Multiple OBs allowed	1 (default) 200 or greater	1	1	1
Startup	1 startup event ^{1, 2} Multiple OBs allowed	100 (default) 200 or greater	1		1
Time delay	Up to 4 time events ³ 1 OB per event	200 or greater	8	2	3
Cyclic	Up to 4 time events ³ 1 OB per event	200 or greater	8		4
Edges	16 rising edge events 16 falling edge events 1 OB per event	200 or greater	32		5
HSC	6 CV = PV events 6 direction changed events 6 external reset events 1 OB per event	200 or greater	16		6
Diagnostic error	1 event (OB 82 only)	82 only	8	3	9
Time error	1 time-error event 1 MaxCycle time event (OB 80 only) 1 2xMaxCycle	80 only	8		26 27

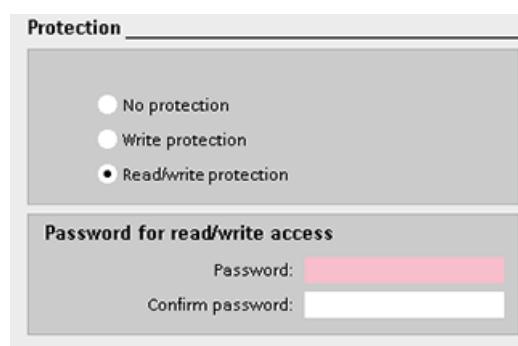
- ¹ Special case for the startup event: The startup event and the program cycle event will never occur at the same time because the startup event will run to completion before the program cycle event will be started (controlled by the operating system).
- ² Special case for the startup event: Only the diagnostic error event (associated with OB 82) is allowed to interrupt the startup event. All other events are queued for later processing after the startup event is finished.
- ³ The CPU provides a total of 4 time events that are shared by the time-delay OBs and the cyclic OBs. The number of time-delay and cyclic OBs in your user program cannot exceed 4.

An OB in a higher priority group interrupts the execution of an OB in a lower priority group. For example, an OB in priority group 2 (such as a cyclic interrupt OB) interrupts a program cycle OB (priority group 1), and an OB 80 (priority group 3) interrupts any OB in either priority group 1 or 2. However, the OBs within the same priority group do not interrupt each other. The CPU stores any events that occur during the processing of an OB. After completing the execution of that OB, the CPU then executes those OBs in the queue according to the relative priority class within that priority group, processing the event with higher priority class first. However, the CPU executes each OB within that priority group to completion before starting the execution of the next OB within the same priority group. After processing all of the events for the interrupting priority group, the CPU then returns to the OB in the lower priority group that had been interrupted and resumes the execution of that OB at the point where it had been interrupted.

If the CPU were to detect an event in priority group 3 (such as a time error event), the time-error OB interrupts the processing of both priority group 1 (such as a program cycle OB) and priority group 2 (such as a cyclic OB). The CPU executes the time-error OB and then returns to the execution of the OB that was interrupted, either in priority group 2 (if interrupted) or in priority group 1.

4.5 Protecting access to the CPU or code block is easy

The CPU provides 3 levels of security for restricting access to specific functions. When you configure the security level and password for a CPU, you limit the functions and memory areas that can be accessed without entering a password.



To configure the password, follow these steps:

1. In the "Device configuration", select the CPU.
2. In the inspector window, select the "Properties" tab.
3. Select the "Protection" property to select the protection level and to enter a password.

The password is case sensitive.

Each level allows certain functions to be accessible without a password. The default condition for the CPU is to have no restriction and no password-protection. To restrict access to a CPU, you configure the properties of the CPU and enter the password.

Entering the password over a network does not compromise the password protection for the CPU. A password-protected CPU allows only one user unrestricted access at a time. Password protection does not apply to the execution of user program instructions including communication functions. Entering the correct password provides access to all of the functions.

PLC-to-PLC communications (using communication instructions in the code blocks) are not restricted by the security level in the CPU. HMI functionality is also not restricted.

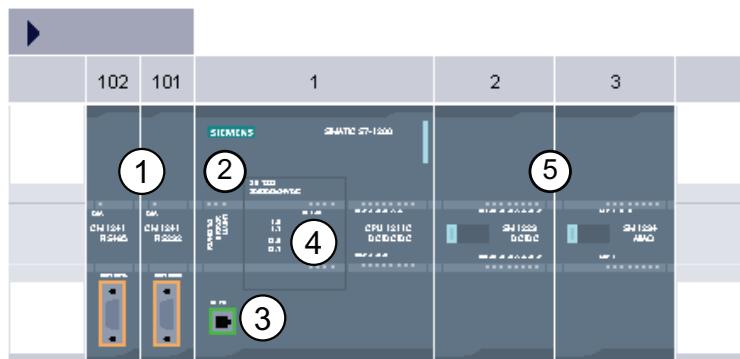
Security level	Access restrictions
No protection	Allows full access without password-protection.
Write protection	Allows read-only access to the CPU, HMI access, and PLC-to-PLC communications without password-protection. Password is required for modifying (writing to) the CPU and for changing the CPU mode (RUN/STOP).
Read/write protection	Allows HMI access and all forms of PLC-to-PLC communications without password-protection. Password is required for reading the data in the CPU, for modifying (writing to) the CPU, and for changing the CPU mode (RUN/STOP).

5

Programming concepts made easy

5.1 Easy to create the device configuration

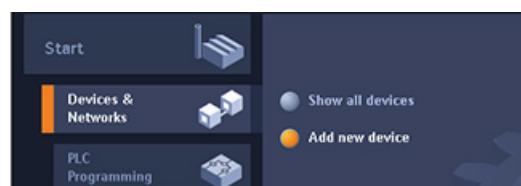
You create the device configuration for your PLC by adding a CPU and additional modules to your project.



- ① Communications module (CM): Up to 3, inserted in slots 101, 102, and 103
- ② CPU: Slot 1
- ③ Ethernet port of CPU
- ④ Signal board (SB): up to 1, inserted in the CPU
- ⑤ Signal module (SM) for digital or analog I/O: up to 8, inserted in slots 2 through 9
CPU 1214C allows 8, CPU 1212C allows 2, CPU 1211C does not allow any

To create the device configuration, add a device to your project.

- In the Portal view, select "Devices & Networks" and click "Add new device".

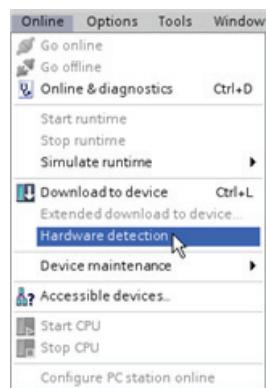


- In the Project view, under the project name, double-click "Add new device".



5.1 Easy to create the device configuration

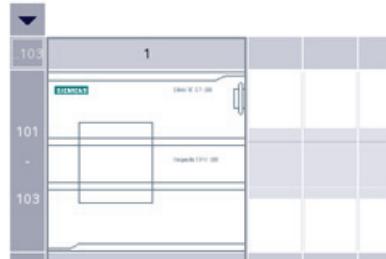
Uploading an existing hardware configuration is easy



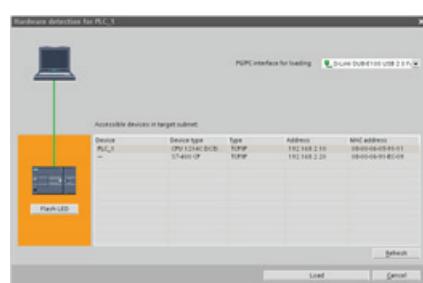
If you are connected to a CPU, you can upload the configuration of that CPU, including any modules, to your project. Simply create a new project and select the "unspecified CPU" instead of selecting a specific CPU. (You can also skip the device configuration entirely by selecting the "Create a PLC program" from the "First steps". STEP 7 Basic then automatically creates an unspecified CPU.)

From the program editor, you select the "Hardware detection" command from the "Online" menu.

From the device configuration editor, you select the option for detecting the configuration of the connected device.



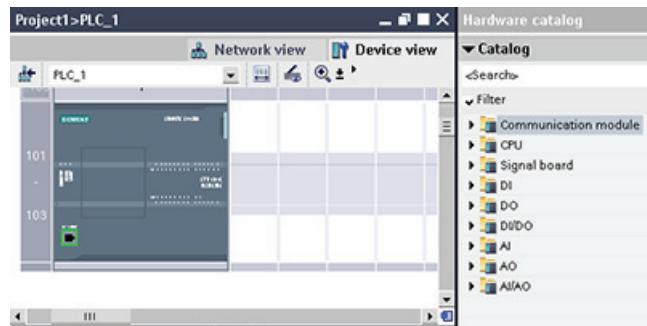
After you select the CPU from the online dialog, STEP 7 Basic uploads the hardware configuration from the CPU, including any modules (SM, SB, or CM). You can then configure the parameters for the CPU and the modules (Page 46).



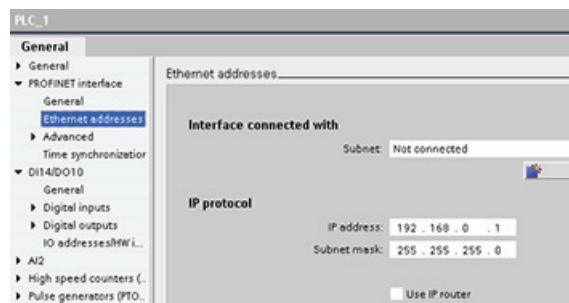
Adding a CPU to the configuration



You create your device configuration by inserting a CPU into your project. Select the CPU in the "Add a new device" dialog and click "OK" to add the CPU to the project.



The Device view shows the CPU and rack.



Selecting the CPU in the Device view displays the CPU properties in the inspector window. Use these properties to configure the operational parameters of the CPU (Page 46).

Note

The CPU does not have a pre-configured IP address. You must manually assign an IP address for the CPU during the device configuration. If your CPU is connected to a router on the network, you also enter the IP address for a router.

5.1 Easy to create the device configuration

Adding a device to the configuration

Use the hardware catalog to add modules to the CPU. There are three types of modules:

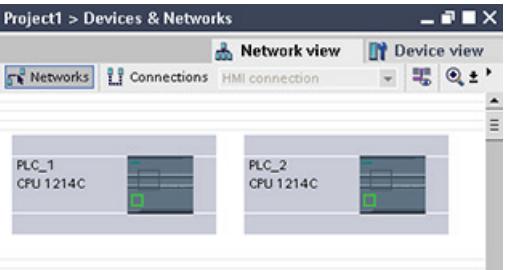
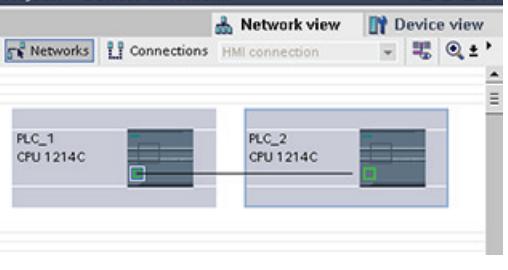
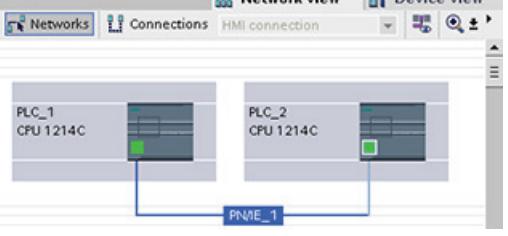
- Signal boards (SB) provide just a few additional I/O points for the CPU. The SB is installed on the front of the CPU.
- Signal modules (SM) provide additional digital or analog I/O points. These modules are connected to the right side of the CPU.
- Communication modules (CM) provide an additional communication port (RS232 or RS485) for the CPU. These modules are connected to the left side of the CPU.

To insert a module into the hardware configuration, select the module in the hardware catalog and either double-click or drag the module to the highlighted slot.

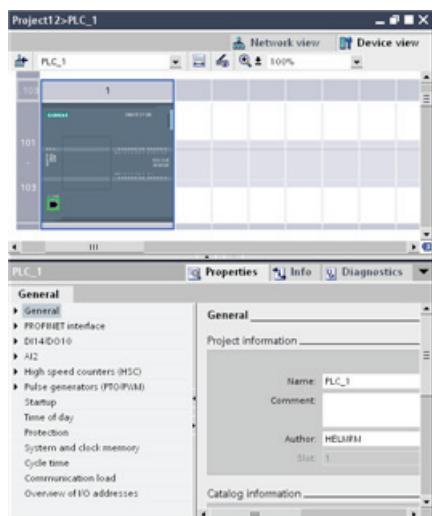
Module	Select the module	Insert the module	Result
SM	<p>Hardware catalog</p> <p>▼ Catalog</p> <p><Search></p> <p>▼ Filter</p> <ul style="list-style-type: none"> ▶ Communication module ▶ CPU ▶ Signal board ▶ DI ▶ DI8 x 24VDC 6ES7 221-1BF30-0 ▶ DI16 x 24VDC 		
SB	<p>Hardware catalog</p> <p>▼ Catalog</p> <p><Search></p> <p>▼ Filter</p> <ul style="list-style-type: none"> ▶ Communication module ▶ CPU ▶ Signal board ▶ DI2/DO2 x 24VDC 6ES7 223-0BD30-0 ▶ AO1 x 12bits ▶ DI ▶ DO 		
CM	<p>Hardware catalog</p> <p>▼ Catalog</p> <p><Search></p> <p>▼ Filter</p> <ul style="list-style-type: none"> ▶ Communication module ▶ RS232 ▶ RS485 6ES7 241-1CH30-0 ▶ CPU ▶ Signal board ▶ DI ▶ DO 		

Configuring a network connection

Use the "Network view" of Device configuration to create the network connections between the devices in your project. After creating the network connection, use the "Properties" tab of the inspector window to configure the parameters of the network.

Network view of "Device configuration"	Description
	Select "Network view" to display the devices to be connected.
	Select the port on one device and drag the connection to the port on the second device.
	Release the mouse button to create the network connection.

5.1.1 Configuring the operation of the CPU and modules



To configure the operational parameters for the CPU, select the CPU in the Device view and use the "Properties" tab of the inspector window.

- PROFINET IP address and time synchronization for the CPU
- Startup behavior of the CPU following an off-to-on transition
- Local (on-board) digital and analog I/O, high-speed counters (HSC), and pulse generators
- System clock (time, time zone and daylight saving time)
- Read/write protection and password for accessing the CPU
- Maximum cycle time or a fixed minimum cycle time and communications load

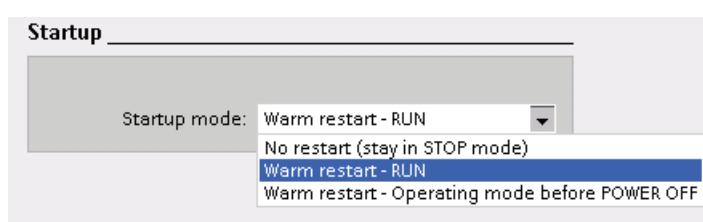
Configuring the STOP-to-RUN operation of the CPU

Whenever the operating state changes from STOP to RUN, the CPU clears the process image inputs, initializes the process image outputs, and processes the startup OBs. (Therefore, any read accesses to the process-image inputs by instructions in the startup OBs will read zero rather than the current physical input value.) To read the current state of a physical input during the startup mode, you must perform an immediate read. The startup OBs and any associated FCs and FBs are executed next. If more than one startup OB exists, each is executed in order according to the OB number, with the lowest OB number executing first.

The CPU also performs the following tasks during the startup processing.

- Interrupts are queued but not processed during the startup phase
- No cycle time monitoring is performed during the startup phase
- Configuration changes to HSC (high-speed counter), PWM (pulse-width modulation), and PtP (point-to-point communication) modules can be made in startup
- Actual operation of HSC, PWM, and point-to-point communication modules only occurs in RUN

After the execution of the startup OBs finishes, the CPU goes to RUN mode and processes the control tasks in a continuous scan cycle.



Use the CPU properties to configure how the CPU starts up after a power cycle: in STOP mode, in RUN mode, or in the previous mode (prior to the power cycle).

The CPU performs a warm restart before going to RUN mode. Warm restart resets all non-retentive memory to the default start values, but the CPU retains the current values stored in the retentive memory.

Note

The CPU always performs a cold restart after a download

Whenever you download an element of your project (such as a program block, data block, or hardware configuration), the CPU performs a cold restart on the next transition to RUN mode. In addition to clearing the inputs, initializing the outputs and clearing the non-retentive memory the cold restart also clears the retentive memory areas.

After the cold restart that follows a download, all subsequent STOP-to-RUN transitions perform a warm restart (that does not clear the retentive memory).

Configuring the operation of the I/O and communication modules

To configure the operational parameters for the signal module (SM), signal board (SB), or communication module (CM), select the module in the Device view and use the "Properties" tab of the inspector window.

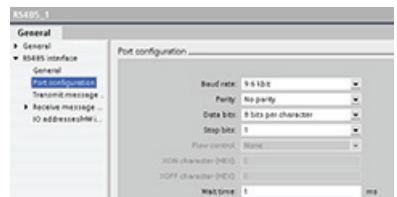
Signal module (SM) and signal board (SB)

- Digital I/O: Configure the individual inputs, such as for Edge detection and "pulse catch" (to stay on after a momentary pulse). Configure the outputs to use a freeze or substitute value on a transition from RUN mode to STOP mode.
- Analog I/O: Configure the parameters for individual inputs (such as voltage / current, range and smoothing) and also enables underflow or overflow diagnostics. Configure the parameters for individual analog outputs and enables diagnostics, such as short-circuit (for voltage outputs) or overflow values.
- Diagnostic addresses: Configure the start address for the set of inputs and outputs of the module.



Communication module (CM)

- Port configuration: Configure the communication parameters, such as baud rate, parity, data bits, stop bits, and wait time
- Transmit and receive message: Configure options related to transmitting and receiving data (such as the message-start and message-end parameters)



You can also change these configuration parameters with your user program.

5.1.2 Configuring the IP address of the CPU

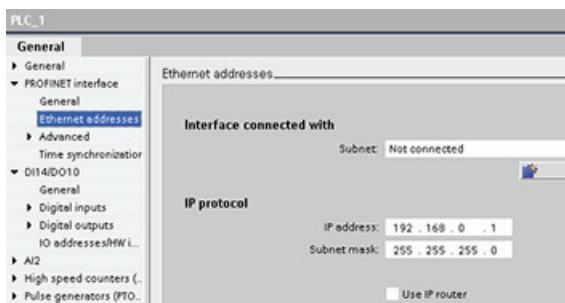
Because the CPU does not have a pre-configured IP address, you must manually assign an IP address. You configure the IP address and the other parameters for the PROFINET interface when you configure the properties for the CPU.

- In a PROFINET network, each device is assigned a unique Media Access Control address (MAC address) by the manufacturer for identification. Each device must also have an IP address.
- A subnet is a logical grouping of connected network devices. A mask (also known as the subnet mask or network mask) defines the boundaries of a subnet. The only connection between different subnets is via a router. Routers are the link between LANs and rely on IP addresses to deliver and receive data packets.

Before you can download an IP address to the CPU, you must ensure that the IP address for your computer matches the IP address of your programming device.

