



1768 CompactLogix Controllers, Revision 19

CompactLogix Catalog Numbers 1768-L43, 1768-L45

Compact GuardLogix Catalog Numbers 1768-L43S, 1768-L45S

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This publication describes enhancements and anomalies (known and corrected) for 1768 CompactLogix and Compact GuardLogix controllers, firmware revision 19.11.

Table 1 - Controllers and Revisions

Cat. No.	Major and Minor Revision No.
1768-L43	19.11
1768-L45	
1768-L43S	
1768-L45S	



IMPORTANT

Consider the following before upgrading the firmware on your Logix5000 controller:

- Before updating your controller, we strongly recommend that you review information pertinent to previous major firmware revisions. For example, when updating from revision 17.x to 19.x, view information in the following publications:

- 1768 CompactLogix Controllers, Revision 17 Release Notes, publication [1768-RN017](#)
- 1768 CompactLogix Controllers, Revision 18 Release Notes, publication [1768-RN018](#)

Firmware release notes contain material for all minor revisions subsequent to each major revision. If your controller, for example, is at revision 17.11, and not the last minor revision, 18.15, you should view all of the information for revisions 18.11...18.15 before updating to revision 19.x.

Release notes are available at: <http://www.rockwellautomation.com/literature>.

- After upgrading the firmware on your module, we strongly recommend that you **retest/validate your application offline before going online.**
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Compatible Software Versions

To use firmware revision 19.11, these minimum software versions are required.

Table 2 - Compatible Software Versions

Software	Required Version
RSLink Classic	2.57 (CPR 9, SR3)
RSLink Enterprise	5.30 (CPR 9, SR3)
RSLogix 5000	19.00 (CPR 9, SR3)
RSNetWorx for ControlNet	10.01 (CPR 9, SR3)
RSNetWorx for DeviceNet	
RSNetWorx for EtherNet/IP	

Before You Begin

Before you upgrade your firmware, consider the following.

IMPORTANT

Loss of communication or power during a controller firmware flash upgrade may result in the controller rejecting the new firmware. If the controller firmware upgrade fails due to the conditions described, these corrective actions may be required:

- Cycle controller power and successfully complete the flash upgrade.
- If a nonrecoverable fault occurs, then return the controller for factory repair.

These preliminary actions are required before upgrading your controller firmware.

Table 3 - Before You Begin

If	Then
You are using ControlFLASH software, version 9 (CPR9 SR3) with firmware revision 19	<p>Consider the following before you install the software:</p> <ul style="list-style-type: none"> • We recommend you install RSLinx communication software, version 2.57, before you install ControlFLASH software, version 9 (CPR9 SR3). • If you install RSLinx communication software, version 2.57, before you install ControlFLASH software, version 9, you can enable or disable the FactoryTalk Security platform during ControlFLASH software, version 9, installation. However, to disable the FactoryTalk Security platform, you must first uninstall ControlFLASH software, version 9, then reinstall it. • If the FactoryTalk Security platform is enabled during ControlFLASH software, version 9, installation, the software opens with a Select FactoryTalk Directory dialog box. At that dialog box, click the following: <ul style="list-style-type: none"> – Network – Local – Cancel - If you click Cancel, you must select a directory. • ControlFLASH software, version 9, only integrates the FactoryTalk Security platform in the FactoryTalk Services Platform, version 2.30 or later.
<p>Your controller meets both of these conditions:</p> <ul style="list-style-type: none"> • It has nonvolatile memory • It is currently at revision 11.x or earlier 	<p>Remove the CompactFlash card from the controller or check the Load Image option of the CompactFlash card. If it is set to On Power Up or On Corrupt Memory, first store the project with the Load Image option set to User Initiated.</p> <p>Otherwise, you may get a major fault when you update the firmware of the controller. This occurs because the On Power Up or On Corrupt Memory options cause the controller to load the project from nonvolatile memory. The firmware mismatch after the load then causes a major fault.</p>
Your controller is close to its limits of memory	<p>This revision may require more memory than previous revisions:</p> <ul style="list-style-type: none"> • To see what components of your current project require more memory, see page 13. • RSLogix 5000 software, version 13.0 or later, lets you estimate the memory requirements of the controller offline. <p>To update to this revision, you may need to use a controller with a larger amount of memory.</p>
Your controller is connected to a DH-485 network	<p>Disconnect it from the DH-485 network before you update the firmware of the controller. If you update the firmware of a controller while it is connected to a DH-485 network, communication on the network may stop.</p>

Enhancements

These enhancements are available when firmware revision 19.11 is used with RSLogix 5000 software, version 19.

Table 4 - Enhancements with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	Load Observer
	The Load Observer is a new servo loop feature that improves servo performance and robustness and simplifies system tuning.
	Option to Suppress Array Faults During Postscan of SFC Actions
	Use this feature to configure your application so that selected faults, that is, 4/20 and 4/83, encountered when an SFC action is postscanned, are suppressed. When the fault is suppressed, the controller uses an internal fault handler to clear it. Clearing the fault causes the postscan process to skip the instruction containing the fault and continue with the next instruction. This enhancement is valid only when SFC instructions are configured for automatic reset.
1768-L43S, 1768-L45S	Safety Unicast Produce/Consume
	CIP Safety unicast Produce/Consume allows direct point-to-point communication between two GuardLogix Controllers on a network, for example, EtherNet/IP or ControlNet. Safety unicast communication is useful when safety data does not need to be shared between more than two GuardLogix controllers.

