

INTERNATIONAL STANDARD

NORME INTERNATIONALE



**Adjustable speed electrical power drive systems –
Part 7-203: Generic interface and use of profiles for power drive systems –
Profile type 3 specification**

**Entraînements électriques de puissance à vitesse variable –
Partie 7-203: Interface générique et utilisation de profils pour les entraînements
électriques de puissance – Spécification du profil de type 3**

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INTERNATIONAL
ELECTROTECHNICAL
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ELECTROTECHNIQUE
INTERNATIONALE

PRICE CODE **XH**
CODE PRIX

ICS 29.200; 35.100.05

ISBN 978-2-83220-710-9

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INTERNATIONAL ELECTROTECHNICAL COMMISSION

ADJUSTABLE SPEED ELECTRICAL POWER DRIVE SYSTEMS –

**Part 7-203: Generic interface and use
of profiles for power drive systems –
Profile type 3 specification**

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This bilingual version (2013-04) corresponds to the monolingual English version, published in 2007-11.

The text of this standard is based on the following documents:

FDIS	Report on voting
22G/184/FDIS	22G/192/RVD

Full information on the voting for the approval of this standard can be found in the report on voting indicated in the above table.

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INTRODUCTION

The IEC 61800 series is intended to provide a common set of specifications for adjustable speed electrical power drive systems.

IEC 61800-7 describes a generic interface between control systems and power drive systems. This interface can be embedded in the control system. The control system itself can also be located in the drive (sometimes known as "smart drive" or "intelligent drive").

A variety of physical interfaces is available (analogue and digital inputs and outputs, serial and parallel interfaces, fieldbuses and networks). Profiles based on specific physical interfaces are already defined for some application areas (e.g. motion control) and some device classes (e.g. standard drives, positioner). The implementations of the associated drivers and application programmers interfaces are proprietary and vary widely.

IEC 61800-7 defines a set of common drive control functions, parameters, and state machines or description of sequences of operation to be mapped to the profiles.

IEC 61800-7 provides a way to access functions and data of a drive that is independent of the used drive profile and communication interface. The objective is a common drive model with generic functions and objects suitable to be mapped on different communication interfaces. This makes it possible to provide common implementations of motion control (or velocity control or drive control applications) in controllers without any specific knowledge of the drive implementation.

There are several reasons to define a generic interface.

For a drive device manufacturer

- Less effort to support system integrators
- Less effort to describe drive functions because of common terminology
- The selection of drives does not depend on availability of specific support

For a control device manufacturer

- No influence of bus technology
- Easy device integration
- Independent of a drive supplier

For a system integrator (builds modules, machines, plants etc.)

- Less integration effort for devices
- Only one understandable way of modeling
- Independent of bus technology

Much effort is needed to design a motion control application with several different drives and a specific control system. The tasks to implement the system software and to understand the functional description of the individual components may exhaust the project resources. In some cases, the drives do not share the same physical interface. Some control devices just support a single interface which will not be supported by a specific drive. On the other hand, the functions and data structures are specified with incompatibilities. It is up to the systems integrator to write interfaces to the application software to handle that which should not be his responsibility.

Some applications need device exchangeability or integration of new devices in an existing configuration. They are faced with different incompatible solutions. The efforts to adopt a solution to a drive profile and to manufacturer specific extensions may be unacceptable. This will reduce the degree of freedom to select a device best suited for this application to the selection of the unit which will be available for a specific physical interface and supported by the controller.