You can use STEP 7 Basic to determine the IP address of your programming device:

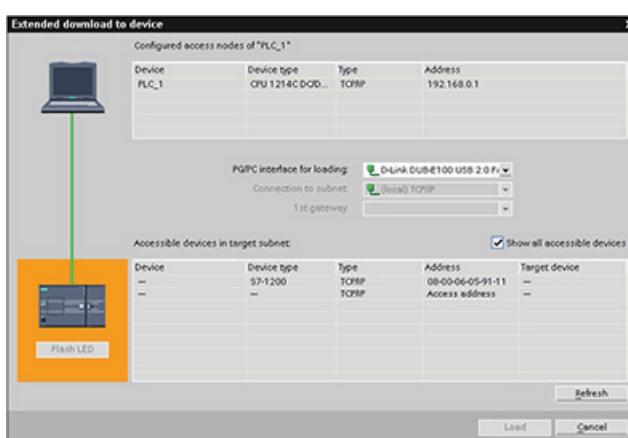
1. Right-click the "Online access" folder in the Project tree" to display the context menu.
2. Select the "Properties" command.



The dialog displays the settings for the programming device.

The IP address for the CPU must be compatible with the IP address and subnet mask for the programming device. Consult your network specialist for the IP address and subnet mask for your CPU.

After determining the IP address and subnet mask for the CPU, enter the IP address for the CPU and for the router (if applicable). Refer to the *S7-1200 System Manual* for more information.



After completing the configuration, download the project to the CPU.

The IP address for the CPU and for the router (if applicable) are configured when you download the project.

5.2 Easy to design your user program

When you create a user program for the automation tasks, you insert the instructions for the program into code blocks (OB, FB, or FC).

An OB is a code block that you use to structure or organize the user program for your application. For many applications, a continuously cycling OB, such as the program cycle OB 1, contains the program logic. In addition to the program cycle OB, the CPU provides other OBs that perform specific functions, such as startup tasks, the handling of interrupts and errors, or the execution of specific program code at specific time intervals. Every OB responds to a specific event in the CPU and can interrupt the execution of the user program, according to pre-defined priority groups and classes..

An FB is a subroutine that is executed when called from another code block (OB, FB, or FC). The calling block passes parameters to the FB and also identifies a specific data block (DB) that stores the data for the specific call or instance of that FB. Changing the instance DB allows a generic FB to control the operation of a set of devices. For example, one FB can control several pumps or valves, with different instance DBs containing the specific operational parameters for each pump or valve. The instance DB maintains the values of the FB between different or consecutive calls of that FB, such as to support asynchronous communication.

An FC is a subroutine that is executed when called from another code block (OB, FB, or FC). The FC does not have an associated instance DB. The calling block passes parameters to the FC. The output values from the FC must be written to a memory address or to a global DB.

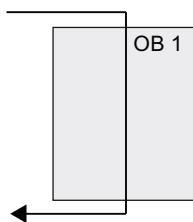
Choosing the type of structure for your user program

Based on the requirements of your application, you can choose either a linear structure or a modular structure for creating your user program.

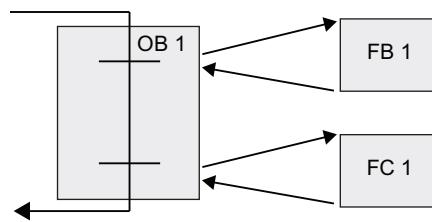
A linear program executes all of the instructions for your automation tasks in sequence, one after the other. Typically, the linear program puts all of the program instructions into one program cycle OB (OB 1) for cyclic execution of the program.

A modular program calls specific code blocks that perform specific tasks. To create a modular structure, you divide the complex automation task into smaller subordinate tasks that correspond to the functional tasks being performed by the process. Each code block provides the program segment for each subordinate task. You structure your program by calling one of the code blocks from another block.

Linear structure:

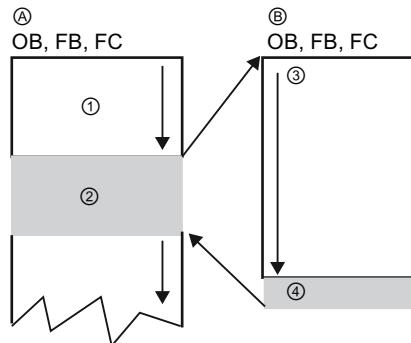


Modular structure:



By designing FBs and FCs to perform generic tasks, you create modular code blocks. You then structure your user program by having other code blocks call these reusable modules. The calling block passes device-specific parameters to the called block. When a code block calls another code block, the CPU executes the program code in the called block. After execution of the called block is complete, the CPU resumes the execution of the calling block. Processing continues with execution of the instruction that follows after the block call.

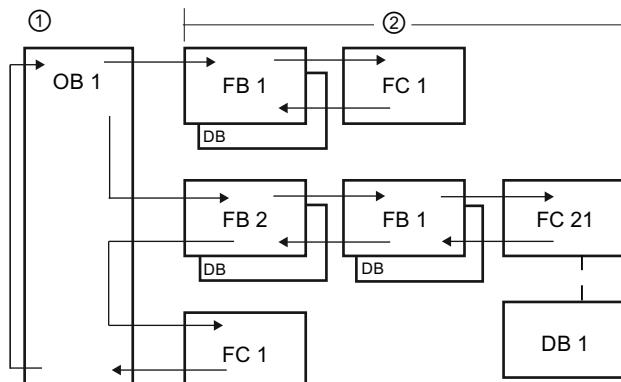
- A Calling block
- B Called (or interrupting) block
- ① Program execution
- ② Instruction or event that initiates the execution of another block
- ③ Program execution
- ④ Block end (returns to calling block)



You can nest the block calls for a more modular structure.

- ① Start of cycle
- ② Nesting depth

In this example, the nesting depth is 4: the program cycle OB plus 3 layers of calls to code blocks.



By creating generic code blocks that can be reused within the user program, you can simplify the design and implementation of the user program.

- You can create reusable blocks of code for standard tasks, such as for controlling a pump or a motor. You can also store these generic code blocks in a library that can be used by different applications or solutions.
- When you structure the user program into modular components that relate to functional tasks, the design of your program can be easier to understand and to manage. The modular components not only help to standardize the program design but can also help to make updating or modifying the program code quicker and easier.
- Creating modular components simplifies the debugging of your program. By structuring the complete program as a set of modular program segments, you can test the functionality of each code block as it is developed.
- Utilizing a modular design that relates to specific functional tasks can reduce the time required for the commissioning of the completed application.

5.2.1 Use OBs for organizing your user program

Organization blocks provide the structure for your program. They serve as the interface between the operating system and the user program. OBs are event-driven. An event, such as a diagnostic interrupt or a time interval, will cause the CPU to execute an OB. Some OBs have predefined start events and behavior.

The program cycle OB contains your main program. You can include more than one program cycle OB in your user program. During RUN mode, the program cycle OBs execute at the lowest priority level and can be interrupted by all other types of program processing. (The startup OBs do not interrupt the program cycle OBs because the CPU executes the startup OBs before going to RUN mode.) After finishing the processing of the program cycle OBs, the CPU immediately executes the program cycle OB again. This cyclic processing is the "normal" type of processing used for PLCs. For many applications, the entire user program is located in a single OB, such as the default program cycle OB 1.



You can create other OBs to perform specific functions, such as startup tasks, for handling interrupts and errors, or for executing specific program code at specific time intervals.

Use the "Add new block" dialog to create a new OB in your user program.

The CPU determines the order for handling interrupt events by a priority assigned to each OB (Page 37).

Creating an additional OB within a class of OB: You can create multiple OBs for your user program, even for the program cycle and startup OB classes. Use the "Add new block" dialog to create an OB. Enter the name for your OB and provide an OB number of 200 or greater.

If you create multiple program cycle OBs for your user program, the CPU executes each program cycle OB in numerical sequence, starting with the main program cycle OB (default: OB 1). For example, after first program cycle OB (OB 1) finishes, the CPU executes the second program cycle OB (such as OB 200).

Configuring the operation of an OB



You can modify the operational parameters for an OB. For example, you can configure the time parameter for a time-delay OB or for a cyclic interrupt OB.

5.2.2 FBs and FCs make programming the modular tasks easy

A function (FC) is like a subroutine. An FC is a code block that typically performs a specific operation on a set of input values. The FC stores the results of this operation in memory locations. Use FCs to perform the following tasks:

- To perform standard and reusable operations, such as for mathematical calculations.
- To perform functional tasks, such as for individual controls using bit logic operations.

An FC can also be called several times at different points in a program. This reuse simplifies the programming of frequently recurring tasks.

Unlike an FB, an FC does not have an associated instance DB. The FC uses its temp memory (L) for the data used to calculate the operation. The temporary data is not saved. To store data for use after the execution of the FC has finished, assign the output value to a global memory location, such as M memory or to a global DB.

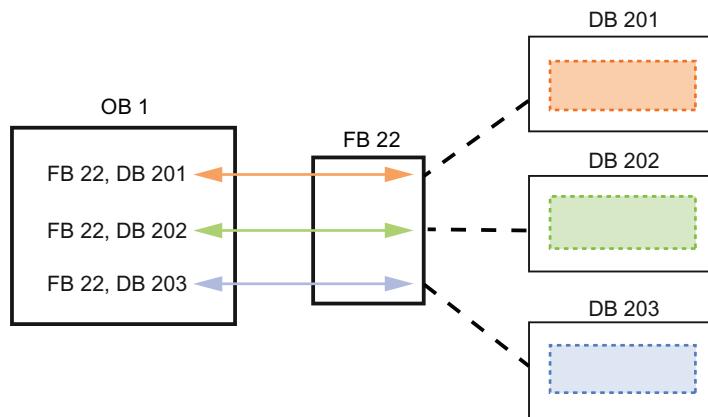
A function block (FB) is like a subroutine with memory. An FB is a code block whose calls can be programmed with block parameters. The FB stores the input (IN), output (OUT), and in/out (IN_OUT) parameters in variable memory that is located in a data block (DB), or "instance" DB. The instance DB provides a block of memory that is associated with that instance (or call) of the FB and stores data after the FB finishes.

You typically use an FB to control the operation for tasks or devices that do not finish their operation within one scan cycle. To store the operating parameters so that they can be quickly accessed from one scan to the next, each FB in your user program has one or more instance DBs. When you call an FB, you also open an instance DB that stores the values of the block parameters and the static local data for that call or "instance" of the FB. The instance DB stores these values after the FB finishes.

You can assign initial values to the parameters in the FB interface. These values are transferred to the associated instance DB. If you do not assign parameters, the values currently stored in the instance DB will be used. In some cases, you must assign parameters.

You can associate different instance DBs with different calls of the FB. The instance DBs allow you to use one generic FB to control multiple devices. You structure your program by having one code block make a call to an FB and an instance DB. The CPU then executes the program code in that FB and stores the block parameters and the static local data in the instance DB. When the execution of the FB finishes, the CPU returns to the code block that called the FB. The instance DB retains the values for that instance of the FB. By designing the FB for generic control tasks, you can reuse the FB for multiple devices by selecting different instance DBs for different calls of the FB.

The following figure shows an OB that calls one FB three times, using a different data block for each call. This structure allows one generic FB to control several similar devices, such as motors, by assigning a different instance data block for each call for the different devices. Each instance DB stores the data (such as speed, ramp-up time, and total operating time) for an individual device. In this example, FB 22 controls three separate devices, with DB 201 storing the operational data for the first device, DB 202 storing the operational data for the second device, and DB 203 storing the operational data for the third device.



5.2.3 Data blocks provide easy storage for program data

You create data blocks (DB) in your user program to store data for the code blocks. All of the program blocks in the user program can access the data in a global DB, but an instance DB stores data for a specific function block (FB).

Your user program can store data in the specialized memory areas of the CPU, such as for the inputs (I), outputs (Q), and bit memory (M). In addition, you can use a data block (DB) for fast access to data stored within the program itself. You can define a DB as being read-only.

The data stored in a DB is not deleted when the data block is closed or the execution of the associated code block comes to an end. There are two types of DBs:

- A global DB stores data for the code blocks in your program. Any OB, FB, or FC can access the data in a global DB.
- An instance DB stores the data for a specific FB. The structure of the data in an instance DB reflects the parameters (Input, Output, and InOut) and the static data for the FB. The Temp memory for the FB is not stored in the instance DB.

Although the instance DB reflects the data for a specific FB, any code block can access the data in an instance DB.

Creating a new code block



1. Open "Program blocks" folder.
2. Double-click "Add new block".
3. In the "Add new block" dialog, click the "Function (FC)" icon.
4. Specify the programming language for the FC by selecting "LAD" from the drop-down menu.
5. Click "OK" to add the block to the project.

Selecting the "Add new and open" option (default) opens the code block in the Project view.



You can easily have any code block (OB, FB, or FC) in your user program call an FB or FC in your CPU.

1. Open the code block that will call the other block.
2. In the project tree, select the code block to be called.
3. Drag the block to the selected network to create a Call instruction.

Note

Your user program cannot call an OB because OBs are event-driven (Page 37). The CPU starts the execution of the OB in response to receiving an event.

5.3 Easy to use the powerful programming languages

You have the option of choosing either the LAD (ladder logic) or FBD (Function Block Diagram) programming language.

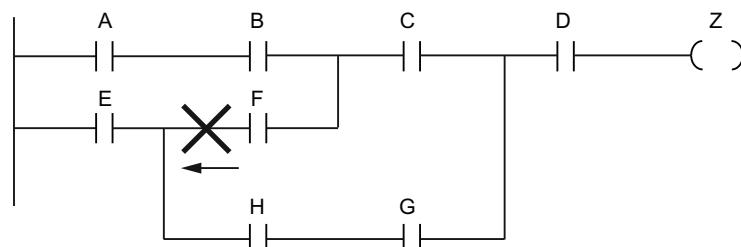
LAD is a graphical programming language. The representation is based on circuit diagrams. To create the logic for complex operations, you can insert branches to create the logic for parallel circuits. Parallel branches are opened downwards or are connected directly to the power rail. You terminate the branches upwards. LAD also provides "box" instructions for a variety of functions, such as math, timer, counter, and move.



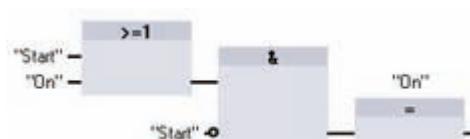
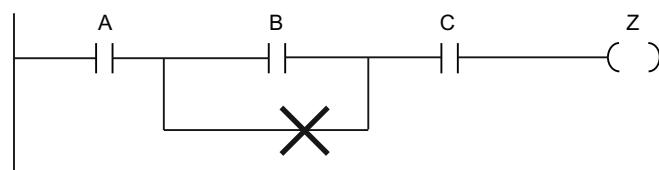
The elements of a circuit diagram (such as normally closed contacts, normally open contacts, and coils) are linked to form networks.

Consider the following rules when creating a LAD network:

- Every LAD network must terminate with a coil or a box instruction. Do not terminate a network with either a Compare instruction or an Edge-detection (Positive-edge or Negative-edge) instruction.
- You cannot create a branch that could result in a power flow in the reverse direction.



- You cannot create a branch that would cause a short circuit.



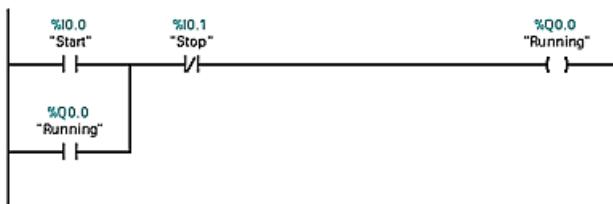
Like LAD, FBD is also a graphical programming language. The representation of the logic is based on the graphical logic symbols used in Boolean algebra.

Mathematical functions and other complex functions can be represented directly in conjunction with the logic boxes. To create the logic for complex operations, insert parallel branches between the boxes.

5.3.1 Providing the basic instructions you expect

Bit logic instructions

The basis of bit logic instruction is contacts and coils. Contacts read the status of a bit, while the coils write the status of the operation to a bit.



Contacts test the binary status of the bit, with the result being "power flow" if on (1) or "no power flow" if off (0).

The state of the coil reflects the status of the preceding logic.

If you use a coil with the same address in more than one program segment, the result of the last calculation in the user program determines the status of the value for that address.

Normally Open Contact



Normally Closed Contact



The Normally Open contact is closed (ON) when the assigned bit value is equal to 1.

The Normally Closed contact is closed (ON) when the assigned bit value is equal to 0.

The basic structure of a bit logic operation is either AND logic or OR logic. Contacts connected in series create AND logic networks. Contacts connected in parallel create OR logic networks.

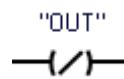
You can connect contacts to other contacts and create your own combination logic. If the input bit you specify uses memory identifier I (input) or Q (output), then the bit value is read from the process-image register. The physical contact signals in your control process are wired to input terminals on the PLC. The CPU scans the wired input signals and updates the corresponding state values in the process-image input register.

You can specify an immediate read of a physical input using ":P" following the tag for an input (such as "Motor_Start:P" or "I3.4:P"). For an immediate read, the bit data values are read directly from the physical input instead of the process image. An immediate read does not update the process image.

Output coil



Inverted output coil



- If there is power flow through an output coil, then the output bit is set to 1.
- If there is no power flow through an output coil, then the output coil bit is set to 0.
- If there is power flow through an inverted output coil, then the output bit is set to 0.
- If there is no power flow through an inverted output coil, then the output bit is set to 1.

The coil output instruction writes a value for an output bit. If the output bit you specify uses memory identifier Q, then the CPU turns the output bit in the process-image register on or off, setting the specified bit equal to power flow status. The output signals for your control actuators are wired to the output terminals of the PLC0. In RUN mode, the CPU system scans your input signals, processes the input states according to your program logic, and then reacts by setting new output state values in the process-image output register. After each program execution cycle, the CPU transfers the new output state reaction stored in the process-image register to the wired output terminals.

You can specify an immediate write of a physical output using ":P" following the tag for an output (such as "Motor_On:P" or "Q3.4:P"). For an immediate write, the bit data values are written to the process image output and directly to the physical output.

Coils are not restricted to the end of a network. You can insert a coil in the middle of a rung of the LAD network, in between contacts or other instructions.

NOT contact inverter (LAD)	AND box with one inverted logic input (FBD)	AND box with inverted logic input and output (FBD)
-------------------------------	---	--

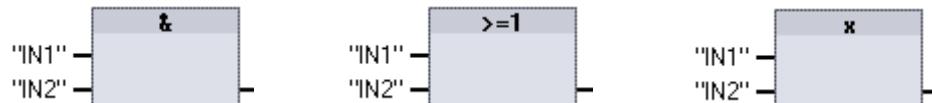


The LAD NOT contact inverts the logical state of power flow input.

- If there is no power flow into the NOT contact, then there is power flow out.
- If there is power flow into the NOT contact, then there is no power flow out.

For FBD programming, you can drag the "Negate binary input" tool from the "Favorites" toolbar or instruction tree and then drop it on an input or output to create a logic inverter on that box connector.

AND box (FBD)	OR box (FBD)	XOR box (FBD)
---------------	--------------	---------------



- All inputs of an AND box must be TRUE for the output to be TRUE.
- Any input of an OR box must be TRUE for the output to be TRUE.
- An odd number of the inputs of an XOR box must be TRUE for the output to be TRUE.

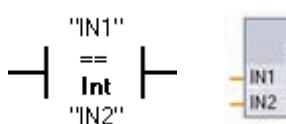
In FBD programming, the contact networks of LAD are represented by AND (&), OR (≥ 1), and exclusive OR (x) box networks where you can specify bit values for the box inputs and outputs. You may also connect to other logic boxes and create your own logic combinations. After the box is placed in your network, you can drag the "Insert binary input" tool from the "Favorites" toolbar or instruction tree and then drop it onto the input side of the box to add more inputs. You can also right-click on the box input connector and select "Insert input".