Corrected Anomalies

These anomalies have been corrected with firmware revision 19.11.

Table 5 - Corrected Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	Controller may fail to transition from Run mode to Program mode when some MSG instruction types are used.
	The failure to transition to Program mode occurs after the controller receives an 0x13 error code, that is, Configuration Data too Short. When a transition request is made after the controller receives an 0x13 error code, the controller acknowledges the request but never completes the transition.
	Either of the following conditions cause this anomaly to occur: <ul style="list-style-type: none"> Controller executes SLC Typed Write message with the Number of Elements exceeding 108 bytes Controller executes SLC Typed Read message with the Number of Elements exceeding 118 bytes The controller remains in Run mode until power is cycled. Lgx00113381, Lgx00109216
	Serial port UART may stall during communication between a controller and a device. This anomaly may have manifested itself in the following conditions when a controller is connected to another device, such as a PanelView terminal, through its serial port: <ul style="list-style-type: none"> Communication through the serial port stops completely. The controller's RS-232 status indicator turns solid green. Execute either of the following tasks to resume communication over the serial port connection: <ul style="list-style-type: none"> Cycle power to the controller. Change the serial port configuration, for example, the node number. For more information about this anomaly, see the Technical Note titled Serial Port UART Appears To Be Stalling #67950, in the Technical Support Knowledgebase available at http://www.rockwellautomation.com/knowledgebase/ . Lgx00113379, Lgx00106893

Table 5 - Corrected Anomalies with Firmware Revision 19.11

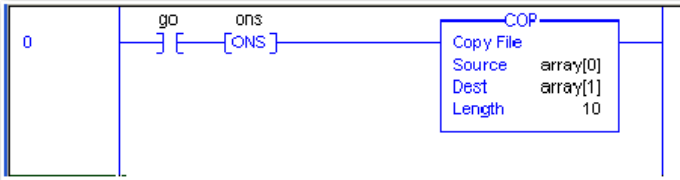
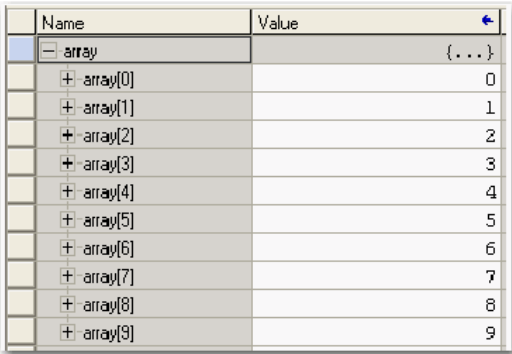
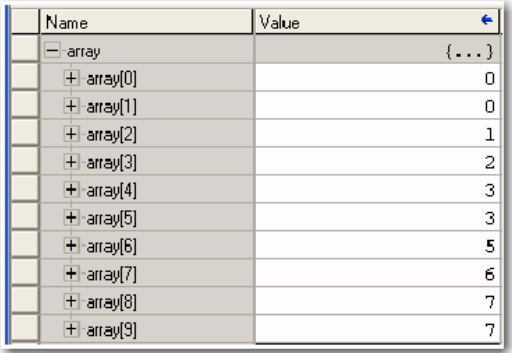
Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>The Copy File (COP) Synchronous Copy File (CPS) instruction use may result in Unexpected Execution</p> <p>If the COP or CPS instructions are configured so that the source and destination tags overlap, the instruction has unexpected execution.</p> <p>For example, these graphics show an example COP instruction and its tag values before execution.</p>   <p>The result should be an array that contains all zeros. Instead, the result is an array that contains the values shown in this graphic.</p>  <p>Lgx00114495, Lgx00114576</p>

Table 5 - Corrected Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>PCCC command bit write does not update the controller.</p> <p>When you use PCCC command bit write (CMD 0F FNC 02) to execute bit-level writes to a controller, the PCCC command appears to complete successfully but does not. Consequently, the data in the controller does not change in the targeted address in the memory. Instead, the write operation writes to the wrong address in memory; this may potentially cause a major non-recoverable fault.</p> <p>A typical condition where you may be using this command is when you set up PLC/SLC mapping in the controller that is the target of the communication. Additionally, you can use this command when communicating to a Logix controller from legacy systems that do not use the CIP protocol.</p> <p>Logix controllers do not initiate this command.</p> <p>For more information about this anomaly, see the Technical Note titled Bit writes fail with a Standard PanelView to a ControlLogix processor with revision 18 firmware when using SLC/PLC mapping #69234, in the Technical Support Knowledgebase available at http://www.rockwellautomation.com/knowledgebase/.</p> <p>Lgx00113378, Lgx00111497</p>
	<p>A watchdog fault occurs during prescan on a transition from Program mode to Run mode.</p> <p>In large applications that include elements, such as many Add-On Instructions, Add-On Instructions with defined prescan routines, and complex Structural Text routines, the prescan could exceed 60 seconds. Because 60 seconds was the prescan watchdog setting, the controller experienced a major recoverable fault.</p> <p>To correct this anomaly, the prescan watchdog has been changed to 300 seconds.</p> <p>IMPORTANT: You cannot configure the prescan watchdog value.</p> <p>Lgx00113376, Lgx00112413</p>
	<p>Controller experiences a major non-recoverable fault during a partial import online to a periodic or event task.</p> <p>This anomaly occurred when the following conditions existed:</p> <ul style="list-style-type: none"> • Program in the Task previously had no Add-On Instructions, and the imported changes included Add-On Instructions. • Program in the Task was being rescheduled under another Task. <p>Lgx00112034, Lgx00108203</p>
	<p>A Shutdown fault action issued by the controller overrides the drive state change only when the drive state change is reported as Disable.</p> <p>Lgx00109658, Lgx00106420</p>
	<p>When using Master Control Reset (MCR) zones that contain Add-On Instructions, the rungs may not evaluate correctly. After the Add-On Instruction, the remainder of the MCR zone is scanned as if the MCR zone were scanned true.</p> <p>If your application requires the use of Add-On Instructions in MCR zones, we recommend you reposition the Add-On Instructions before or after the MCR zone and add their own conditional logic.</p> <p>For more information about this anomaly, see the Technical Note titled MCR Zones Containing Add-On Instructions May Not Scan Rungs as False in Certain Firmware Revisions #68915, in the Technical Support Knowledgebase available at http://www.rockwellautomation.com/knowledgebase/.</p> <p>Lgx00113377, Lgx00110876</p>

Table 5 - Corrected Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>The Coordinated Control (CC), Internal Model Control (IMC), and Modular Multivariable Control (MMC) instructions may experience a bump in the output control variable (CV) if you transition from Manual mode to Auto mode soon after placing the controller into Run mode. For this anomaly to occur, your application must have one of the following conditions:</p> <ul style="list-style-type: none"> • CVxInitValue is not equal to zero. • CVxProg is wired to a non-zero value that is different from CVxInitValue while in ProgramManual mode. • CVxOper is wired to a non-zero value that is different from CVxInitValue while in OperatorManual mode. <p>In addition, the CC instruction may experience a bump in the output CV if you transition from Manual mode to Auto mode soon after a Modelinit. For this to occur, CVxEUMin and CVxEUMax must have a range other than 0...100.</p> <p>In both cases, the bump will occur if the time from the initial condition to the Manual -> Auto mode switch is less than $(3 * CVxModelTC) + CVxModelDt$. The sooner the mode switch is made, the larger the bump.</p> <p>Lgx00113391, Lgx00111367</p> <hr/> <p>When a controller is configured for rotary operation and produces axes that other controllers consume, the consumed actual position was not tracking the consumed commanded position and manifested itself via two anomalous behaviors. The actual position appeared to have a small constant displacement in comparison to commanded position and would also exceed the expected unwind value.</p> <hr/> <p>IMPORTANT This anomaly occurs only when the controller producing the axes is configured for rotary operation.</p> <hr/> <p>You could work around this anomaly in one of the following ways:</p> <ul style="list-style-type: none"> • If the produced axes were commanded axes, and it was acceptable in your application, you could reference the consumed axes' Commanded Position. • If the produced axes were virtual axes, you could reference the consumed axes' Commanded Position. This option would work for all applications. <p>Lgx00111591, Lgx00111473</p> <hr/> <p>If a Motion Group is configured as General Fault Type = Major Fault and a motion fault occurs, there is a remote possibility either the fault log gets overrun or a major non-recoverable fault occurs.</p> <p>Lgx00113529, Lgx00109362</p> <hr/> <p>On the rare occasion that a controller misses an input update from a SERCOS motion module, the controller then stops processing input updates for 256 coarse updates. During the time in which the controller is not processing input updates, it uses data from the last input update before missing an update. Therefore, the controller does not use current input data for 256 coarse updates.</p> <p>After 256 coarse updates, the controller re-synchronizes with the SERCOS motion module and uses current data on the axis until another missed input update occurs.</p> <p>Lgx00113524, Lgx00112064</p>

Table 5 - Corrected Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>The controller may experience a major non-recoverable (MNRF) fault if these conditions exist:</p> <ul style="list-style-type: none"> System Configuration uses the following three coordinate systems: <ul style="list-style-type: none"> Coordinate system 1 (CS1) contains the X, Y, Z axes and is the Source Coordinate System for a Transform. Coordinate system 2 (CS2) contains the J1, J2, J3 axes and is the Target Coordinate System. Coordinate system 3 (CS3) contains the X, Y, A axes and is a third coordinate system containing one or more axes in the coordinate system. Preconditions exist: <ul style="list-style-type: none"> A transform has been activated, that is, a Motion Coordinated Transform (MCT) instruction was executed, between the source, that is CS1, and target, that is CS2, coordinate systems. Any axis in CS2 is moving. For example, a Motion Axis Move (MAM) instruction is active on an axis in CS2, or a Motion Coordinated Linear Move (MCLM) instruction is active in CS2. Either of the following actions are taken: <ul style="list-style-type: none"> A MCLM or Motion Coordinated Circular Move (MCCM) instruction is executed on CS3. A MAM instruction is executed on any axis in CS1. <p>Lgx00108920, Lgx00113383</p> <p>On a Velocity/Torque axis, a MGS instruction configured for a Stop mode of Fast Stop (this includes a programmed Stop mode of Fast Stop) decelerates the axis to a stop and then disables the drive. As of this release, the drive remains enabled.</p> <p>Lgx00112392, Lgx00110834</p>
1768-L43S, 1768-L45S	<p>If a Compact GuardLogix controller uses produced and consumed tags in a safety application, the tags must be at least 17 bits. If the tags are fewer than 17 bits, the controller receives an error message of Message Timeout.</p> <p>Lgx00113373, Lgx00109284</p>

Known Anomalies

These anomalies have been identified with firmware revision 19.11.