Box inputs and output can be connected to another logic box, or you can enter a bit address or bit symbol name for an unconnected input. When the box instruction is executed, the current input states are applied to the binary box logic and, if true, the box output will be true.

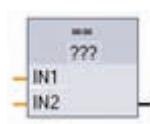
Compare instructions

You use the compare instructions to compare two values of the same data type. When the comparison is TRUE, the contact is activated (LAD) or the box output is TRUE (FBD).

LAD



FBD



After you click on the instruction in the program editor, you can select the comparison type and data type from the drop-down menus.

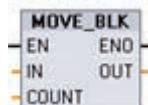
Relation type	The comparison is true if:
==	IN1 is equal to IN2
<>	IN1 is not equal to IN2
>=	IN1 is greater than or equal to IN2
<=	IN1 is less than or equal to IN2
>	IN1 is greater than IN2
<	IN1 is less than IN2

Move and Block Move instructions

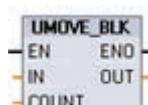
You use the move instructions to copy data elements to a new memory address and convert from one data type to another. The source data is not changed by the move process.



MOVE copies a data element stored at a specified address to a new address.



MOVE_BLK (interruptible move) copies a block of data elements to a new address



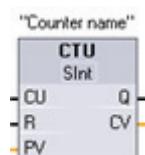
UMOVE_BLK (uninterruptible move) copies a block of data elements to a new address

- The MOVE instruction copies a single data element from the source address specified by the IN parameter to the destination address specified by the OUT parameter.
- The MOVE_BLK and UMOVE_BLK instructions have an additional COUNT parameter. The COUNT specifies how many data elements are copied. The number of bytes per element copied depends on the data type assigned to the IN and OUT parameter tag names in the PLC tag table.

Counters

You use the counter instructions to count internal program events and external process events. Each counter uses a structure stored in a data block to maintain counter data. You assign the data block when the counter instruction is placed in the editor. These instructions use software counters whose maximum counting rate is limited by the execution rate of the OB they are placed in.

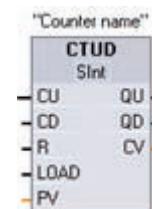
CTU counts up.



CTD counts down.



CTUD counts up and down.



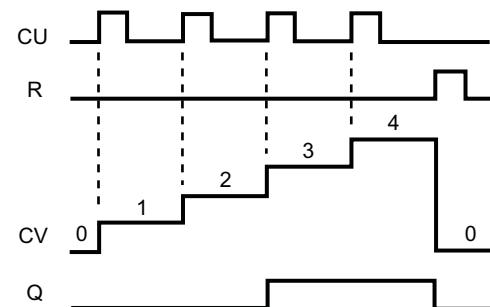
Select the count value data type from the drop-down list under the counter name.

The number of counters that you can use in your user program is limited only by the amount of memory in the CPU. Counters use the following amount of memory:

- For SInt or USInt data types, the counter instruction uses 3 bytes.
- For Int or UInt data types, the counter instruction uses 6 bytes.
- For DInt or UDInt data types, the counter instruction uses 3 bytes.

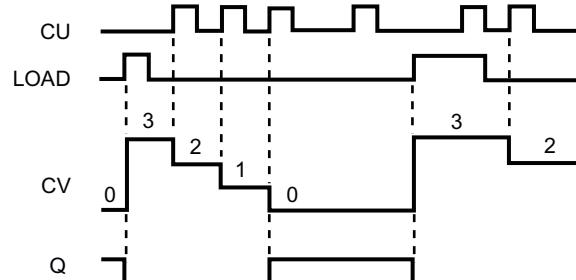
The CTU counts up by 1 when the value of parameter CU changes from 0 to 1. The figure shows a CTU timing diagram with an unsigned integer count value (where PV = 3).

- If the value of parameter CV (Current count value) is greater than or equal to the value of parameter PV (Preset count value), then the counter output parameter Q = 1.
- If the value of the reset parameter R changes from 0 to 1, then the current count value is reset to 0.



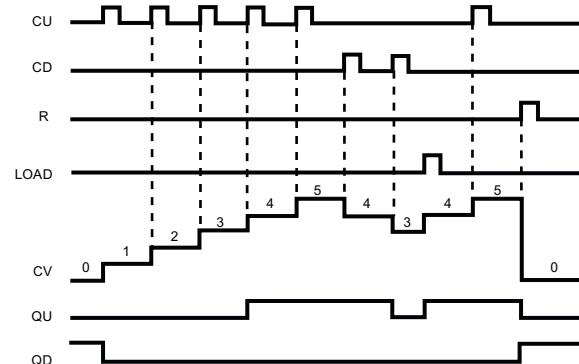
The CTD counts down by 1 when the value of parameter CD changes from 0 to 1. The figure shows a CTD timing diagram with an unsigned integer count value (where PV = 3).

- If the value of parameter CV (Current count value) is equal to or less than 0, the counter output parameter Q = 1.
- If the value of parameter LOAD changes from 0 to 1, the value at parameter PV (Preset value) is loaded to the counter as the new CV (Current count value).



The CTUD counts up or down by 1 on the 0 to 1 transition of the Count up (CU) or Count down (CD) inputs. The figure shows a CTUD timing diagram with an unsigned integer count value (where PV = 4).

- If the value of parameter CV (Current count value) is equal to or greater than the value of parameter PV (Preset value), then the counter output parameter QU = 1.
- If the value of parameter CV is less than or equal to zero, then the counter output parameter QD = 1.
- If the value of parameter LOAD changes from 0 to 1, then the value at parameter PV (Preset value) is loaded to the counter as the new CV (Current count value). If the value of the reset parameter R is changes from 0 to 1, the current count value is reset to 0.

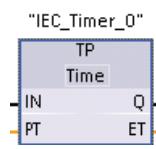


Timers

You use the timer instructions to create programmed time delays:

- TP: The pulse timer generates a pulse with a preset width time.
- TON: The on-delay timer output Q is set to ON after a preset time delay.
- TOF: The off-delay timer output Q is reset to OFF after a preset time delay.
- TONR: The on-delay retentive timer output is set to ON after a preset time delay. Elapsed time is accumulated over multiple timing periods until the R input is used to reset the elapsed time.
- RT: Reset a timer by clearing the time data stored in the specified timer instance data block.

TP, TON, and TOF timers have the same input and output parameters.



The TONR timer has the additional reset input parameter R.



The RT instruction resets the timer data for the specified timer.

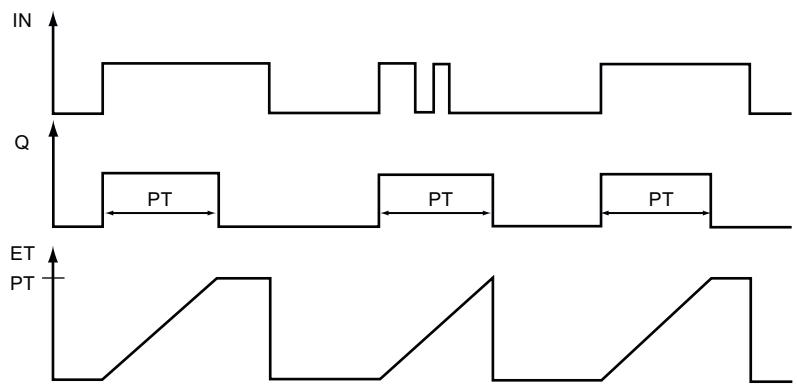
"Timer name"
----[RT]----

The number of timers that you can use in your user program is limited only by the amount of memory in the CPU. Each timer uses 16 bytes of memory:

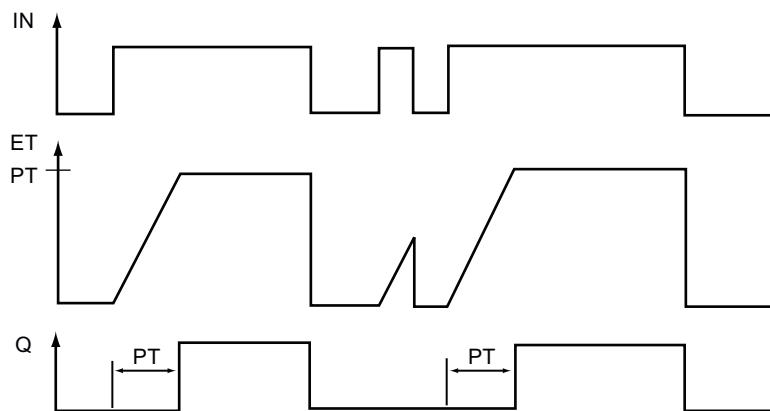
Each timer uses a structure stored in a data block to maintain timer data. You assign the data block when the timer instruction is placed in the editor. When you place timer instructions in a function block, you can select the multi-instance data block option, the timer structure names can be different with separate data structures, but the timer data is contained in a single data block and does not require a separate data block for each timer.

This reduces the processing time and data storage necessary for handling the timers. There is no interaction between the timer data structures in the shared multi-instance data block.

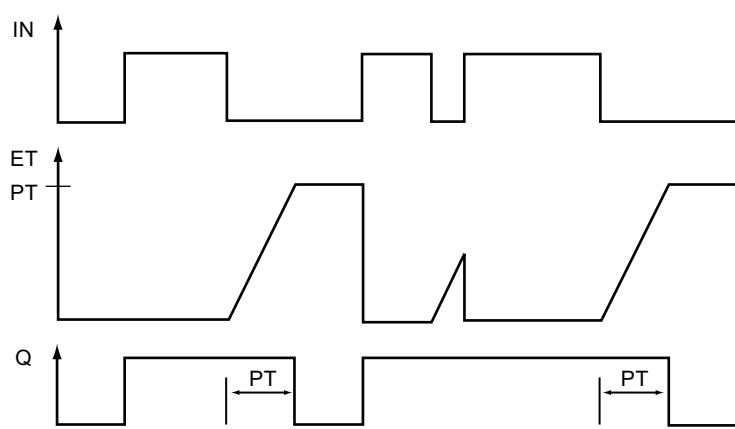
TP timer
Pulse timing diagram

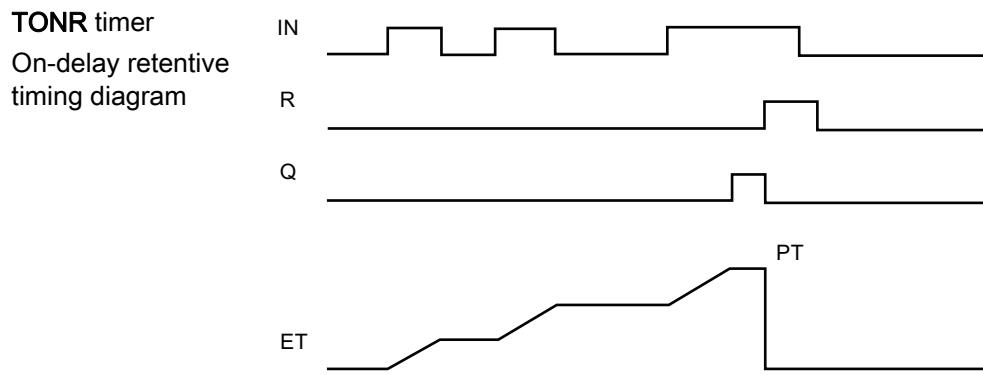


TON timer
On-delay timing diagram



TOF timer
Off-delay timing diagram





S7-1200 provides powerful instructions

In addition to the basic instructions, S7-1200 also provides an impressive set of instructions that help you easily resolve complex control applications. The following instructions are just a sampling of the power packed into the S7-1200.

CTRL_PWM instruction: The CTRL_PWM Pulse Width Modulation (PWM) instruction provides a fixed cycle time output with a variable duty cycle. The PWM output runs continuously after being started at the specified frequency (cycle time). The pulse width is varied as required.



For more information, see the description of pulse-width modulation (Page 84).

PID_Compact instruction: PID (Proportional/Integral/Derivative) control calculates the difference between feedback and set point value with the PID algorithm and outputs the result to actuators (such as heater or frequency converter) in order to maintain the set point. The PID_Compact instruction makes a PID controller with optimizing self tuning for automatic and manual mode available.

Execute the PID_Compact instruction at constant intervals of the sampling time (preferably in a cyclic interrupt OB).

The PID_Compact instruction measures the time interval between two calls and evaluates the results for monitoring the sampling time. A mean value of the sampling time is generated at each mode changeover and during initial startup. This value is used as reference for the monitoring function and is used for calculation in the block. Monitoring includes the current measuring time between two calls and the mean value of the defined controller sampling time.

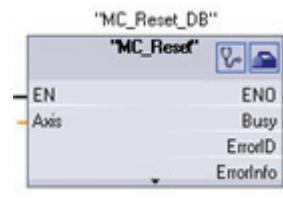


Modes	Description
Inactive	After the user program has been downloaded the first time, the PID controller remains in the "Inactive" operating mode. In this case carry out a "Self tuning during initial start" in the commissioning window. During ongoing operation the PID controller changes to the "Inactive" operating mode when an error occurs or when the "Controller stop" icon is clicked in the commissioning window.
Self tuning	The "Self tuning during initial start" or "Self tuning at the operating point" operating mode executes when the function is called in the commissioning window.
Automatic mode	In auto mode, the PID_Compact instruction corrects the control loop in accordance with specified parameters.
Manual mode	The manipulated variable can be set manually if the PID controller is operated in manual mode.

Motion control instructions: The motion control instructions use an associated technology data block and the dedicated PTO (pulse train outputs) of the CPU to control the motion on an axis. For information about the operation of the motion control instructions, see the online information system of STEP 7 Basic.



MC_Power enables and disables a motion control axis.



MC_Reset resets all motion control errors. All motion control errors that can be acknowledged are acknowledged.



MC_Home establishes the relationship between the axis control program and the axis mechanical positioning system.



MC_Halt cancels all motion processes and causes the axis motion to stop. The stop position is not defined.



MC_MoveJog executes jog mode for testing and startup purposes.



MC_MoveAbsolute starts motion to an absolute position. The job ends when the target position is reached.

MC_MoveRelative starts a positioning motion relative to the start position.

MC_MoveVelocity causes the axis to travel with the specified speed.

5.4 Other features to make programming easy

5.4.1 System memory and clock memory provide standard functionality

You use the CPU properties to enable bytes for "system memory" and "clock memory". Your program logic can reference the individual bits of these functions.

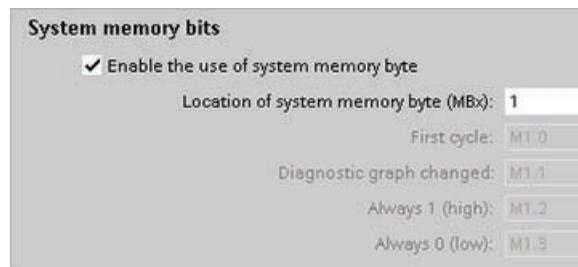
- You can assign one byte in M memory for system memory. The byte of system memory provides the following four bits that can be referenced by your user program:
 - "Always off" bit is always set to 0.
 - "Always on" bit is always set to 1.
 - "Diagnostic graph changed" is set to 1 for one scan after the CPU logs a diagnostic event.

The CPU does not set the "Diagnostic graph changed" bit until the end of the first execution of the of the program cycle OBs. Your user program cannot detect if there has been a diagnostic change either during the execution of the startup OBs or the first execution of the program cycle OBs.

 - "First scan" bit is set to 1 for the duration of the first scan after the startup OB finishes. (After the execution of the first scan, the "first scan" bit is set to 0.)
- You can assign one byte in M memory for clock memory. Each bit of the byte configured as clock memory generates a square wave pulse. The byte of clock memory provides 8 different frequencies, from 0.5 Hz (slow) to 10 Hz (fast). You can use these bits as control bits, especially when combined with edge instructions, to trigger actions in the user program on a cyclic basis.

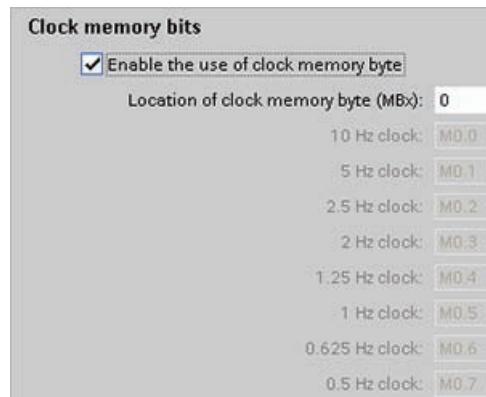
The CPU initializes these bytes on the transition from STOP mode to STARTUP mode, and the bits of the clock memory change synchronously to the CPU clock throughout STARTUP and RUN modes.

Because both the clock memory and system memory are unreserved M memory, instructions or communications can write to these locations and corrupt the data. Overwriting the system memory or clock memory bytes can corrupt the data in these functions and cause your user program to operate incorrectly. Always configure the system memory and clock memory for a memory address that is not accessed by other elements of your user program.



The system memory byte turns bits on (value = 1) for the following conditions:

- First scan: Turns on for the first scan cycle after a power cycle
- Diagnostic graph changed.
- Always 1 (high): Always turned on
- Always 0 (low): Always turned off



The clock memory byte cycles the individual bits on and off at fixed intervals.

The clock flags each generate a square wave pulse on the corresponding M memory bit. These bits can be used as control bits, especially when combined with edge instructions, to trigger actions in the user code on a cyclic basis.

Note

Consider assigning a PLC tag name to the bits of the system memory or clock memory. The tag name can describe the functionality of the bit for easy reference, and you can easily enter the tag name in your user program.

5.4.2 Watch tables make monitoring the user program easy

You use "watch tables" for monitoring and modifying the values of a user program being executed by the online CPU. You can create and save different watch tables in your project to support a variety of test environments. This allows you to reproduce tests during commissioning or for service and maintenance purposes.

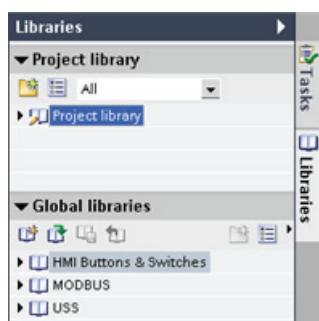
	Name	Address	Display format	Monitor value	Monitor with trigger	Modify with trigger
1	"Start"	%IO.0	Bool		Permanent	Permanent
2	"Stop"	%IO.1	Bool		Permanent	Permanent
3	"Running"	%IO.2	Bool		Permanent	Permanent
4	"Del"	%IO.3	Bool		Permanent	Permanent

With a watch table, you can monitor and interact with the CPU as it executes the user program. You can display or change values not only for the tags of the code blocks and data blocks, but also for the memory areas of the CPU, including the inputs and outputs (I and Q), peripheral inputs, bit memory (M), and DBs (Page 33). With a watch table, you can enable the peripheral outputs (such as "Stop:P" or "Q3.4:P") of a CPU in STOP mode. For example, you can assign specific values to the outputs when testing the wiring for the CPU.

A watch table also allows you to "force" or set a tag to a specific value (Page 94). Forced values are applied once per scan. They can be changed during program execution but for outputs, the forced values will be written at the end of the scan. To force an input or output (using ":P"), simply click the one of the "Force" buttons.