Table 6 - Known Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>Unsuccessful MSG execution results in subsequent unsuccessful messages in master/slave controller configurations.</p> <p>When a DF-1 serial connection is used between a master and slave controller, a MSG instruction is not successfully executed and an in-polling sequence error occurs if the master station address is not listed in the poll node list.</p> <p>However, with this anomaly, after the in-polling sequence error, subsequent MSG instructions are also unsuccessful.</p> <p>To work around this anomaly, change the master controller's station address to a different value or re-execute the unsuccessful MSG instruction in Master Transmit mode and use the Between Station Polls parameter.</p> <p>Lgx00083882, Lgx00082610</p> <p>PI function block appears to stop executing as the output does not change and no instruction faults are logged.</p> <p>If the PI instruction is being used in Linear mode, this floating-point equation is used to calculate the ITerm.</p> $Kp \times Wld \times \frac{WldInput + WldInput_{n-1}}{2} \times DeltaT + ITerm_{n-1}$ <p>Due to the use of the single-precision floating point values, it may be possible, depending on the values of WLD and KP, for the ITerm value to be small enough, less than 0.0000001, to be lost when adding to the ITerm_{n-1}.</p> <p>For more information regarding the PI instruction, see the Logix5000 Controllers Process Control and Drives Instructions User Manual, publication 1756-RM006.</p> <p>Lgx00070832</p>

Table 6 - Known Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>Changes made to the Buffer Timeout value for FactoryTalk Alarms and Events subscribers do not take effect until the existing buffer has been deleted.</p> <p>The FactoryTalk alarm buffer (stored in Logix controller memory) is designed to persist through power cycles. If you change the Buffer Timeout value (via the Communication Setup dialog box in FactoryTalk View SE software), the controller does not use the new timeout value until the existing buffer is deleted and then recreated. To force recreation of this buffer, do one of the following:</p> <ul style="list-style-type: none"> • Redownload the project to the controller • Disconnect the FactoryTalk Alarms and Events subscriber and leave it disconnected until the existing timeout expires. <p>Lgx00069461</p>
	<p>Under some rare occurrences, if a Motion Axis Move (MAM) instruction with Merge Enabled is activated during the deceleration segment of an active MAM instruction then the new MAM instruction may overshoot its programmed endpoint. The occurrence of the overshoot depends on the following factors:</p> <ul style="list-style-type: none"> • The original MAM instruction's remaining travel distance at the time of the merge and the new MAM instruction's remaining travel distance • The relationship of the decel jerk of the new MAM instruction to the decel jerk of the original MAM instruction • If the original MAM instruction is decelerating <p>Typically, the overshoot does not occur. If either of the following conditions exist, you will avoid the overshoot:</p> <ul style="list-style-type: none"> • The new MAM instruction is programmed with Merge Disabled. If there is no other motion active at the time of the merge, then the Merge Disable results in the same operation as the Merge Enable. • The new MAM instruction has a slightly higher jerk (in units/seconds³) than the original MAM instruction. You should note, though, lower value of jerk in % of time results in higher value of jerk (in units/seconds³). <p>Lgx00078822</p>
	<p>If a Motion Group Shutdown Reset (MGSR) instruction is executed while a Motion Group Shutdown (MGSD) is still executing, motion error #7, that is, Shutdown State Error, results.</p> <p>The purpose of an MGSR instruction is to bring an axis group out of the shutdown state. However, when the scenario described in the previous paragraph exists, the MGSR instruction is not executed because the shutdown procedure, initiated by the MGSD instruction, has precedence. Thus, the MGSR instruction generates motion error #7 because the shutdown procedure has not completed. The shutdown procedure must complete before any attempt to reset the shutdown.</p> <p>Lgx00095484</p>
	<p>A small window exists where, when the .PC bit is set on a Motion Group Stop (MGS) instruction configured as Stop Mode = Fast Disable, all axes in the selected group are not disabled. However, the axes in the group are disabled after the next Coarse Update.</p> <p>Lgx00113546, Lgx00106782</p>
	<p>The .ACCEL and .DECEL Motion status bits operate differently than in RSLogix 5000 programming software, version 17.x because the axis status bits of the consumed axis are recalculated instead of reusing the axis status bits of the producer axis.</p> <p>Lgx00107454</p>