5.4.3 Project and global libraries for easy access

The global and project libraries allow you to reuse the stored objects throughout a project or across projects. For example, you can create block templates for use in different projects and adapt them to the particular requirements of your automation task. You can store a variety of objects in the libraries, such as FCs, FBs, DBs, device configuration, data types, watch tables, process screens, and faceplates. You can also save the components of the HMI devices in your project.



Each project has a project library for storing the objects to be used more than once within the project. This project library is part of the project. Opening or closing the project opens or closes the project library, and saving the project saves any changes in the project library.

You can create your own global library to store the objects you want to make available for other projects to use. When you create a new global library, you save this library to a location on your computer or network.

STEP 7 Basic provides several global libraries for use by any project.

Note

Saving the project does not save or update the global library. To save a global library that you added or modified, use the "Save the changes to the library" button in the tool bar of the global library.

5.4.4 Cross reference to show usage

The Inspector window displays cross-reference information about how a selected object is used throughout the complete project, such as the user program, the CPU and any HMI devices. The "Cross-reference" tab displays the instances where a selected object is being used and the other objects using it. The Inspector window also includes blocks which are only available online in the cross-references. To display the cross-references, select the "Show cross-references" command. (In the Project view, find the cross references in the "Tools" menu.)

Note

You do not have to close the editor to see the cross-reference information.

You can sort the entries in the cross-reference. The cross-reference list provides an overview of the use of memory addresses and tags within the user program.

- When creating and changing a program, you retain an overview of the operands, tags and block calls you have used.
- From the cross-references, you can jump directly to the point of use of operands and tags.
- During a program test or when troubleshooting, you are notified about which memory location is being processed by which command in which block, which tag is being used in which screen, and which block is called by which other block.

Column	Description
Object	Name of the object that uses the lower-level objects or that is being used by the lower-level objects
Quantity	Number of uses
Location	Each location of use, for example, network
Property	Special properties of referenced objects, for example, the tag names in multi-instance declarations
as	Shows additional information about the object, such as whether an instance DB is used as template or as a multiple instance
Access	Type of access, whether access to the operand is read access (R) and/or write access (W)
Address	Address of the operand
Type	Information on the type and language used to create the object
Path	Path of object in project tree

5.4.5 Call structure to examine the calling hierarchy

The call structure describes the call hierarchy of the block within your user program. It provides an overview of the blocks used, calls to other blocks, the relationships between blocks, the data requirements for each block, and the status of the blocks. You can open the program editor and edit blocks from the call structure.

Displaying the call structure provides you with a list of the blocks used in the user program. STEP 7 Basic highlights the first level of the call structure and displays any blocks that are not called by any other block in the program. The first level of the call structure displays the OBs and any FCs, FBs, and DBs that are not called by an OB. If a code block calls another block, the called block is shown as an indentation under the calling block. The call structure only displays those blocks that are called by a code block.

You can selectively display only the blocks causing conflicts within the call structure. The following conditions cause conflicts:

- Blocks that execute any calls with older or newer code time stamps
- Blocks that call a block with modified interface
- Blocks that use a tag with modified address and/or data type
- Block that are called neither directly nor indirectly by an OB
- Blocks that call a non-existent or missing block

You can group several block calls and data blocks as a group. You use a drop-down list to see the links to the various call locations.

You can also perform a consistency check to show time stamp conflicts. Changing the time stamp of a block during or after the program is generated can lead to time stamp conflicts, which in turn cause inconsistencies among the blocks that are calling and being called.

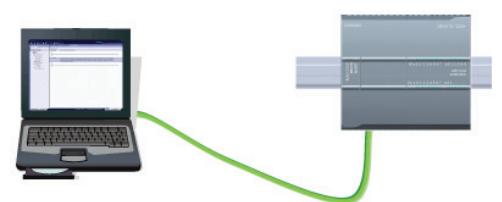
- Most time stamp and interface conflicts can be corrected by recompiling the code blocks.
- If compilation fails to clear up inconsistencies, use the link in the "Details" column to go to the source of the problem in the program editor. You can then manually eliminate any inconsistencies.
- Any blocks marked in red must be recompiled.

6

Easy to communicate between devices

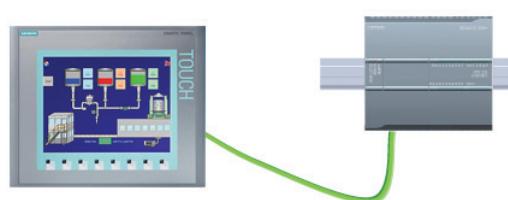
The integrated PROFINET port of the CPU supports both Ethernet and TCP/IP-based communications standards in order to communicate with the following devices:

- Programming device with STEP 7 Basic
- HMI devices
- Other CPUs or non-Siemens devices using standard TCP communications protocols transmission block (T-block) instructions



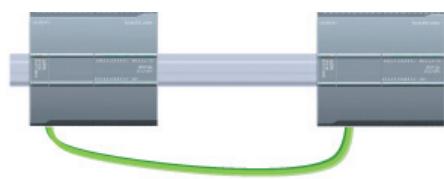
For a direct connection between the programming device and a CPU :

- The project must include the CPU.
- The programming device is not part of the project, but must be running STEP 7 Basic.



For a direct connection between an HMI panel and a CPU:

- The project must include both the CPU and the HMI.



For a direct connection between two CPUs:

- The project must include both CPUs.
- You must configure a network connection between the two CPUs.

For a network with more than two devices connected together:

- The project must include the devices (CPU and HMI). Do not include the router in the configuration.
- You must configure the network connections between the devices.



6.1 PROFINET instructions (T-blocks)

The CPU uses the Transport Connection Protocol (TCP) and the ISO Transport over TCP (RFC 1006) application protocols. When configuring a connection with a CPU for ISO-over-TCP, use only ASCII characters in the TSAP extension for the passive communication partners.

An Ethernet switch is not required for a direct connection between a programming device or HMI and a CPU. An Ethernet switch is required for a network with more than two CPUs or HMI devices.

Note

The PROFINET port on the CPU does not contain an Ethernet switching device. You can use a rack-mounted Siemens CSM1277 4-port Ethernet switch[®] to connect your CPUs and HMI devices.

6.1 PROFINET instructions (T-blocks)



TSEND_C establishes a TCP or ISO on TCP communication connection to a partner station, sends data, and can terminate the connection. After the connection is set up and established, it is automatically maintained and monitored by the CPU. TSEND_C combines the functions of TCON, TDISCON and TSEND.

Use the T-block instructions only in a program cycle OB (such as OB 1).

- To establish a connection, execute TSEND_C with CONT = 1. After successful establishing of the connection, set the DONE parameter for one cycle.
- To terminate the communication connection, execute TSEND_C with CONT = 0. The connection will be aborted immediately. This also affects the receiving station. The connection will be closed there and data inside the receive buffer could be lost.
- To send data over an established connection, execute TSEND_C with a rising edge on REQ. After a successful send operation, TSEND_C sets the DONE parameter for one cycle.
- To establish a connection and send data, execute TSEND_C with CONT =1 and REQ = 1. After a successful send operation, TSEND_C sets the DONE parameter for one cycle.

Note

Due to the asynchronous processing of TSEND_C, you must keep the data in the sender area consistent until the DONE parameter or the ERROR parameter assumes the values TRUE. For TSEND_C, a TRUE state at the parameter DONE means that the data was sent successfully. It does not mean that the connection partner CPU actually read the receive buffer. Due to the asynchronous processing of TRCV_C, the data in the receiver area are only consistent when parameter DONE = 1.



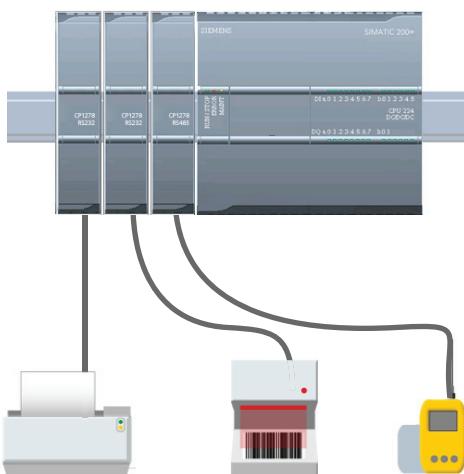
TRCV_C establishes a TCP or ISO-on-TCP communication connection to a partner CPU, receives data, and can terminate the connection. After the connection is set up and established, it is automatically maintained and monitored by the CPU. The TRCV_C instruction combines the functions of the TCON, TDISCON, and TRCV instructions.

- To establish a connection, execute TRCV_C with parameter CONT = 1.
- To receive data, execute TRCV_C with parameter EN_R = 1. Receive data continuously when parameters EN_R = 1 and CONT = 1.
- To terminate the connection, execute TRCV_C with parameter CONT = 0. The connection will be aborted immediately and data could be lost.

Note

The processing of the TSEND_C and TRCV_C instructions can take an undetermined amount of time. To ensure that these instructions are processed in every scan cycle, always call them from within the main program cycle scan, such as from a program cycle OB or from a code block that is called from the program cycle scan. Do **not** call these instructions from a hardware interrupt OB, a time-delay interrupt OB, a cyclic interrupt OB, an error interrupt OB, or a startup OB.

6.2 PtP, USS, and Modbus communication protocols

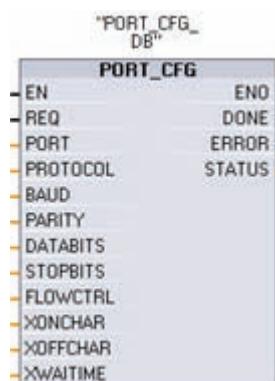


The CPU supports the PtP protocol for character-based serial communication, in which the user application completely defines and implements the protocol of choice. PtP enables a wide variety of possibilities:

- Sending information directly to an external device such as a printer
- Receiving information from devices such as barcode readers, RFID readers, third-party camera or vision systems, and many other types of devices
- Sending and receiving data with devices such as GPS devices, third-party camera or vision systems, or radio modems

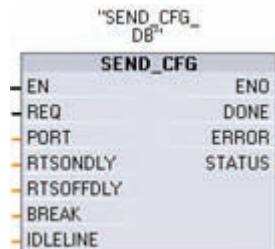
PtP is serial communication that supports a variety of baud rates and parity options. STEP 7 Basic provides libraries of instructions that you can use in programming your application. These libraries provide PtP communication functions for the USS drive protocol (RS485 only) and Modbus RTU Master and RTU Slave protocols.

6.2.1 PtP instructions

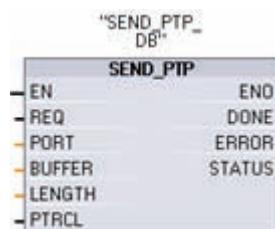


The PORT_CFG, SEND_CFG, and RCV_CFG instructions allow you to change the configuration from your user program.

- PORT_CFG changes the port parameters such as baud rate.
- SEND_CFG changes the configuration of serial transmission parameters.
- RCV_CFG changes the configuration of serial receiver parameters in a communication port. This instruction configures the conditions that signal the start and end of a received message. Messages that satisfy these conditions will be received by the RCV_PTP instruction.



The dynamic configuration changes are not permanently stored in the CPU. After a power cycle, the initial static configuration from the device configuration will be used.



The SEND_PTP, RCV_PTP, and RCV_RST instructions control the PtP communication:

- SEND_PTP transfers the specified buffer to the CM module. The CPU continues to execute the user program while the module sends the data at the specified baud rate.
- RCV_PTP checks for messages that have been received in the CM module. If a message is available, it will be transferred from the CM to the CPU.
- The RCV_RST resets the receive buffer.

Each CM module can buffer up to a maximum of 1K bytes. This buffer can be allocated across multiple received messages.

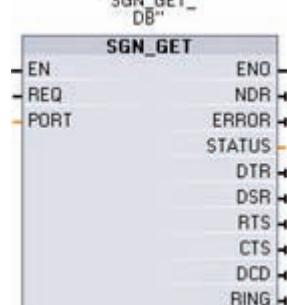


"SGN_SET_DB"



The SGN_SET and SGN_GET are valid only for the RS232 CM module. Use these instructions to read or set the RS232 communication signals.

"SGN_GET_DB"

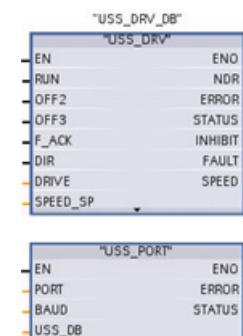


6.2.2 Library of USS instructions

The USS library supports the USS protocol and provides the functions that are specifically designed for communicating with drives over the RS485 port of a CM module. You can control the physical drive and the read/write drive parameters with the USS library. Each RS485 CM supports a maximum of 16 drives.

- The USS_PORT instruction handles actual communication between the CPU and all the drives attached to one CM. Insert a different USS_PORT instruction for each CM in your application. Ensure that the user program executes the USS_PORT instruction fast enough to prevent a communication timeout by the drive. Use the USS_PORT instruction in the program cycle or any interrupt OB.
- The USS_DRV instruction accesses a specified drive on the USS network. The input and output parameters of the USS_DRV instruction are the status and controls for the drive. If there are 16 drives on the network, your program must have at least 16 USS_DRV instructions, with one instruction for each drive. Ensure that the CPU executes the USS_DRV instruction at the rate that is required to control the functions of the drive. Use the USS_DRV instruction only in the program cycle OB.
- The USS_RPM and USS_WPM instructions read and write the operating parameters of the remote drive. These parameters control the internal operation of the drive. See the drive manual for the definition of these parameters. Your program can contain as many of these instructions as necessary. However, only one read or write request can be active for any one drive at any given time. Use the USS_RPM and USS_WPM instructions only in a program cycle OB.

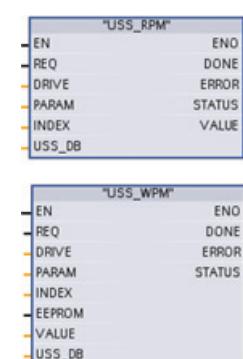
An instance DB contains temporary storage and buffers for all of the drives on the USS network connected to each CM module. The USS instructions for a drive use the instance DB to share the information.



The USS_DRV instruction exchanges data with the drive, by creating request messages and interpreting the drive response messages. All of the USS instructions associated with one USS network and CM must use the same instance DB.
Use a separate USS_DRV instruction for each drive.

The USS_PORT instruction handles communication over the USS network. Typically, there is only one USS_PORT instruction for each CM, and the USS_PORT instruction handles the transmission to or from a single drive.

Execute the USS_PORT from a time-delay interrupt OB to prevent drive timeouts and keep the most recent USS data updates available for USS_DRV calls.



The USS_RPM instruction reads a parameter from the drive.
Execute the USS_RPM from the program cycle OB.

The USS_WPM instruction modifies a parameter in the drive.
Execute the USS_WPM from the program cycle OB.
The "EEPROM" parameter controls the writing of the data to the EEPROM. To extend the service life of your EEPROM, Use the "EEPROM" parameter to minimize the number of EEPROM write operations.

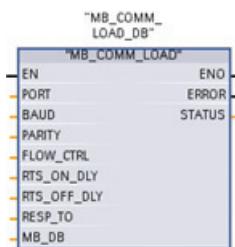
Calculating the time required for communicating with the drive

Communications with the drive are asynchronous to the CPU scan. The CPU typically completes several scans before one drive communications transaction is completed.

The USS_PORT interval is the time required for one drive transaction. The following table shows the minimum USS_PORT interval for each baud rate. Calling the USS_PORT function more frequently than the USS_PORT interval will not increase the number of transactions. The drive timeout interval is the amount of time that might be taken for a transaction, if communications errors caused 3 tries to complete the transaction. By default, the USS protocol library automatically does up to 2 retries on each transaction.

Baud rate	Calculated minimum USS_PORT call Interval (milliseconds)
1200	790
2400	405
4800	212.5
9600	116.3
19200	68.2
38400	44.1
57600	36.1
115200	28.1

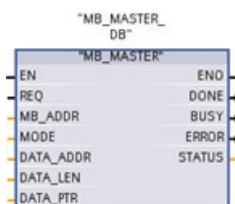
6.2.3 Library of Modbus instructions



The MB_COMM_LOAD instruction configures a port on the CM module for Modbus RTU protocol communications.

You can use either the RS232 or the RS485 CM module.

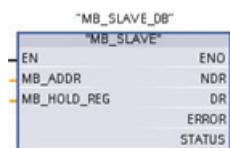
Your user program must execute the MB_COMM_LOAD to configure a port before either a MB_SLAVE or a MB_MASTER instruction can communicate with that port.



The MB_MASTER instruction allows your user program to communicate as a Modbus master. You can access data in one or more Modbus slave devices.

Inserting the MB_MASTER instruction creates an instance data block. Use this DB name as the MB_DB parameter on the MB_COMM_LOAD instruction.

Execute all MB_MASTER instructions for a given port from the same OB (or OB priority level).



The MB_SLAVE instruction allows your user program to communicate as a Modbus slave. A Modbus RTU master can issue a request and then your program responds via MB_SLAVE execution.

Inserting the MB_SLAVE instruction creates an instance data block. Use this DB name as the MB_DB parameter on the MB_COMM_LOAD instruction.

Execute all MB_SLAVE instructions from a cyclic interrupt OB.

The Modbus instructions do not use communication interrupt events to control the communication process. Your program must poll the MB_MASTER or MB_SLAVE instructions for transmit and receive complete conditions.

If a port is to respond as a slave to a Modbus master, then that port cannot be used by MB_MASTER. Only one instance of MB_SLAVE execution can be used with a given port. Likewise, If a port is to be used to initiate Modbus master requests, that port cannot be used by MB_SLAVE . One or more instances of MB_MASTER execution can be used with that port.

If your program operates a Modbus slave, then MB_SLAVE must poll (execute periodically) at a rate that allows it to make a timely response to incoming requests from a Modbus master.

If your program operates a Modbus master and uses MB_MASTER to send a request to a slave, then you must continue to poll (execute MB_MASTER) until the response from the slave is returned.

Easy to use the built-in pulse generators



You can configure the outputs of the CPU or signal board (SB) to function as a pulse generator or pulse-train output (PTO). The pulse-width modulation (PWM) instruction and the basic motion instructions use these outputs.

For information about the basic motion instructions, refer to the online help of STEP 7 Basic.

Note

Pulse-train outputs cannot be used by other instructions in the user program.

When you configure the outputs of the CPU or SB as pulse generators (for use with the PWM or basic motion control instructions), the corresponding output addresses (Q0.0, Q0.1, Q4.0, and Q4.1) are removed from the Q memory and cannot be used for other purposes in your user program. If your user program writes a value to an output used as a pulse generator, the CPU does not write that value to the physical output.

NOTICE
Do not exceed the maximum pulse frequency.
As described in the S7-1200 System Manual, the maximum pulse frequency of the pulse output generators is 100 KHz for the digital outputs of the CPU and 20 KHz for the digital outputs of the signal board.
When configuring the basic motion instructions, be aware that STEP 7 Basic does not alert you if you configure an axis with a maximum speed or frequency that exceeds this hardware limitation. This could cause problems with your application, so always ensure that you do not exceed the maximum pulse frequency of the hardware.

7.1 High-speed counters

A high-speed counter (HSC) can be used as an input for an incremental shaft encoder. The shaft encoder provides a specified number of counts per revolution and a reset pulse that occurs once per revolution. The clock(s) and the reset pulse from the shaft encoder provide the inputs to the HSC.

The HSC is loaded with the first of several presets, and the outputs are activated for the time period where the current count is less than the current preset. The HSC provides an interrupt when the current count is equal to preset, when reset occurs, and also when there is a direction change.