Table 6 - Known Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<div data-bbox="342 388 1398 420"> <p>IMPORTANT This anomaly occurs only in SERCOS applications that use Kinetix SERCOS drives and linear motors.</p> </div> <p data-bbox="342 489 1390 539">Under certain conditions, it is possible that the Real Time Axis attribute VelocityFeedback contains an incorrect value. The inaccuracy is the result of incorrect scaling of that attribute.</p> <p data-bbox="342 560 1218 588">Your program will have an incorrect value for the VelocityFeedback attribute if you follow these steps.</p> <ol data-bbox="342 609 1430 682" style="list-style-type: none"> 1. While offline, you write your RSLogix 5000 program and, as part of that program, the VelocityFeedback attribute is selected. 2. You save the program and download it to the controller. 3. You go online. <p data-bbox="342 703 1459 753">The VelocityFeedback attribute value is incorrect because that attribute was enabled before the program was saved, downloaded, and put online.</p> <p data-bbox="342 774 1341 802">To work around this anomaly, do not enable the VelocityFeedback attribute until the RSLogix 5000 program is online.</p> <p data-bbox="342 823 456 850">Lgx00107793</p> <p data-bbox="342 867 1464 940">When a Master Axis Position Cam (MAPC) instruction, with Execution Schedule = Pending, is executed, its master axis is ignored. However, its master axis' scaling constant is used to scale the Master Scaling parameter instead of the scaling constant on the axis that is currently active. Using the incorrect scaling constant results in incorrect overall scaling of the PCAM.</p> <p data-bbox="342 961 954 989">You can take one of the following actions to work around this anomaly:</p> <ul data-bbox="342 1008 1170 1081" style="list-style-type: none"> • Set the PCAM's master axis to be identical to the active master axis. • Update the Master Scaling coefficient off the pending move to achieve desired scaling factor. <p data-bbox="342 1100 581 1127">Lgx00113538, Lgx00112356</p> <p data-bbox="342 1144 1451 1194">When using Add-On Instructions, if you use the same backing/reference tag for multiple Add-On Instructions that are in different tasks, the controller may experience a major non-recoverable (MNRF) fault.</p> <p data-bbox="342 1215 1469 1266">For example, you have an Add-On Instruction called Motor_Start that is used twice in the application, once in Periodic Task 1 and once in Periodic Task 2, in both cases the Motor_Start Add-On Instruction uses the same backing/reference tag Pump_Motor_Start.</p> <p data-bbox="342 1287 891 1314">The following events may occur when the program is executing:</p> <ol data-bbox="342 1333 1122 1554" style="list-style-type: none"> 1. Periodic Task 1 is executing and the Motor_Start is being scanned. 2. Periodic Task 2 preempts Periodic Task 1. 3. Periodic Task 2 runs and the Motor_Start is executed. 4. Periodic Task 1 is allowed to again execute and completes scanning of the Motor_Start. 5. Upon completion of scanning Motor_Start the controller can MNRF. <p data-bbox="342 1575 1117 1602">The MNRF occurs if one instance of the Motor_Start scans false and the other scans true.</p> <p data-bbox="342 1621 1149 1648">To work around this anomaly, use individual backing/reference tag for all Add-On Instructions.</p> <p data-bbox="342 1667 581 1694">Lgx00113790, Lgx00113448</p>

Table 6 - Known Anomalies with Firmware Revision 19.11

Cat. No.	Description
1768-L43S, 1768-L45S	<p>The use of a safety tag with several multicast consuming controllers at varying firmware revisions can result in a connection timeout.</p> <p>If your application is configured with Compact GuardLogix controllers consuming safety tags produced by a Compact GuardLogix controller at revision 18.x, and the consuming controllers of one safety tag are at varying firmware revisions you may experience a connection timeout with error code 0x203. In the event of a connection timeout, all of the consuming controllers appear to connect to the tag and run for some time, but then the connection timeout occurs.</p> <p>If you use a single consumer of a safety tag, that consumer will connect and remain connected.</p> <p>To workaround this anomaly, set the revision of the producing controller to the same revision as the lowest revision of the consumers connecting to the safety tag. For example, if you have consuming Compact GuardLogix controllers at revisions 17.x and 18.x, set the producing controller to revision 17.x to match the lowest revision of the consumers.</p> <p>Lgx00104877</p>

Restrictions

These restrictions exist for firmware revision 19.11.

Restrictions with Firmware Revision 19.11

Cat. No.	Description				
1768-L43, 1768-L45, 1768-L43S, 1768-L45S	<p>The end cap must be attached to the CompactLogix system before you upgrade the controller or I/O module.</p> <p>Enabling the time synchronization feature of a CompactLogix controller results in the controller becoming the local master. It does not result in the controller becoming synchronized with other wall clock times in the system.</p> <p>If a 1769 I/O fault occurs, you must cycle power to the CompactLogix controller after clearing the major fault. I/O communication is not restored until after the power cycle. You should never use the fault handling routine to clear local I/O faults. You should clear local I/O faults manually on a per case basis, and then the controller should be power cycled.</p> <p>When you perform a Partial Import Online (PIO) of a function block routine that contains S-Curve function blocks across Logix platforms, set the .Initialize bit in the backing tag control structure of all S-Curve instructions. This configuration causes the S-Curve instructions to re-initialize themselves.</p> <p>Failure to set the .Initialize bit in the backing tag control structure of all S-Curve instructions, may cause the S-Curve function block to execute with uninitialized values.</p> <p>LgX114927, Lgx114935</p> <p>With RSLogix 5000 programming software, version 19 and controller firmware revision 19.11, the Fault/Program states for Compact I/O modules are not supported and cannot be configured by using the Module Configuration dialog box.</p> <p>Because the CompactLogix system does not provide support for local modules to use the alternate outputs, do not configure the attributes or tags listed below. These tags are still created when you add the I/O modules to the configuration.</p> <p>Attribute Tags to Avoid</p> <table> <tr> <th>For Digital Output Modules</th><th>For Analog Output Modules</th></tr> <tr> <td> <ul style="list-style-type: none"> ProgToFaultEn ProgMode ProgValue FaultMode FaultValue </td><td> <ul style="list-style-type: none"> CHxProgToFaultEn CHxProgMode CHxFaultMode Where CHx = the channel number </td></tr> </table>	For Digital Output Modules	For Analog Output Modules	<ul style="list-style-type: none"> ProgToFaultEn ProgMode ProgValue FaultMode FaultValue 	<ul style="list-style-type: none"> CHxProgToFaultEn CHxProgMode CHxFaultMode Where CHx = the channel number
For Digital Output Modules	For Analog Output Modules				
<ul style="list-style-type: none"> ProgToFaultEn ProgMode ProgValue FaultMode FaultValue 	<ul style="list-style-type: none"> CHxProgToFaultEn CHxProgMode CHxFaultMode Where CHx = the channel number 				

Restrictions with Firmware Revision 19.11

Cat. No.	Description
1768-L43S, 1768-L45S	<p>We recommend that you configure the Compact GuardLogix controller so that it becomes the CST master. To do so, select Enable Time Synchronization on the Date/Time tab of the Controller Properties dialog box. If you do not configure the Compact GuardLogix controller to become the CST master and your project uses safety tags that are produced, I/O faults can occur when the project is downloaded.</p> <p>For more information about enabling the Compact GuardLogix controller to become the CST master, see the Compact GuardLogix Controllers User Manual, publication 1768-UM002.</p> <p>Lgx00104194</p>

Install the Controller Revision

To download the latest controller firmware revision, go to <http://www.rockwellautomation.com/support/downloads> and select your desired revision. Then, use the ControlFLASH utility to upgrade your controller.

Alternatively, if you have installed RSLogix 5000 software, version 16, and related firmware, you may not need to complete the tasks described. The AutoFlash feature of RSLogix 5000 software detects if your controller firmware needs upgraded upon a program download to the controller. If a firmware upgrade is necessary, AutoFlash will initiate an update.

After you have completed your firmware upgrade, you should complete these steps to verify that the upgrade was successful.

1. Cycle power to the controller.
2. Go online with the controller and view controller properties.
3. Verify that the firmware revision listed matches the firmware to which you intended to upgrade.
4. If the controller's firmware is not correct, initiate another firmware upgrade.

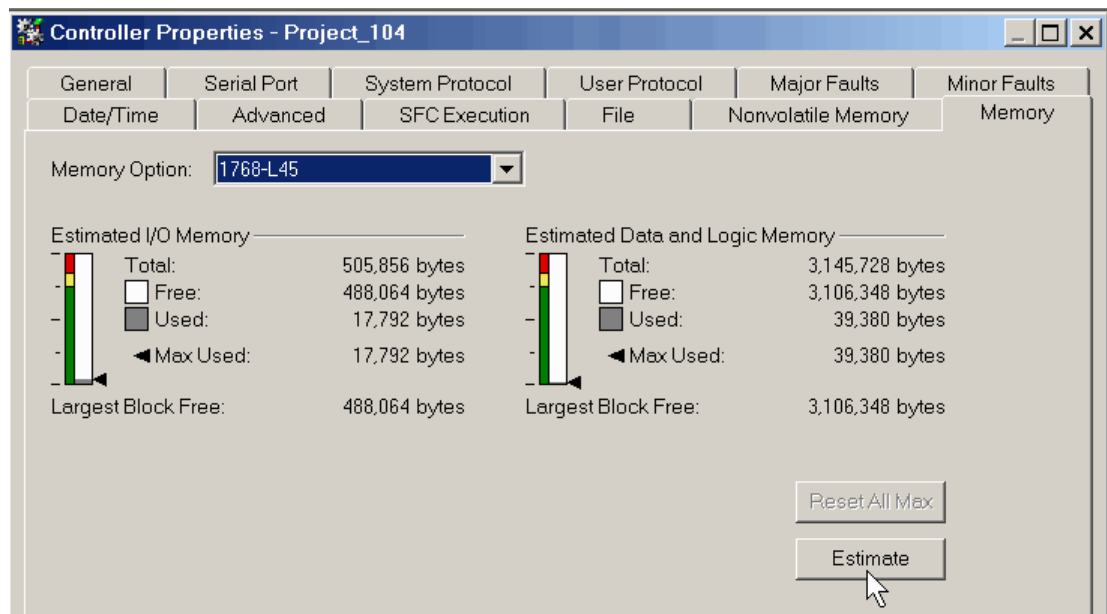
For more information about errors when completing a ControlFLASH upgrade, see the ControlFLASH Firmware Upgrade Kit Quick Start, publication [1756-QS105](#).

Additional Memory Requirements

This firmware revision may require more memory than previous revisions (for example, 10.x, 11.x). To estimate additional memory requirements for your application, you can either use the memory estimation tool provided with RSLogix 5000 software or the tables provided in these release notes.

Use the Estimate Tool

To estimate the amount of memory required by your application, convert the project to the controller revision desired and use the Estimate tool available in the Memory tab of the Controller Properties.