As each current-count-value-equals-preset-value interrupt event occurs, a new preset is loaded and the next state for the outputs is set. When the reset interrupt event occurs, the first preset and the first output states are set, and the cycle is repeated.

Since the interrupts occur at a much lower rate than the counting rate of the HSC, precise control of high-speed operations can be implemented with relatively minor impact to the scan cycle of the CPU. The method of interrupt attachment allows each load of a new preset to be performed in a separate interrupt routine for easy state control. (Alternatively, all interrupt events can be processed in a single interrupt routine.)

Selecting the functionality for the HSC

All HSCs function the same way for the same counter mode of operation. There are four basic types of HSC: single-phase counter with internal direction control, single-phase counter with external direction control, two-phase counter with 2 clock inputs, and A/B phase quadrature counter. Note that every mode is not supported by every HSC. You can use each HSC type with or without a reset input. When you activate the reset input, it clears the current value and holds it clear until you deactivate reset.

Frequency function: Some HSC modes allow the HSC to be configured (type of counting) to report the frequency instead of a current count of pulses. Three different frequency measuring periods are available: 0.01, 0.1, or 1.0 seconds.

The frequency measuring period determines how often the HSC calculates and reports a new frequency value. The reported frequency is an average value determined by the total number of counts in the last measuring period. If the frequency is rapidly changing, the reported value will be an intermediate between the highest and lowest frequency occurring during the measuring period. The frequency is always reported in Hertz (pulses per second), regardless of the frequency-measuring-period setting.

Counter modes and inputs: The following table shows the inputs used for the clock, direction control, and reset functions associated with the HSC. The same input cannot be used for two different functions, but any input not being used by the present mode of its HSC can be used for another purpose.

For example, if HSC1 is in a mode that uses built-in inputs but does not use the external reset (I0.3), then I0.3 can be used for edge interrupts or for HSC2.

Description			Default Input Assignment			Function
HSC	HSC1	Built In or Signal Board or monitor PTO 0 ¹	I0.0 I4.0 PTO 0 Pulse	I0.1 I4.1 PTO 0 Direction	I0.3 I4.3 -	
	HSC2	Built In or signal board or monitor PTO 1 ¹	I0.2 I4.2 PTO 1 Pulse	I0.3 I4.3 PTO 1 Direction	I0.1 I4.1 -	
	HSC3 ²	Built In	I0.4	I0.5	I0.7	
	HSC4 ³	Built In	I0.6	I0.7	I0.5	
	HSC5 ⁴	Built In or Signal Board	I1.0 I4.0	I1.1 I4.1	I1.2 I4.3	
	HSC6 ⁴	Built In or signal board	I1.3 I4.2	I1.4 I4.3	I1.5 I4.1	
Mode	Single-phase counter with internal direction control		Clock	-	-	Count or frequency
					Reset	Count
	Single-phase counter with external direction control		Clock	Direction	-	Count or frequency
					Reset	Count
	Two-phase counter with 2 clock inputs		Clock up	Clock down	-	Count or frequency
					Reset	Count
	A/B-phase quadrature counter		Phase A	Phase B	-	Count or frequency
					Phase Z	Count
	Monitor pulse train outputs (PTO) ¹		Clock	Direction	-	Count

- ¹ Pulse train output monitoring always uses clock and direction. If the corresponding PTO output is configured for pulse only, then the direction output should generally be set for positive counting.
- ² HSC3 with a reset input is not possible for the CPU 1211C which supports only 6 built-in inputs.
- ³ HSC4 is not possible for the CPU 1211C which supports only 6 built-in inputs.
- ⁴ HSC5 and HSC6 are only supported by the CPU 1211C and CPU 1212C when a signal board is installed.

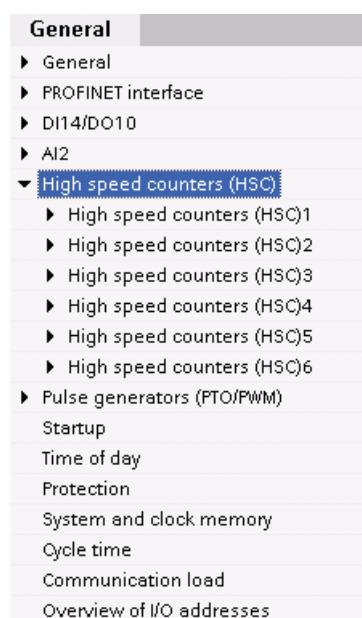
Accessing the current value for the HSC

The CPU stores the current value of each HSC in an input (I) address. The following table shows the default addresses assigned to the current value for each HSC. You can change the input address for the current value by modifying the properties of the CPU (Page 46).

High-speed counter	Data type	Default address
HSC1	DInt	ID1000
HSC2	DInt	ID1004
HSC3	DInt	ID1008
HSC4	DInt	ID1012
HSC5	DInt	ID1016
HSC6	DInt	ID1020

7.1 High-speed counters

Configuration of the HSC



The CPU allows you to configure up to 6 high-speed counters. You edit the "Properties" of the CPU to configure the parameters of each individual HSC.

Configure the parameters for the high-speed counters by editing the "Properties" of the CPU, such as counter function, initial values, reset options and interrupt events.

After configuring the HSC, use the CTRL_HSC instruction in your user program to control the operation of the HSC.

Using the CTRL_HSC instruction



The CTRL_HSC instruction controls the high-speed counters for counting events that occur faster than the CPU scan rate.

Each CTRL_HSC instruction stores the data in an instance DB. Inserting the CTRL_HSC instruction into your user program creates this instance DB.

Parameter	Data type	Description
HSC	HW_HSC	HSC identifier
DIR	BOOL	1 = Request new direction
CV	BOOL	1 = Request to set new counter value
RV	BOOL	1= Request to set new reference value
PERIOD	BOOL	1 = Request to set new period value (only for frequency measurement mode)
NEW_DIR	INT	New direction: 1= forward, -1= backward
NEW_CV	DINT	New counter value
NEW_RV	DINT	New reference value

Parameter	Data type	Description
NEW_PERIOD	INT	New period value in seconds: .01, .1, or 1 (only for frequency measurement mode)
BUSY	BOOL	Function busy
STATUS	WORD	Execution condition code

While the counting rate of the CTU, CTD, and CTUD counter instructions is limited by the CPU scan rate, the HSC operates asynchronously to the CPU scan and allow counting events up to a 100 kHz count rate (for HSC 1, 2, or 3 and onboard CPU count input configuration).

You must configure the high-speed counters in the project settings for the CPU device configuration before you can use high-speed counters in your program. The HSC device configuration settings select counting modes, I/O connections, interrupt assignment, and operation as a high-speed counter or as a device to measure pulse frequency. You can operate the high-speed counter with no program control or with program control.

Many high-speed counter configuration parameters are set only in the project device configuration. Some high-speed counter parameters are initialized in the project device configuration, but can be modified later under program control. The CTRL_HSC instruction parameters provide program control of the counting process:

- Set the counting direction to a NEW_DIR value
- Set the current count value to a NEW_CV value
- Set the reference value to a NEW_RV value
- Set the Period value (for frequency measurement mode) to a NEW_PERIOD value

If the following boolean flag values are set to 1 when the CTRL_HSC instruction is executed, the corresponding NEW_xxx value is loaded to the counter. Multiple requests (more than one flag is set at the same time) are processed in a single execution of the CTRL_HSC instruction.

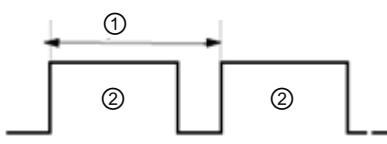
- DIR = 1 is a request to load a NEW_DIR value, 0 = no change
- CV = 1 is a request to load a NEW_CV value, 0 = no change
- RV = 1 is a request to load a NEW_RV value, 0 = no change
- PERIOD = 1 is a request to load a NEW_PERIOD value, 0 = no change

The CTRL_HSC instruction is usually placed in a hardware interrupt OB that is executed when the counter hardware interrupt event is triggered. For example, if a CV=RV event triggers the counter interrupt, then a hardware interrupt OB code block can execute a CTRL_HSC instruction to change the reference value by loading a NEW_RV value.

The current count value is not available in the CTRL_HSC parameters. The Process Image address that stores the current count value is assigned during the high-speed counter hardware configuration. You may use program logic to directly read the count value and the value returned to your program will be a correct count for the instant in which the counter was read, but the counter will continue to count high-speed events. The actual count value could change before your program completes a process using an old count value.

7.2 Pulse-width modulation (PWM)

Two pulse generators are available for controlling high-speed pulse output functions: Pulse Width Modulation (PWM) and Pulse train output (PTO). Since the PWM output can be varied from 0 to full scale, it provides a digital output that in many ways is the same as an analog output. For example, the PWM output can be used to control the speed of a motor from stop to full speed, or it can be used to control position of a valve from closed to fully opened. PTO is used by the motion control instructions.



Duty cycle can be expressed, for example, as a percentage of the cycle time or as a relative quantity (such as 0 to 1000 or 0 to 10000). The pulse width can vary from 0 (no pulse, always off) to full scale (no pulse, always on).

- ① Cycle time
- ② Pulse width time

The CTRL_PWM instruction provides a fixed cycle time output with a variable duty cycle. The PWM output runs continuously after being started at the specified frequency (cycle time). The pulse width is varied as required to affect the control.

You can assign each pulse generator to either PWM or PTO, but not both at the same time.

Configuring the pulse generators

The two pulse generators are mapped to specific digital outputs as shown in the following table. You can use onboard CPU outputs, or you can use the optional signal board outputs. The output point numbers are shown in the following table (assuming the default output configuration). If you have changed the output point numbering, then the output point numbers will be those you assigned. Regardless, PTO1/PWM1 uses the first two digital outputs, and PTO2/PWM2 uses the next two digital outputs, either on the CPU or on the attached signal board. Note that PWM requires only one output, while PTO can optionally use two outputs per channel. If an output is not required for a pulse function, it is available for other uses.

Description	Default output assignment	Pulse	Direction
PTO 1	Onboard CPU	Q0.0	Q0.1
	Signal board	Q4.0	Q4.1
PWM 1	Onboard CPU	Q0.0	--
	Signal board	Q4.0	--
PTO 2	Onboard CPU	Q0.2	Q0.3
	Signal board	Q4.2	Q4.3
PWM 2	Onboard CPU	Q0.2	--
	Signal board	Q4.2	--

To prepare for PWM operation, first configure a pulse channel in the device configuration by selecting the CPU, then "Pulse Generator (PTO/PWM)", and choose either "PWM1" or "PWM2". Enable the pulse generator (check box). If a pulse generator is enabled, a unique default name is assigned to this particular pulse generator. You can change this name by editing it in the "Name:" edit box, but it must be a unique name. Names of enabled pulse generators will become tags in the "constant" tag table, and will be available for use as the PWM parameter of the CTRL_PWM instruction. You have the option to rename the pulse generator, add a comment, and assign parameters as follows:

- Pulse generator used as follows: PWM or PTO (choose PWM)
- Output source: onboard CPU or Signal Board
- Time base: milliseconds or microseconds
- Pulse width format:
 - Percent (0 to 100)
 - Thousandths (0 to 1000)
 - Ten-thousandths (0 to 10000)
- Cycle time: Enter your cycle time value. This value can only be changed here.
- Initial pulse width: Enter your initial pulse width value. The pulse width value can be changed during runtime.
- Start address: Enter the word-length address of the output (Q) where you want to locate the pulse width value. The default location is QW1000 for PWM1, and QW1002 for PWM2. The value at this location controls the width of the pulse and is initialized to the "Initial pulse width:" value specified above each time the PLC transitions from STOP to RUN mode. You change this Q-word value during run time to cause a change in the pulse width.

Using the CTRL_PWM instruction



When placing a CTRL_PWM instruction into the program editor, a DB will be assigned. A data block (DB) is used by the CTRL_PWM instruction to store parameter information. The data block parameters are controlled by the CTRL_PWM instruction.

Parameter	Data type	Description
PWM	WORD	PWM identifier: Names of enabled pulse generators will become tags in the "constant" tag table, and will be available for use as the PWM parameter.
ENABLE	BOOL	1=start pulse generator 0 = stop pulse generator
BUSY	BOOL	Function busy
STATUS	WORD	Execution condition code

7.2 Pulse-width modulation (PWM)

Use the tag name for the PWM parameter to specify the enabled pulse generator.

When the EN input is TRUE, the PWM_CTRL instruction starts or stops the identified PWM based on the value at the ENABLE input. Pulse width is specified by the value in the associated Q word output address. Because the CPU processes the request when the CTRL_PWM instruction is executed, parameter BUSY will always report FALSE on S7-1200 CPU models.

The pulse width will be set to the initial value configured in device configuration when the PLC first enters the RUN mode. You write values to the word-length output (Q) address that was specified in device configuration ("Output addresses" / "Start address:") as needed to change the pulse width. Use an instruction, such as Move, Convert, Math, or PID, to write the specified pulse width to the appropriate word-length output (Q). You must use the valid range for the output value (percent, thousandths, ten-thousandths, or S7 analog format).

Easy to use the online tools

8.1 Going online and connecting to a CPU

The online connection provides you with additional capabilities:

- Using the CPU operator panel to change the operating mode of the CPU (Page 89)
- Uploading, comparing, and synchronizing the code blocks of the user program (Page 90)
- Using a watch table (Page 93) to test the user program and to force (Page 94) values in the CPU
- Using the diagnostic buffer (Page 92) to display the events

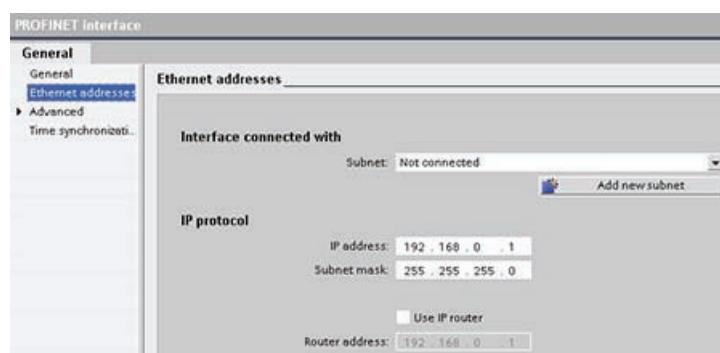


To load your project (including the user program, device configuration, and IP address), create an online connection to a CPU. Use the "Online access" folder to connect to an online CPU:

1. Open the "Online access" folder and select the online connection for your CPU.
2. Double-click "Update accessible devices" to display the online CPU.

Use the "Online tools" task card to access the data on online CPU.

8.2 Downloading an IP address to an online CPU



To assign an IP address, you must perform the following tasks:

- Configure the IP address for the CPU (Page 48)
- Save and download the configuration to the CPU.

The IP address and subnet mask for the CPU must be compatible with the IP address and subnet mask of the programming device. Consult your network specialist for the IP address and subnet mask for your CPU.

8.2 Downloading an IP address to an online CPU



If the CPU has not been previously configured, you can also use "Online access" (Page 87) to set the IP address.

An IP address that has been downloaded as part of the device configuration will not be lost on a power cycle of the PLC.

After you have downloaded the device configuration with the IP address, you can see the IP address under the "Online access" folder.

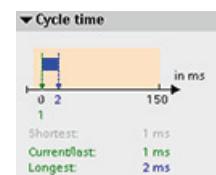
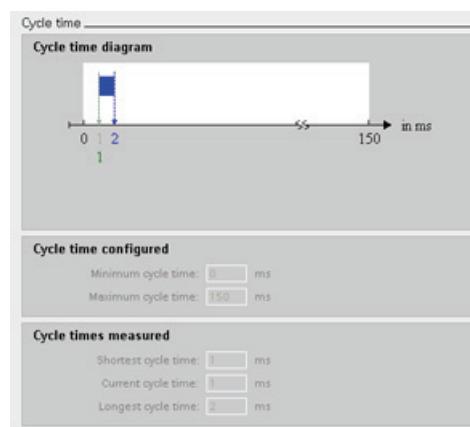
8.3 Interacting with the online CPU

The Online and Diagnostics portal provides an operator panel for changing the operating mode of the online CPU. The "Online tools" task card displays an operator panel that shows the operating mode of the online CPU. The operator panel also allows you to change the operating mode of the online CPU. Use the button on the operator panel to change the operating mode (STOP or RUN). The operator panel also provides an MRES button for resetting the memory.



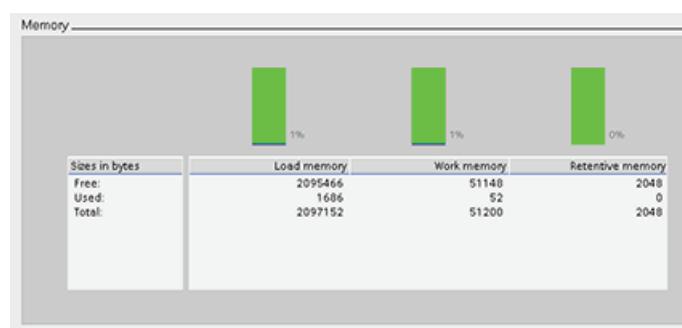
The color of the RUN/STOP indicator shows the current operating mode of the CPU: yellow indicates STOP mode, and green indicates RUN mode.

To use the operator panel, you must be connected online to the CPU. After you select the CPU in the device configuration or display a code block in the online CPU, you can display the operator panel from the "Online tools" task card.



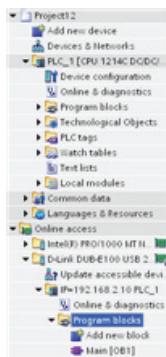
You can monitor the cycle time of an online CPU.

You can also view the memory usage of the CPU.



8.4 Uploading from the online CPU

STEP 7 provides two methods for uploading the code blocks of the user program from an online CPU.



Using the Project navigation, you can drag and drop the code blocks from the online CPU to a CPU in your off-line project.

1. With your project open, expand the "Online access" container and select an online CPU.
2. Expand the online CPU to display the code blocks of the user program.
3. Drag the "Program blocks" folder from the online CPU to the "Program blocks" container of the CPU in your offline project.

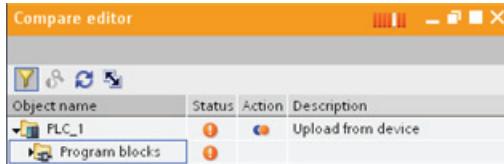
STEP 7 Basic copies the code blocks from the online CPU to your offline project.



You can also use the "Compare" function to synchronize the code blocks between the online CPU and the offline CPU:

1. Select the offline CPU.
2. Select the "Compare offline/online" command from the "Tools" menu.

If the code blocks of the offline do not match the code blocks of the online CPU, the "Compare" editor allows you to synchronize the two CPUs.



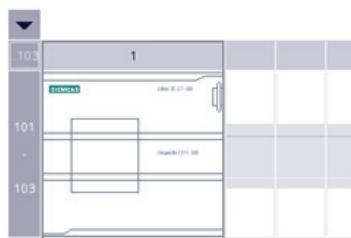
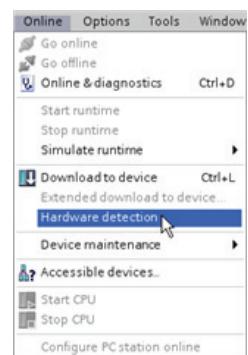
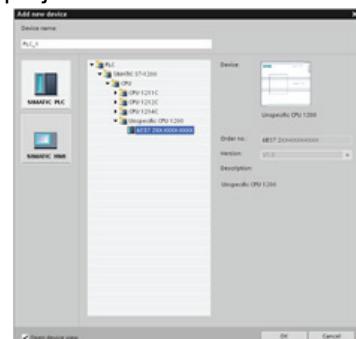
Click the "Action" icon to select whether to upload, download or take no action.

Click the "Synchronize" button to load the code blocks to or from the designated CPU.

Using the "unspecified CPU" to upload the hardware configuration

If you have a physical CPU that you can connect to the programming device, it is easy to upload the configuration of the hardware.

You must first connect the CPU to your programming device, and you must create a new project.



The device is not specified.
→ Please use the [hardware catalog](#) to specify the CPU,
→ or [detect](#) the configuration of the connected device.

After creating the unspecified CPU, you can upload the hardware configuration for the online CPU.

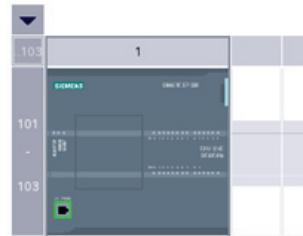
- From the program editor, you select the "Hardware detection" command from the "Online" menu.
- From the device configuration editor, you select the option for detecting the configuration of the connected device

Use either of the following options to insert an "unspecified CPU":

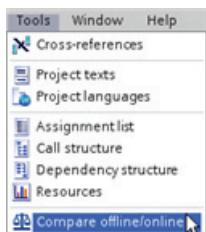
- In the device configuration (Project view or Portal view), add a new device, but select the "unspecified CPU" instead of selecting a specific CPU..
- In the Portal view, click the "Create a PLC program" from the "First steps".

STEP 7 Basic creates an unspecified CPU.

After you select the CPU from the online dialog, STEP 7 Basic uploads the hardware configuration from the CPU, including any modules (SM, SB, or CM). The IP address is **not** uploaded. You must go to "Device configuration" to manually configure the IP address.



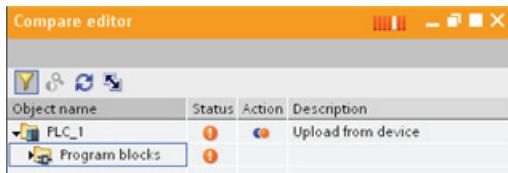
8.5 Comparing offline and online CPUs



You can compare the code blocks in an online CPU with the code blocks in your offline project:

1. Select the offline CPU.
2. Select the "Compare offline/online" command from the "Tools" menu.

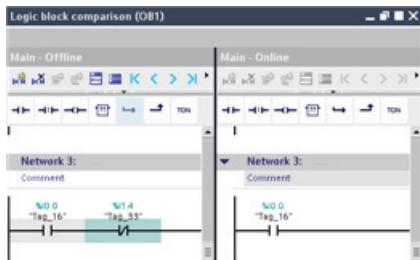
If the code blocks of the offline do not match the code blocks of the online CPU, the "Compare" editor allows you to synchronize the two CPU.



Click the "Action" icon to select whether to upload, download or take no action.



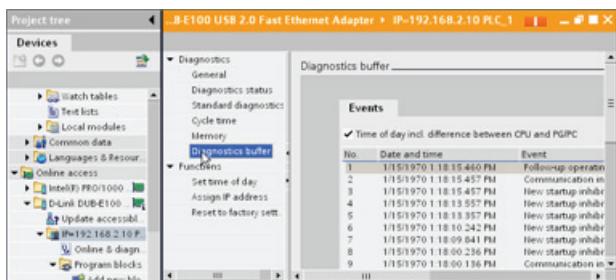
Click the "Synchronize" button loads the code blocks to the designated CPU.



Click the "detailed comparison" button to show the code blocks side-by-side. The detailed comparison highlights the differences between the code blocks of online and offline CPUs.



8.6 Displaying the diagnostic events



The CPU provides a diagnostic buffer which contains an entry for each diagnostic event, such as transition of the CPU operating mode or errors detected by the CPU or modules.

To access the diagnostic buffer, you must be online.

While the CPU maintains power, up to 50 most recent events are available in this log. When the log is full, a new event replaces the oldest event in the log. When power is lost, the ten most recent events are saved.

Each entry includes a date and time the event occurred, an event category, and an event description. The entries are displayed in chronological order with the most recent event at the top.

8.7 Using a watch table for monitoring the CPU

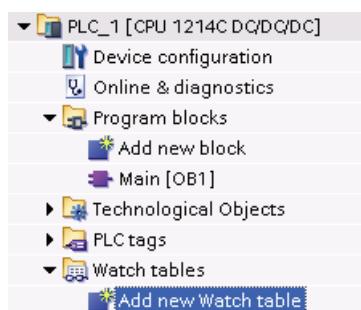
A watch table allows you to monitor or modify data points while the CPU executes your user program. These data points can be inputs (I), outputs (Q), peripheral inputs or outputs (such as "On:P", "I 3.4:P" or "Q3.4:P"), M memory, or a DB. The monitoring function does not change the program sequence. It presents you with information about the program sequence and the data of the program in the CPU. You can also use the "Modify" and "Force" functions to test the execution of your user program.

	Name	Address	Display format	Monitor value	Monitor with trigger	Modify with trigger
1	"Start"	%IO.0	Bool		Permanent	Permanent
2	"Stop"	%IO.1	Bool		Permanent	Permanent
3	"Running"	%IO.2	Bool		Permanent	Permanent
4	"Del"	%IO.3	Bool		Permanent	Permanent

Note

The digital I/O points used by the high-speed counter (HSC), pulse-width modulation (PWM), and pulse-train output (PTO) devices are assigned during device configuration. When digital I/O point addresses are assigned to these devices, the values of the assigned I/O point addresses cannot be modified by the "Force" function of the watch table.

With a watch table, you can monitor or modify the values of the individual tags. You can also force a tag to a specific value. You can specify to monitor or modify the tag at the beginning or the end of the scan cycle, when the CPU changes to STOP mode, or "permanently" (with the value not being reset after a STOP to RUN transition).



To create a watch table:

1. Double-click "Add new watch table" to open a new watch table.
2. Enter the tag name to add a tag to the watch table.

To monitor the tags, you must have an online connection to the CPU. The following options are available for modifying tags:

- "Modify now" immediately changes the value for the selected addresses for one scan cycle.
- "Modify with trigger" changes the values for the selected addresses. This function does not provide feedback to indicate that the selected addresses were actually modified. If feedback of the change is required, use the "Modify now" function.
- "Enable peripheral outputs" allows you to turn on the peripheral outputs when the CPU is in STOP mode. This feature is useful for testing the wiring of the output modules.

The various functions can be selected using the buttons at the top of a watch table. Enter the tag name to monitor and select a display format from the dropdown selection. With an online connection to the CPU, clicking the "Monitor" button displays the actual value of the data point in the "Monitor value" field.

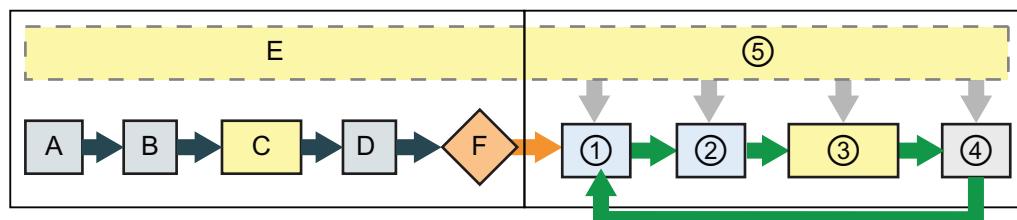
8.8 Forcing variables in the CPU

A watch table provides a "force" function that overwrites the value for an input or output point to a specified value for the peripheral input or peripheral output address. The CPU applies this forced value to the input process image prior to the execution of the user program and to the output process image before the outputs are written to the modules.

- Prior to the execution of the scan, the CPU overwrites the value of the peripheral input with the forced value. The user program uses the forced value in processing.
- At the end of the scan, the CPU overwrites the output values generated by the user program with any forced value specified for the peripheral outputs. The forced value appears at the physical output and is used by the process.

When an input or output is forced in a watch table, the force actions become part of the user program. If you close STEP 7 Basic, the forced elements remain active for the user program being executed by the CPU program until they are cleared. To clear these forced elements, you must use STEP 7 Basic to connect with the online CPU and use the watch table to turn off or stop the force function for those elements.

If the CPU is executing the user program from a write-protected memory card, you cannot initiate or change the forcing of I/O from a watch table because you cannot override the values in the write-protected user program. Any attempt to force the write-protected values generates an error. If you use a memory card to transfer a user program, any forced elements on that memory card will be transferred to the CPU.



Startup

- A The clearing of the I memory area is not affected by the Force function.
- B The initialization of the outputs values is not affected by the Force function.
- C During the execution of the startup OBs, the CPU applies the force value when the user program accesses the physical input.
- D After copying the state of the physical inputs to I memory, the CPU applies the force values.
- E The storing of interrupt events into the queue is not affected.
- F The enabling of the writing to the outputs is not affected.

RUN

- ① While writing Q memory to the physical outputs, the CPU applies the force value as the outputs are updated.
- ② After copying the state of the physical inputs to I memory, the CPU applies the force values.
- ③ During the execution of the user program (program cycle OBs), the CPU applies the force value when the user program accesses the physical input.
- ④ Self-test diagnostics are not affected by the Force function.
- ⑤ Handling of communication requests and the processing of interrupts during any part of the scan cycle is not affected.

Technical specifications

A.1 General specifications

The S7-1200 automation system complies with the following standards and test specifications. The test criteria for the S7-1200 automation system are based on these standards and test specifications.



The S7-1200 Automation System satisfies requirements and safety related objectives according to the EC directives listed below and conforms to the harmonized European standards (EN) for the programmable controllers listed in the Official Journals of the European Community.

- EC Directive 2006/95/EC (Low Voltage Directive) "Electrical Equipment Designed for Use within Certain Voltage Limits"
 - EN 61131-2:2007 Programmable controllers - Equipment requirements and tests
- EC Directive 2004/108/EC (EMC Directive) "Electromagnetic Compatibility"
 - Emission standard
EN 61000-6-4:2007: Industrial Environment
 - Immunity standard
EN 61000-6-2:2005: Industrial Environment
- EC Directive 94/9/EC (ATEX) "Equipment and Protective Systems Intended for Use in Potentially Explosive Atmosphere"
 - EN 60079-15:2005: Type of Protection 'n'

The CE Declaration of Conformity is held on file available to competent authorities at:

Siemens AG
 IA AS RD ST PLC Amberg
 Werner-von-Siemens-Str. 50
 D92224 Amberg
 Germany



Underwriters Laboratories Inc. complying with

- Underwriters Laboratories, Inc.: UL 508 Listed (Industrial Control Equipment)
- Canadian Standards Association: CSA C22.2 Number 142 (Process Control Equipment)

NOTICE

The SIMATIC S7-1200 series meets the CSA standard.

The cULus logo indicates that the S7-1200 has been examined and certified by Underwriters Laboratories (UL) to standards UL 508 and CSA 22.2 No. 142.

Technical specifications

A.1 General specifications



Factory Mutual Research (FM):
Approval Standard Class Number 3600 and 3611
Approved for use in:
Class I, Division 2, Gas Group A, B, C, D, Temperature Class T4A Ta = 40° C
Class I, Zone 2, IIC, Temperature Class T4 Ta = 40° C



EN 60079-0:2006: Explosive Atmospheres - General Requirements
EN 60079-15:2005: Electrical Apparatus for potentially explosive atmospheres;
Type of protection 'n'
II 3 G Ex nA II T4

The following special conditions for safe use of the S7-1200 must be followed:

- Install modules in a suitable enclosure providing a minimum degree of protection of IP54 according to EN 60529 and take into account the environmental conditions under which the equipment will be used.
- When the temperature under rated conditions exceeds 70° C at the cable entry point, or 80° C at the branching point of the conductors, the temperature specification of the selected cable should be in compliance with the actual measured temperature.
- Provisions should be made to prevent the rated voltage from being exceeded by transient disturbances of more than 40%.



The S7-1200 automation system satisfies requirements of standards to AS/NZS 2064 (Class A)

Maritime approval: The S7-1200 products are periodically submitted for special agency approvals related to specific markets and applications. Consult your local Siemens representative if you need additional information related to the latest listing of exact approvals by part number.

Classification societies:

- ABS (American Bureau of Shipping)
- BV (Bureau Veritas)
- DNV (Det Norske Veritas)
- GL (Germanischer Lloyd)
- LRS (Lloyds Register of Shipping)
- Class NK (Nippon Kaiji Kyokai)

Industrial environments: The S7-1200 automation system is designed for use in industrial environments.

Application Field	Noise Emission Requirements	Noise Immunity Requirements
Industrial	EN 61000-6-4:2007	EN 61000-6-2:2005

Electromagnetic compatibility: Electromagnetic Compatibility (EMC) is the ability of an electrical device to operate as intended in an electromagnetic environment and to operate without emitting levels of electromagnetic interference (EMI) that may disturb other electrical devices in the vicinity.

Electromagnetic Compatibility - Immunity per EN 61000-6-2	
EN 61000-4-2 Electrostatic discharge	8 kV air discharge to all surfaces 6 kV contact discharge to exposed conductive surfaces
EN 61000-4-3 Radiated electromagnetic field	80 to 100 MHz, 10 V/m, 80% AM at 1 kHz 1-4 to 2.0 GHz, 3 V/m, 80% AM a 1 kHz 2.0 to 2.7 GHz, 1 V/m, 80% AM at 1 kHz
EN 61000-4-4 Fast transient bursts	2 kV, 5 kHz with coupling network to AC and DC system power 2 kV, 5 kHz with coupling clamp to I/O
EN 61000-4-5 Surge immunity	AC systems - 2 kV common mode, 1kV differential mode DC systems - 2 kV common mode, 1kV differential mode For DC systems (I/O signals, DC power systems) external protection is required.
EN 61000-4-6 Conducted disturbances	150 kHz to 80 MHz, 10 V RMS, 80% AM at 1kHz
EN 61000-4-11 Voltage dips	AC systems 0% for 1 cycle, 40% for 12 cycles and 70% for 30 cycles at 60 Hz

Electromagnetic Compatibility - Conducted and Radiated Emissions per EN 61000-6-4	
Conducted Emissions EN 55011, Class A, Group 1 0.15 MHz to 0.5 MHz 0.5 MHz to 5 MHz 5 MHz to 30 MHz	<79dB (μ V) quasi-peak; <66 dB (μ V) average <73dB (μ V) quasi-peak; <60 dB (μ V) average <73dB (μ V) quasi-peak; <60 dB (μ V) average
Radiated Emissions EN 55011, Class A, Group 1 30 MHz to 230 MHz 230 MHz to 1 GHz	<40dB (μ V/m) quasi-peak; measured at 10m <47dB (μ V/m) quasi-peak; measured at 10m

Environmental conditions

Environmental Conditions - Transport and Storage	
EN 60068-2-2, Test Bb, Dry heat and EN 60068-2-1, Test Ab, Cold	-40° C to +70° C
EN 60068-2-30, Test Db, Damp heat	25° C to 55° C, 95% humidity
EN 60068-2-14, Test Na, temperature shock	-40° C to +70° C, dwell time 3 hours, 2 cycles
EN 60068-2-32, Free fall	0.3 m, 5 times, product packaging
Atmospheric pressure	1080 to 660h Pa (corresponding to an altitude of -1000 to 3500m)

Technical specifications

A.1 General specifications

Environmental Conditions - Operating	
Ambient temperature range (Inlet Air 25 mm below unit)	0° C to 55° C horizontal mounting 0° C to 45° C vertical mounting 95% non-condensing humidity
Atmospheric pressure	1080 to 795 hPa (Corresponding to an altitude of -1000 to 2000m)
Concentration of contaminants	SO ₂ : < 0.5 ppm; H ₂ S: < 0.1 ppm; RH < 60% non-condensing
EN 60068-2-14, Test Nb, temperature change	5° C to 55°, 3° C/minute
EN 60068-2-27 Mechanical shock	15 G, 11 ms pulse, 6 shocks in each of 3 axis
EN 60068-2-6 Sinusoidal vibration	DIN rail mount: 3.5mm from 5-9 Hz, 1G from 9 - 150 Hz Panel Mount: 7.00mm from 5-9 Hz, 2G from 9 to 150 Hz 10 sweeps each axis, 1 octave per minute

High Potential Isolation Test	
24 V/5 V nominal circuits	520 VDC (type test of optical isolation boundaries)
115/230 V circuits to ground	1,500 VAC routine test/1950 VDC type test
115/230 V circuits to 115/230 V circuits	1,500 VAC routine test/1950 VDC type test
115 V/230V circuits to 24 V/5 V circuits	1,500 VAC routine test/3250 VDC type test

Protection Class: Protection Class II according to EN 61131-2 (Protective conductor not required)

Degree of protection

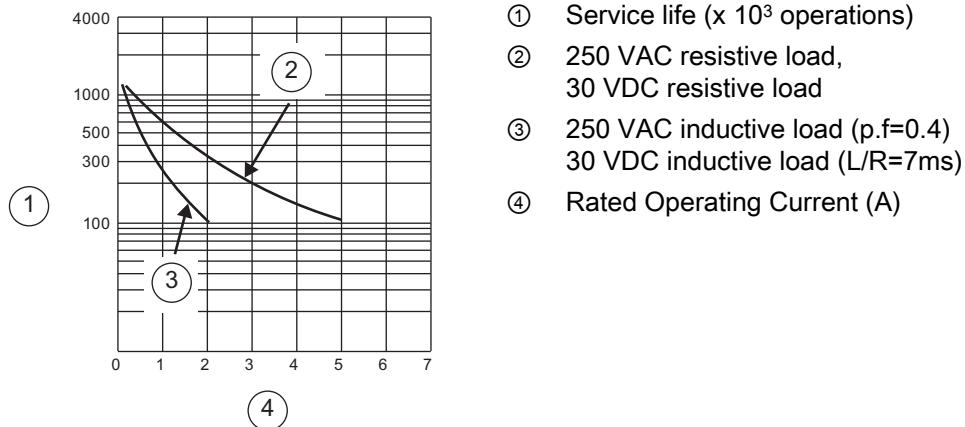
- IP20 Mechanical Protection, EN 60529
- Protects against finger contact with high voltage as tested by standard probe. External protection required for dust, dirt, water and foreign objects of < 12.5mm in diameter.

Rated voltages

Rated Voltage	Tolerance
24 VDC	20.4 VDC to 28.8 VDC
120/230 VAC	85 VAC to 264 VAC, 47 to 63 Hz

NOTICE
When a mechanical contact turns on output power to the S7-1200 CPU, or any digital signal module, it sends a "1" signal to the digital outputs for approximately 50 microseconds. You must plan for this, especially if you are using devices which respond to short duration pulses.

Relay electrical service life: The typical performance data supplied by relay vendors is shown below. Actual performance may vary depending upon your specific application. An external protection circuit that is adapted to the load will enhance the service life of the contacts.



A.2 CPU modules

For the complete set of technical specifications, see the S7-1200 system manual.