Estimate Based on Application Components

If you do not have the desired version of RSLogix 5000 software, use this table to estimate the additional memory that your project may require.

If you are upgrading your system through multiple firmware revisions, add all components your application uses for each of the revisions you upgrade through. For example, if you are upgrading from revision 15.x to revision 18.x, total your application components for revisions 15.x to 16.x, 16.x to 17.x, and 17.x to 18.x.

Table 7 - Additional Memory Requirements per Application Component

If you upgrade from revision (add all that apply)	Then add the following memory requirements to your project		Which comes from this type of memory	
	Component	Increase/Decrease Per Instance	I/O	Data and Logic
18.x to 19.x		<no change>		
17.x to 18.x	Program	+ 8 bytes		✓
	Equipment phase	+ 20 bytes		✓
	Add-On Instruction	+ 12 bytes		✓
	Each tag	+ 4 bytes		✓
	In addition, if you use a tag of the types listed below, increase the memory as indicated for each instance:			
	Produced tag	+ 36 bytes + (24 bytes * number of consumers)	✓	
	Consumed tag	+ 24 bytes	✓	
	Data access control	+ 4 bytes per symbol		✓
	Tag that uses ALARM_ANALOG data type	- 20 bytes		✓
	Tag that uses ALARM_DIGITAL data type	+ 28 bytes		✓
	Tag that uses MOTION_GROUP data type	+ 76		✓
	Tag that uses AXIS_SERVO_DRIVE or AXIS_GENERIC_DRIVE data type	+ 786 bytes		✓
	Tag that uses AXIS data type other than AXIS_SERVO_DRIVE or AXIS_GENERIC_DRIVE	+ 818 bytes		✓
	Tag that uses COORDINATE_SYSTEM data type with no transform dimensions	+ 40 bytes		✓
	Tag that uses COORDINATE_SYSTEM data type with transform dimensions	+ 100 bytes		✓
	Module input connection	+ 20 bytes		✓
	Module output connection	+ 24 bytes		✓
	Safety controller	- 8 bytes		✓
	Safety partner	- 8 bytes		✓

Table 7 - Additional Memory Requirements per Application Component

If you upgrade from revision (add all that apply)	Then add the following memory requirements to your project		Which comes from this type of memory	
	Component	Increase/Decrease Per Instance	I/O	Data and Logic
17.x to 18.x	For each controller (> 1K bytes change):			
	1756-L6x, 1756-L6xS, 1756-L63XT	+ 16728 bytes		✓
	1768-L4x, 1768-L4xS	+ 14448 bytes		✓
	1769-L2x	+ 35084 bytes	✓	
	1769-L31	+ 14740 bytes	✓	
	1769-L32C, 1756-L35CR	+ 35400 bytes	✓	
	1769-L32E, 1756-L35E	+ 35036 bytes	✓	
	1789-L10, 1789-L30, 1789-L60	+ 4992	✓	
16.x to 17.x	Task	+ 4 bytes		✓
	Program	+ 4 bytes		✓
	Equipment phase	+ 8 bytes		✓
	LD routine	+ 12 bytes		✓
	FBD routine	- 8 bytes		✓
	SFC routine	+ 28 bytes		✓
	ST routine	+ 4 bytes		✓
	Add-On Instruction	- 12 bytes		✓
	If you use a tag of the types listed below, increase the memory as indicated for each instance:			
	Produced tag	+ [4 bytes + (4 bytes * number of consumers)]	✓	
	Consumed tag	+ 8 bytes	✓	
	Tag that uses MESSAGE data type	+ 4 bytes		✓
	Tag that uses ALARM_ANALOG data type	- 64 bytes		✓
	Tag that uses ALARM_DIGITAL data type	- 28 bytes		✓
	Tag that uses AXIS_SERVO_DRIVE or AXIS_GENERIC_DRIVE data type	- 34 bytes (2 bytes x number of output cam execution targets)		✓
	Tag that uses AXIS data type other than AXIS_SERVO_DRIVE or AXIS_GENERIC_DRIVE	- 52 bytes (2 bytes x number of output cam execution targets)		✓
	Tag that uses COORDINATE_SYSTEM data type of 2 dimensions with 2 transform dimensions	+ 20 bytes		✓
	Tag that uses COORDINATE_SYSTEM data type of 3 dimensions with 3 transform dimensions	+ 108 bytes		✓

Table 7 - Additional Memory Requirements per Application Component

If you upgrade from revision (add all that apply)	Then add the following memory requirements to your project		Which comes from this type of memory	
	Component	Increase/Decrease Per Instance	I/O	Data and Logic
15.x to 16.x	If you use a tag of the types listed below, increase the memory as indicated for each instance:			
	Tag that uses ALARM_ANALOG data type (with no associated tag references)	+ 16 bytes		✓
	Tag that uses ALARM_DIGITAL data type (with no associated tag references)	+ 4 bytes		✓
	Tag that uses ALARM_ANALOG data type (if associated tags are configured for the ALARM_ANALOG tag)	+ 22 bytes + (9 x the number of configured, associated tags) + (3 x the sum of the bytes used by the data type of each of the configured associated tags) For example, an analog alarm moved to V16.03 with two Associated Tags – one DINT (4 bytes) and one STRING (88 bytes) would need to add: $22 + 9(2) + 3(92) = 316$ bytes		✓
	Tag that uses the COORDINATE_SYSTEM data type	+ 132 bytes		✓
14.x to 15.x	Input module	+ 4 bytes	✓	
	If you use a tag of the types listed below, increase the memory as indicated for each instance:			
	Produced tag	+ 12 bytes	✓	
	Consumed tag	+ 4 bytes	✓	
	Tag that uses COORDINATE_SYSTEM data type	+ 748 bytes		✓
	Tag the uses any AXIS data type	+ 800 bytes		✓
	Task	+ 20 bytes		✓
	Program or equipment phase	+ 24 bytes		✓
	Routine	+ 4 bytes		✓
	Serial port	+ 1120 bytes		✓
	Project	+ 4012 bytes		✓