General specifications	CPU 1211C	CPU 1212C	CPU 1214C
Dimensions (W x H x D)	90 x 100 x 75 (mm)	90 x 100 x 75 (mm)	110 x 100 x 75 (mm)
Weight			
<ul style="list-style-type: none"> • AC/DC/relay • DC/DC/Relay • DC/DC/DC 	<ul style="list-style-type: none"> • 420 grams • 380 grams • 370 grams 	<ul style="list-style-type: none"> • 425 grams • 385 grams • 370 grams 	<ul style="list-style-type: none"> • 475 grams • 435 grams • 415 grams
Power dissipation			
<ul style="list-style-type: none"> • AC/DC/relay • DC/DC/Relay • DC/DC/DC 	<ul style="list-style-type: none"> • 10 W • 8 W • 8 W 	<ul style="list-style-type: none"> • 11 W • 9 W • 9 W 	<ul style="list-style-type: none"> • 14 W • 12 W • 12 W
Current available (5 VDC) for SM and CM bus	750 mA max.	1000 mA max.	1600 mA max.
Current available (24 VDC) sensor power	300 mA max.	300 mA max.	400 mA max.
Digital input current consumption (24VDC)	4 mA/input used	4 mA/input used	4 mA/input used

Technical specifications

A.2 CPU modules

CPU features	CPU 1211C	CPU 1212C	CPU 1214C
User memory			
<ul style="list-style-type: none"> • Work memory • Load memory • Retentive memory 	<ul style="list-style-type: none"> • 25 Kbytes • 1 Mbytes • 2 Kbytes 	<ul style="list-style-type: none"> • 25 Kbytes • 1 Mbytes • 2 Kbytes 	<ul style="list-style-type: none"> • 50 Kbytes • 2 Mbytes • 2 Kbytes
On-board digital I/O	6 inputs 4 outputs	8 inputs 6 outputs	14 inputs 10 outputs
On-board analog I/O	2 inputs	2 inputs	2 inputs
Process image size			
<ul style="list-style-type: none"> • Inputs • Outputs 	<ul style="list-style-type: none"> • 1024 bytes • 1024 bytes 	<ul style="list-style-type: none"> • 1024 bytes • 1024 bytes 	<ul style="list-style-type: none"> • 1024 bytes • 1024 bytes
Bit memory (M)	4096 bytes	4096 bytes	8192 bytes
SM modules expansion	None	2 SMs max.	8 SMs max.
SB expansion	1 SB max.	1 SB max.	1 SB max.
CM expansion	3 CMs max.	3 CMs max.	3 CMs max.
High-speed counters	3 total	4 total	6 total
<ul style="list-style-type: none"> • Single phase (clock rate) • Quadrature phase (clock rate) 	<ul style="list-style-type: none"> • 3 at 100 kHz • 3 at 80 kHz 	<ul style="list-style-type: none"> • 3 at 100 kHz and 1 at 30 kHz • 3 at 80 kHz and 1 at 20 kHz 	<ul style="list-style-type: none"> • 3 at 100 kHz and 3 at 30 kHz • 3 at 80 kHz and 3 at 20 kHz
Pulse outputs	2	2	2
Pulse catch inputs	6	8	14
Time delay / cyclic interrupts	4 total with 1 ms resolution	4 total with 1 ms resolution	4 total with 1 ms resolution
Edge interrupts	6 rising and 6 falling	8 rising and 8 falling	12 rising and 12 falling
With optional SB	10 rising and 10 falling	12 rising and 12 falling	14 rising and 14 falling
Real time clock			
<ul style="list-style-type: none"> • Accuracy • Retention time (maintenance-free Super Capacitor) 	<ul style="list-style-type: none"> • +/- 60 seconds/month • 10 days typ./6 days min. at 40°C 	<ul style="list-style-type: none"> • +/- 60 seconds/month • 10 days typ./6 days min. at 40°C 	<ul style="list-style-type: none"> • +/- 60 seconds/month • 10 days typ./6 days min. at 40°C
Execution speed			
<ul style="list-style-type: none"> • Boolean • Move Word • Real Math 	<ul style="list-style-type: none"> • 0.1 µs/instruction • 12 µs/instruction • 18 µs/instruction 	<ul style="list-style-type: none"> • 0.1 µs/instruction • 12 µs/instruction • 18 µs/instruction 	<ul style="list-style-type: none"> • 0.1 µs/instruction • 12 µs/instruction • 18 µs/instruction
Communication	1 Ethernet port	1 Ethernet port	1 Ethernet port
<ul style="list-style-type: none"> • Data rates • Isolation (external signal to PLC logic) • Cable type 	<ul style="list-style-type: none"> • 10/100 Mb/s • Transformer isolated, 1500 VDC • CAT5e shielded 	<ul style="list-style-type: none"> • 10/100 Mb/s • Transformer isolated, 1500 VDC • CAT5e shielded 	<ul style="list-style-type: none"> • 10/100 Mb/s • Transformer isolated, 1500 VDC • CAT5e shielded
Connections			
<ul style="list-style-type: none"> • HMI • PG • User program • CPU-to-CPU 	<ul style="list-style-type: none"> • 3 • 1 • 8 • 3 	<ul style="list-style-type: none"> • 3 • 1 • 8 • 3 	<ul style="list-style-type: none"> • 3 • 1 • 8 • 3

Digital inputs	Description	
Number of inputs	Total	Number that can be on simultaneously
<ul style="list-style-type: none"> • CPU 1211C • CPU 1212C • CPU 1214C 	<ul style="list-style-type: none"> • 6 • 8 • 14 	<ul style="list-style-type: none"> • 6 • 8 • 14
Type	Sink/Source (IEC Type 1 sink)	
Rated voltage	24 VDC at 4 mA, nominal	
Continuous permissible voltage	30 VDC, max.	
Surge voltage	35 VDC for 0.5 sec.	
Logic 1 signal (min.)	15 VDC at 2.5 mA	
Logic 0 signal (max.)	5 VDC at 1 mA	
Isolation (field side to logic)	500 VAC for 1 minute	
Isolation groups	1	
Filter times	0.2, 0.4, 0.8, 1.6, 3.2, 6.4, and 12.8 ms (selectable in groups of 4)	
HSC clock input rates (max.)	Logic 1 level = 15 to 26 VDC <ul style="list-style-type: none"> • Single phase: 100 KHz Quadrature phase: 80 KHz • Single phase: 100 KHz (la.0 to la.5) and 30 KHz (la.6 to la.7) Quadrature phase: 80 KHz (la.0 to la.5) and 20 KHz (la.6 to la.7) • Single phase: 100 KHz (la.0 to la.5) and 30 KHz (la.6 to lb.5) Quadrature phase: 80 KHz (la.0 to la.5) and 20 KHz (la.6 to lb.5) 	
Cable length (meters)	500 shielded, 300 unshielded, 50 shielded for HSC inputs	

Digital outputs	Relay	DC
Number of outputs	AC/DC/Relay and DC/DC/Relay <ul style="list-style-type: none"> • CPU 1211C: 4 • CPU 1212C: 6 • CPU 1214C: 10 	DC/DC/DC <ul style="list-style-type: none"> • CPU 1211C: 4 • CPU 1212C: 6 • CPU 1214C: 10
Number of outputs that can be on simultaneously	AC/DC/Relay and DC/DC/Relay <ul style="list-style-type: none"> • CPU 1211C: 4 • CPU 1212C: 6 • CPU 1214C: 10 	DC/DC/DC <ul style="list-style-type: none"> • CPU 1211C: 4 • CPU 1212C: 6 • CPU 1214C: 10
Type	Relay, dry contact	Solid state - MOSFET
Voltage range	5 to 30 VDC or 5 to 250 VAC	20.4 to 28.8 VDC
Logic 1 signal at max. current	N/A	20 VDC min.
Logic 0 signal with 10 KΩ load	N/A	0.1 VDC max.
Current (max.)	2.0 A	0.5 A
Lamp load	30 W DC / 200 W AC	5 W
ON state resistance	0.2 Ω max. when new	0.6 Ω max.
Leakage current per point	N/A	10 μA max.
Surge current	7 A with contacts closed	8 A for 100 ms max.
Overload protection	No	No

Technical specifications

A.2 CPU modules

Digital outputs	Relay	DC
Isolation (field side to logic)	<ul style="list-style-type: none"> Coil to contact 1500 VAC for 1 minute Coil to logic: None 	500 VAC for 1 minute
Isolation resistance	100 MΩ min. when new	N/A
Isolation between open contacts	750 VAC for 1 minute	N/A
Isolation groups	AC/DC/Relay and DC/DC/Relay <ul style="list-style-type: none"> CPU 1211C: 1 CPU 1212C: 2 CPU 1214C: 2 	DC/DC/DC <ul style="list-style-type: none"> CPU 1211C: 1 CPU 1212C: 1 CPU 1214C: 1
Inductive clamp voltage	N/A	L+ minus 48 VDC, 1 W dissipation
Switching delay (Qa.0 to Qa.3)	10 ms max.	1.0 µs max., off to on 3.0 µs max., on to off
Switching delay (Qa.4 to Qb.1)	10 ms max.	50 µs max., off to on 200 µs max., on to off
Pulse Train Output rate (Qa.0 and Qa.2)	Not recommended	100 KHz max., 2 Hz min.
Lifetime mechanical (no load)	10,000,000 open/close cycles	N/A
Lifetime contacts at rated load	100,000 open/close cycles	
Behavior on RUN to STOP	Last value or substitute value (default value 0)	
Cable length (meters)	500 m shielded, 150 m unshielded	

Analog inputs	Description
Number and type of inputs	2 Voltage (single-ended) inputs CPU 1211C, CPU 1212C, and CPU 1214C
Range	0 to 10 V
Full-scale range (data word) ¹	0 to 27648
Overshoot range (data word) ¹	27649 to 32511
Overflow (data word) ¹	32512 to 32767
Resolution	10 bits
Maximum withstand voltage	35 VDC
Smoothing ²	None, Weak, Medium, or Strong
Noise rejection ³	10, 50, or 60 Hz
Impedance	≥100 kΩ
Isolation (field side to logic)	None
Accuracy (25°C / 0 to 55°C)	3.0% / 3.5% of full-scale
Common mode rejection	40 dB, DC to 60 Hz
Operational signal range	Signal plus common mode voltage must be less than +12 V and greater than -12 V
Cable length	100 m, twisted and shielded

¹ Refer to the S7-1200 system manual for voltage and current representations of the analog inputs.

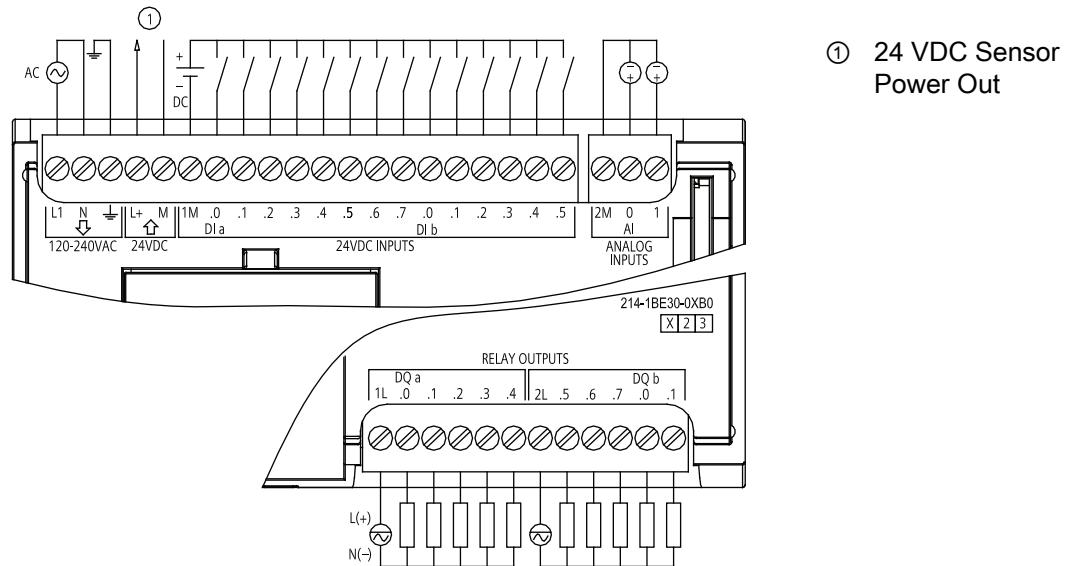
² Refer to the S7-1200 system manual for step response times of the analog inputs.

³ Refer to the S7-1200 system manual for sample rates of the analog inputs.

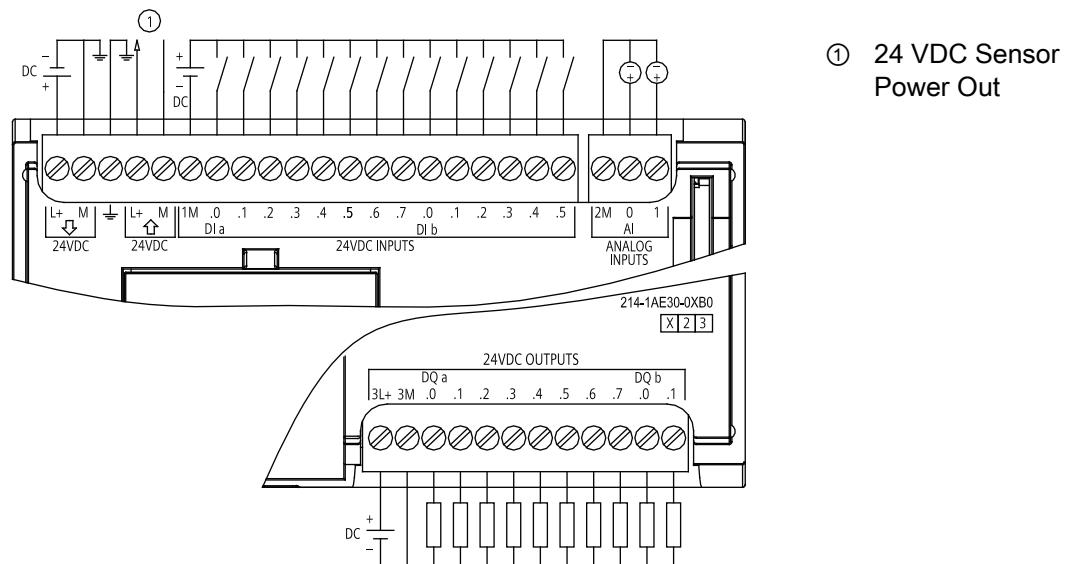
Sample wiring diagrams for the S7-1200 CPU

For complete information, see the S7-1200 system manual.

CPU 1214C AC/DC/Relay



CPU 1214C DC/DC/DC



Technical specifications

A.3 Signal boards

A.3 Signal boards

General	SB 1223 DI 2x24VDC, DQ 2x24VDC	SB 1223 AQ 1x12bit
Order number	6ES7 223-0BD30-0XB0	6ES7 232-4HA30-0XB0
Dimensions (W x H x D)	38 x 62 x 21 (mm)	38 x 62 x 21 (mm)
Weight	40 grams	40 grams
Power dissipation	1.0 W	1.5 W
Current consumption (SM Bus)	50 mA	15 mA
Current consumption (24 VDC)	4 mA / Input used	40 mA (no load)
Inputs/outputs	2 inputs (IEC Type 1 sink) 2 outputs (solid state - MOSFET)	1 output (voltage or current)

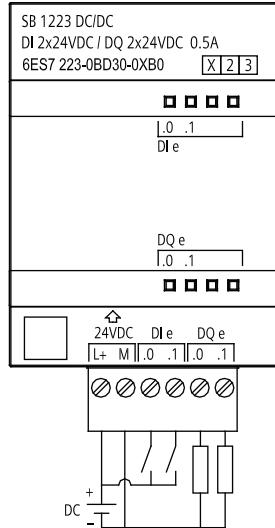
Digital inputs	SB 1223 DI 2x24VDC, DQ 2x24VDC
Number and type of inputs (Number of inputs on simultaneously)	IEC Type 1 sink: 2 inputs (2)
Rated voltage	24 VDC at 4 mA, nominal
Continuous permissible voltage	30 VDC, max.
Surge voltage	35 VDC for 0.5 sec.
Logic 1 signal (min.)	15 VDC at 2.5 mA
Logic 0 signal (max.)	5 VDC at 1 mA
HSC clock input rates (max.)	20 kHz (15 to 30 VDC); 30 kHz (15 to 26 VDC)
Isolation (field side to logic)	500 VAC for 1 minute
Isolation groups	1
Filter times	0.2, 0.4, 0.8, 1.6, 3.2, 6.4, and 12.8 ms Selectable in groups of 2
Cable length (meters)	500 shielded, 300 unshielded

Digital Outputs	SB 1223 DI 2x24VDC, DQ 2x24VDC
Number and type of outputs (Number of outputs on simultaneously)	Solid state - MOSFET: 2 outputs (2)
Voltage range	20.4 to 28.8 VDC
Logic 1 signal at max. current	20 VDC min.
Logic 0 signal with 10K Ω load	0.1 VDC max.
Current (max.)	0.5 A
Lamp load	5 W
On state contact resistance	0.6 Ω max.
Leakage current per point	10 µA max.
Pulse Train Output rate	20 KHz max., 2 Hz min.
Surge current	5 A for 100 ms max.
Overload protection	No
Isolation (field side to logic)	500 VAC for 1 minute
Isolation groups	1
Currents per common	1 A

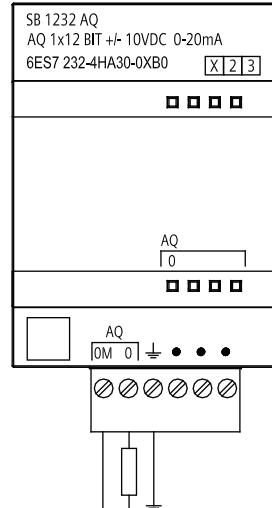
Digital Outputs	SB 1223 DI 2x24VDC, DQ 2x24VDC
Inductive clamp voltage	L+ minus 48 V, 1 W dissipation
Switching delay	2 µs max. off-to-on; 10 µs max. on-to-off
Behavior on RUN to STOP	Last value or substitute value (default value 0)
Cable length (meters)	500 shielded, 150 unshielded

Analog Outputs	SB 1223 AQ 1x12bit	
Number and type of outputs	1 (voltage or current)	
Range	±10 V or 0 to 20 mA	
Resolution	Voltage: 12 bits	Current: 11 bits
Full scale range (data word)	Voltage: -27,648 to 27,648	Current: 0 to 27,648
Accuracy (25°C / 0 to 55°C)	±0.5% / ±1% of full scale	
Settling time (95% of new value)	Voltage: 300 µS (R), 750 µS (1 uF)	Current: 600 µS (1 mH), 2 ms (10 mH)
Load impedance	Voltage: $\geq 1000 \Omega$	Current: $\leq 600 \Omega$
Behavior on RUN to STOP	Last value or substitute value (default value 0)	
Isolation (field side to logic)	None	
Cable length (meters)	100 meters, twisted and shielded	
Diagnostics	Overflow/underflow	Yes
	Short to ground (voltage mode only)	Yes
	Wire break (current mode only)	Yes

SB 1223 2x24VDC 2x24VDC



SB 1232 AQ 1



Technical specifications

A.4 Digital signal modules

A.4 Digital signal modules

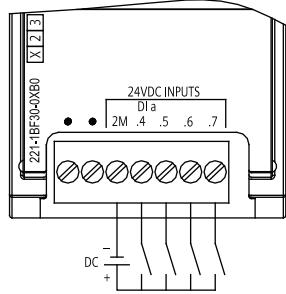
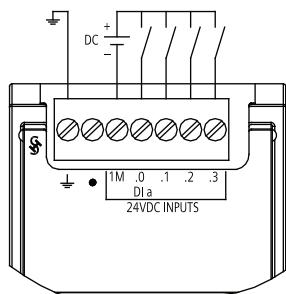
The following specifications provide a sample of the digital SM modules available for S7-1200. Refer to the S7-1200 system manual for more information.

Sample SM 1221 digital input signal modules

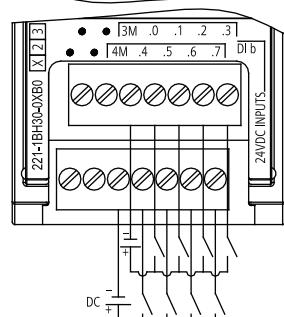
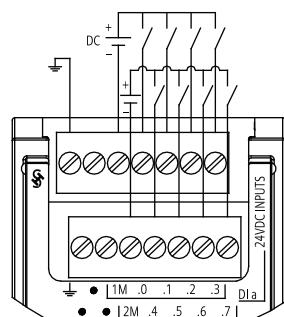
General	SM 1221 DI 8x24VDC	SM 1221 DI 16x24VDC
Number of inputs (Number of inputs on simultaneously)	8 (8)	16 (16)
Dimensions (W x H x D)	45 x 100 x 75 (mm)	45 x 100 x 75 (mm)
Weight	170 grams	210 grams
Power dissipation	1.5 W	2.5 W
Current consumption (SM Bus)	105 mA	130 mA
Current consumption (24 VDC)	4 mA / input used	4 mA / input used

Digital inputs	Description
Input type	Sink/Source (IEC Type 1 sink)
Rated voltage	24 VDC at 4 mA, nominal
Continuous permissible voltage	30 VDC, max.
Surge voltage	35 VDC for 0.5 sec.
Logic 1 signal (min.)	15 VDC at 2.5 mA
Logic 0 signal (max.)	5 VDC at 1 mA
Isolation (field side to logic)	500 VAC for 1 minute
Isolation groups	DI 8x24VDC: 2; DI 16x24VDC: 4
Filter times (ms)	0.2, 0.4, 0.8, 1.6, 3.2, 6.4, and 12.8 (selectable in groups of 4)
Cable length (meters)	500 shielded, 300 unshielded

SM 1221 DI 8 x 24 VDC



SM 1221 DI 16 x 24 VDC



Sample SM 1222 output-only signal modules

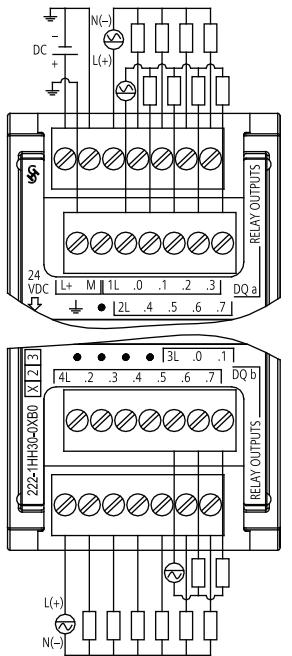
General	SM1222 DQ 16xRelay	SM1222 DQ 16x24VDC
Number and type of outputs	16 relay, dry contact	16 solid state - MOSFET
Dimensions (W x H x D)	45 x 100 x 75 (mm)	45 x 100 x 75 (mm)
Weight	260 grams	220 grams
Power dissipation	8.5 W	2.5 W
Current consumption (SM Bus)	135 mA	140 mA
Current consumption (24 VDC)	11 mA / Relay coil used	N/A

Digital outputs	SM1222 DQ 16xRelay	SM1222 DQ 16x24VDC
Number and type of outputs (Number of outputs on simultaneously)	16 relay, dry contact (16)	16 solid state - MOSFET (16)
Voltage range	5 to 30 VDC or 5 to 250 VAC	20.4 to 28.8 VDC
Logic 1 signal at max. current Logic 0 signal with 10K Ω load	N/A	20 VDC min. 0.1 VDC max.
Current (max.)	2.0 A	0.5 A
Lamp load	30 W DC / 200 W AC	5 W
On state contact resistance	0.2 Ω max. when new	0.6 Ω max.
Leakage current per point	N/A	10 μA max.
Surge current	7 A with contacts closed	8 A for 100 ms max.
Overload protection	No	No
Isolation (field side to logic)	Coil to contact: 1500 VAC for 1 minute Coil to logic: None	500 VAC for 1 minute
Isolation resistance	100 MΩ min. when new	N/A
Isolation between open contacts	750 VAC for 1 minute	
Isolation groups	4	1
Current per common (max.)	10 A	8 A
Inductive clamp voltage	N/A	L+ minus 48 V, 1 W dissipation
Switching delay	10 ms max.	50 μs max. off to on 200 μs max. on to off
Lifetime mechanical (no load)	10,000,000 open/close cycles	N/A
Lifetime contacts at rated load	100,000 open/close cycles	
Behavior on RUN to STOP	Last value or substitute value (default value 0)	Last value or substitute value (default value 0)
Cable length (meters)	500 shielded, 150 unshielded	500 shielded, 150 unshielded

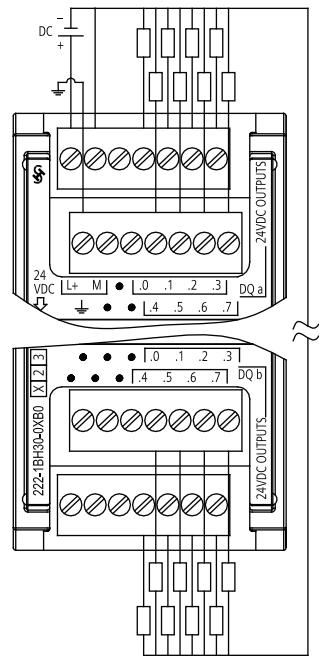
Technical specifications

A.4 Digital signal modules

SM 1222 DQ 16 x Relay



SM 1222 DQ 16 x 24 VDC



Sample SM 1223 combination digital input/output signal modules

General	SM 1223 DI 16x24 VDC, DQ 16xRelay	SM 1223 DI 16x24 VDC, DQ16x24 VDC
Number and type of inputs (Number of inputs on simultaneously)	16 sink/source (IEC Type 1 sink) (16)	16 sink/source (IEC Type 1 sink) (16)
Number and type of outputs (Number of inputs on simultaneously)	16 relay, dry contact (16)	16 solid state - MOSFET (16)
Dimensions (W x H x D)	70 x 100 x 75 (mm)	70 x 100 x 75 (mm)
Weight	350 grams	310 grams
Power dissipation	10 W	4.5 W
Current consumption (SM Bus)	180 mA	185 mA
Current consumption (24 VDC)	4 mA / Input used 11 mA / Relay coil used	4 mA / Input used

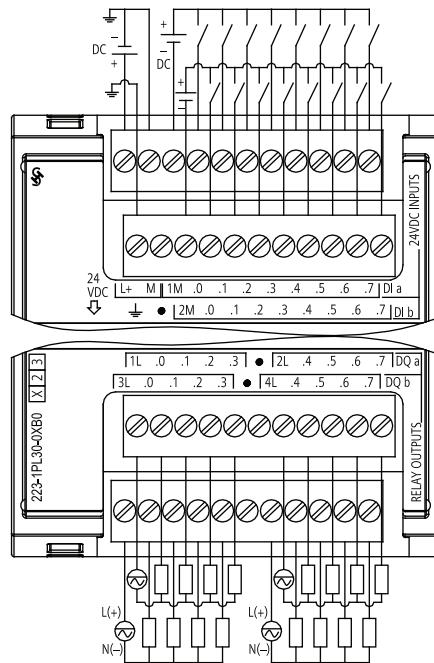
Digital inputs	Description
Number and type of inputs	16 sink/source (IEC Type 1 sink)
Rated voltage	24 VDC at 4 mA, nominal
Continuous permissible voltage	30 VDC, max.
Surge voltage	35 VDC for 0.5 sec.
Logic 1 signal (min.)	15 VDC at 2.5 mA
Logic 0 signal (max.)	5 VDC at 1 mA
Isolation (field side to logic)	500 VAC for 1 minute
Isolation groups	2
Filter times (ms)	0.2, 0.4, 0.8, 1.6, 3.2, 6.4, and 12.8 ms, selectable in groups of 4
Cable length (meters)	500 shielded, 300 unshielded

Digital outputs	SM 1223 DI 16x24 VDC, DQ 16xRelay	SM 1223 DI 16x24 VDC, DQ16x24 VDC
Number and type of outputs (Number of outputs on simultaneously)	16 relay, dry contact (16)	16 solid state - MOSFET (16)
Voltage range	5 to 30 VDC or 5 to 250 VAC	20.4 to 28.8 VDC
Logic 1 signal at max. current	N/A	20 VDC min.
Logic 0 signal with 10K Ω load		0.1 VDC max.
Current (max.)	2.0 A	0.5 A
Lamp load	30 W DC / 200 W AC	5 W
On state contact resistance	0.2 Ω max. when new	0.6 Ω max.
Leakage current per point	N/A	10 μA max.
Surge current	7 A with contacts closed	8 A for 100 ms max.
Overload protection	No	No
Isolation (field side to logic)	Coil to contact: 1500 VAC for 1 minute Coil to logic: None	500 VAC for 1 minute
Isolation resistance	100 MΩ min. when new	N/A
Isolation between open contacts	750 VAC for 1 minute	
Isolation groups	4	1
Current per common (max.)	8 A	8 A
Inductive clamp voltage	N/A	L+ minus 48 V, 1 W dissipation
Switching delay	10 ms max.	50 μs max. off to on 200 μs max. on to off
Lifetime mechanical (no load)	10,000,000 open/close cycles	N/A
Lifetime contacts at rated load	100,000 open/close cycles	
Behavior on RUN to STOP	Last value or substitute value (default value 0)	
Cable length (meters)	500 shielded, 150 unshielded	

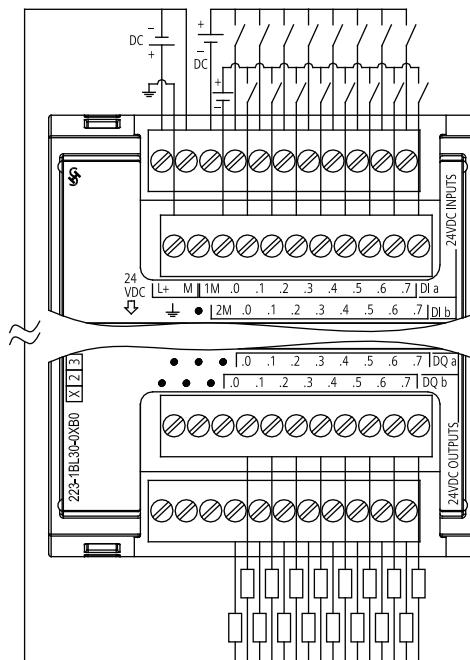
Technical specifications

A.5 Analog signal modules

SM1223 DI 16 x 24 VDC, DQ 16 x Relay



SM 1223 DI 16 x 24 VDC, DQ 16 x 24 VDC



A.5 Analog signal modules

The following specifications provide a sample of the analog SM modules available for S7-1200. Refer to the S7-1200 system manual for more information.

General	SM 1231 AI 4x13bit	SM 1234 AI 4x13bit AQ 2x14bit	SM 1232 AQ 2x14bit
Number and type of inputs (Selectable in groups of 2)	4 Voltage or Current (differential)	4 Voltage or Current (differential)	0
Number and type of outputs	0	2 voltage or current	2 voltage or current
Dimensions W x H x D	45 x 100 x 75 (mm)	45 x 100 x 75 (mm)	45 x 100 x 75 (mm)
Weight	180 grams	220 grams	180 grams
Power dissipation	1.5 W	2.0 W	1.5 W
Current consumption (SM Bus)	80 mA	80 mA	80 mA
Current consumption (24 VDC)	45 mA	60 mA (no load)	45 mA (no load)

Analog inputs	Description
Type of inputs	Voltage or Current (differential), selectable in groups of 2
Range	± 10 V, ± 5 V, ± 2.5 V, or 0 to 20 mA
Full scale range (data word)	-27,648 to 27,648
Overshoot/undershoot range (data word) ¹	Voltage: 32,511 to 27,649 / -27,649 to -32,512 Current: 32,511 to 27,649 / 0 to -4864
Overflow/underflow (data word) ¹	Voltage: 32,767 to 32,512 / -32,513 to -32,768 Current: 32,767 to 32,512 / -4865 to -32,768
Resolution	12 bits + sign bit
Maximum withstand voltage/current	± 35 V / ± 40 mA
Smoothing ²	None, weak, medium, or strong
Noise rejection ³	400, 60, 50, or 10 Hz
Impedance	≥ 9 M Ω (voltage) / 250 Ω (current)
Isolation (field side to logic)	None
Accuracy (25°C / 0 to 55°C)	$\pm 0.1\%$ / $\pm 0.2\%$ of full scale
Analog to digital conversion time	625 μ s (400 Hz rejection)
Common mode rejection	40 dB, DC to 60 Hz
Operational signal range	Signal plus common mode voltage must be less than +12 V and greater than -12 V
Cable length (meters)	100 meters, twisted and shielded

¹ Refer to the S7-1200 system manual for voltage and current representations of the analog inputs.

² Refer to the S7-1200 system manual for step response times of the analog inputs.

³ Refer to the S7-1200 system manual for sample rates of the analog inputs.

Analog outputs	Description
Type of outputs	Voltage or current
Range	± 10 V or 0 to 20 mA
Resolution	Voltage: 14 bits Current: 13 bits
Full scale range (data word) ¹	Voltage: -27,648 to 27,648 Current: 0 to 27,648
Accuracy (25°C / 0 to 55°C)	$\pm 0.3\%$ / $\pm 0.6\%$ of full scale
Settling time (95% of new value)	Voltage: 300 μ S (R), 750 μ S (1 μ F) Current: 600 μ S (1 mH), 2 ms (10 mH)
Load impedance	Voltage: ≥ 1000 Ω Current: ≤ 600 Ω
Behavior on RUN to STOP	Last value or substitute value (default value 0)
Isolation (field side to logic)	None
Cable length (meters)	100 meters twisted and shielded

¹ Refer to the S7-1200 system manual for voltage and current representations of the analog outputs.

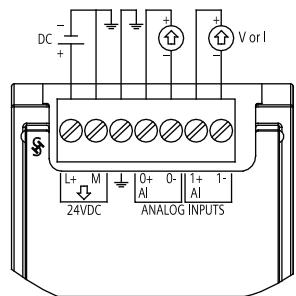
Diagnostics	SM 1231 AI 4x13bit	SM 1234 AI 4x13bit AQ 2x14bit	SM 1232 AQ 2x14bit
Overflow/underflow	Yes ¹	Yes ¹	N/A
Short to ground (voltage mode only)	No	Yes (outputs)	Yes
Wire break (current mode only)	No	Yes, (outputs)	Yes
24 VDC low voltage	Yes	Yes	Yes

¹ If a voltage greater than +30 VDC or less than -15 VDC is applied to the input, the resulting value will be unknown and the corresponding overflow or underflow may not be active.

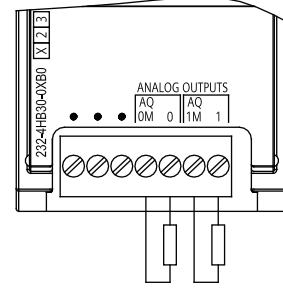
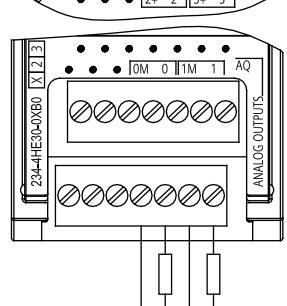
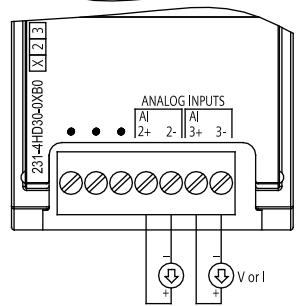
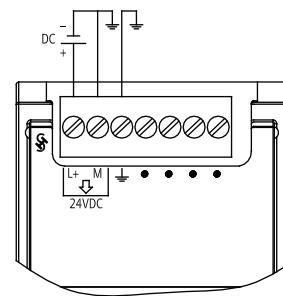
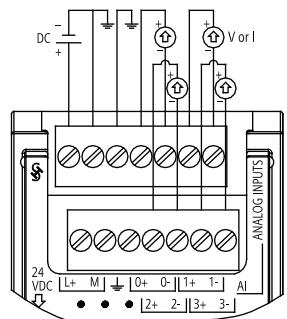
Technical specifications

A.6 Communication modules

SM 1231 AI 4 x 13 Bit



SM 1234 AI 4x13bit AQ 2x14bit SM 1232 AQ 2 x 14 bit



A.6 Communication modules

The following specifications provide a sample of the CM modules available for S7-1200. Refer to the S7-1200 system manual for pin-outs and other information.

General	CM 1241 RS485	CM 1241 RS232
Dimensions (W x H x D)	30 x 100 x 75 (mm)	30 x 100 x 75 mm
Weight	150 grams	150 grams
Power loss (dissipation)	1.1 W	1.1 W
From +5 VDC	220 mA	220 mA

Transmitter and Receiver		Description
Transmitter (RS485)	Common mode voltage range	-7 V to +12 V, 1 second, 3 VRMS continuous
	Transmitter differential output voltage	2 V min. at $R_L = 100 \Omega$ 1.5 V min. at $R_L = 54 \Omega$
	Termination and bias	10K Ω to +5 V on B, PROFIBUS Pin 3 10K Ω to GND on A, PROFIBUS Pin 8
Transmitter (RS232)	Transmitter output voltage	+/- 5 V min. at $R_L = 3K \Omega$
	Transmit output voltage	+/- 15 VDC max.
Receiver	Receiver input impedance	<ul style="list-style-type: none"> RS485: 5.4K Ω min. including termination RS232: 3 K Ω min.
	Receiver threshold/sensitivity	<ul style="list-style-type: none"> RS485: +/- 0.2 V min., 60 mV typical hysteresis RS232: 0.8 V min. low, 2.4 max. high 0.5 V typical hysteresis
	Receiver input voltage (RS232 only)	+/- 30VDC max.
Isolation	Signal to chassis ground Signal to CPU logic common	500 VAC, 1 minute
Cable length, shielded (max.)		<ul style="list-style-type: none"> RS485: 1000 m. RS232: 10 m.

CM 1241 RS485				
Pin	Description	Connector (female)	Pin	Description
1 GND	Logic or communication ground		6 PWR	+5V with 100 ohm series resistor: Output
2	Not connected		7	Not connected
3 TxD+	Signal B (RxD/TxD+): Input/Output		8 TXD-	Signal A (RxD/TxD-): Input/Output
4 RTS	Request to send (TTL level): Output		9	Not connected
5 GND	Logic or communication ground		SHELL	Chassis ground

CM 1241 RS232				
Pin	Description	Connector (male)	Pin	Description
1 DCD	Data carrier detect: Input		6 DSR	Data set ready: Input
2 RxD	Received data from DCE: Input		7 RTS	Request to send: Output
3 TxD	Transmitted data to DCE: Output		8 CTS	Clear to send: Input
4 DTR	Data terminal ready: Output		9 RI	Ring indicator (not used)
5 GND	Logic ground		SHELL	Chassis ground

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