Table 7 - Additional Memory Requirements per Application Component

If you upgrade from revision (add all that apply)	Then add the following memory requirements to your project		Which comes from this type of memory	
	Component	Increase/Decrease Per Instance	I/O	Data and Logic
13.x to 14.x	If you use a tag of the types listed below, increase the memory as indicated for each instance:			
	Tag that uses the COORDINATE SYSTEM data type	+ 60 bytes		✓
	Tag that uses any AXIS data type	+ 4 bytes		✓
12.x to 13.x	Program	+ 12 bytes		✓
	Task	+ 4 bytes		✓
	User-defined data type	+ 4 bytes		✓
	I/O module	+ 16 bytes	✓ (8 bytes)	✓ (8 bytes)
	If you use a tag of the types listed below, increase the memory as indicated for each instance:			
	Produced tag	+ 8 bytes	✓	
	Consumed tag	+ 8 bytes	✓	
11.x to 12.x	I/O module with a comm format = Rack Optimization	+ 90 bytes		✓
	I/O module with a comm format = something other than Rack Optimization (such as a direct connection)	+ 144 bytes		✓
	CompactLogix 1769 I/O module	+ 170 bytes		✓
	Bridge module with a comm format = None	+ 160 bytes		✓
	Bridge module with a comm format = Rack Optimization	+ 220 bytes		✓
10.x to 11.x	User-defined data type <ul style="list-style-type: none"> Number of user-defined data types in the controller organizer > Data Types folder > User-Defined folder Not the use of that data type in tags 	+ 128 bytes		✓
	Indirect address (using a tag as the subscript for an array in an instruction, such as an Array_A[Tag_B]). This memory change applies only if the array: <ul style="list-style-type: none"> uses a structure as its data type does not use one of these data types: CONTROL, COUNTER, PID, or TIMER has only one dimension (such as UDT_1[5]) 	- 60 bytes		✓
9.x to 10.x	Program	+ 12 bytes		✓
	Routine	+ 16 bytes		✓

Table 7 - Additional Memory Requirements per Application Component

If you upgrade from revision (add all that apply)	Then add the following memory requirements to your project			Which comes from this type of memory	
	Component	Increase/Decrease Per Instance	I/O	Data and Logic	
8.x to 9.x	If you use a tag of the types listed below, increase the memory as indicated for each instance:				
	Tag that uses the MESSAGE data type	+ 376 bytes			✓
7.x to 8.x	Project	+ 1050 bytes	✓		
	Tag	+ 0.55 bytes			✓
	Message that transfers more than 500 bytes of data and targets a controller in the same chassis This memory is allocated only when the MSG instruction is enabled. To estimate, count the number of these messages that are enabled and/or cached at one time	+ 2000 bytes	✓		
6.x to 7.x	If you use a tag of the types listed below, increase the memory as indicated for each instance:				
	Base tag	+ 24 bytes			✓
	Alias tag	+ 16 bytes			✓
	Produced tag	DINT 4	+ 12 bytes	✓	
		REAL 4	+ 12 bytes	✓	
	Consumed tag	DINT 4	+ 12 bytes		
		REAL 4	+ 12 bytes		
	Routine	+ 68 bytes			✓
5.x to 6.x	Routine	+ 116 bytes			✓

Additional Resources

These documents contain additional information.

Resource	Description
Logix5000 Controllers Common Procedures Reference Manual, publication 1756-PM001	Contains information specific to procedures related to programming your controller.
1768 CompactLogix Controllers, Revision 17 Release Notes, publication 1768-RN017	Describes anomalies and enhancements related to controller revision 17.
1768 CompactLogix Controllers, Revision 18 Release Notes, publication 1768-RN018	Describes anomalies and enhancements related to controller revision 18.
Logix5000 Controllers Execution Time and Memory Use Reference Manual, publication 1756-RM087	Provides calculations of execution times and memory use for Logix5000 controllers.
ControlFLASH Firmware Upgrade Kit Quick Start, publication 1756-QS105	Contains informations about upgrading firmware and related error messages.

You can view or download Rockwell Automation publications at <http://www.rockwellautomation.com/literature>. To order paper copies of technical documentation, contact your local Rockwell Automation distributor or sales representative.

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If you experience a problem within the first 24 hours of installation, review the information that is contained in this manual. You can contact Customer Support for initial help in getting your product up and running.

United States or Canada	1.440.646.3434
Outside United States or Canada	Use the Worldwide Locator at http://www.rockwellautomation.com/support/americas/phone_en.html , or contact your local Rockwell Automation representative.

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