



**Note 1:**

The information in this manual relates to:

HART firmware version V105.

HART DD Files versions, Device Revision 2 (DEV\_REV 2) and Device Description File revision 3 (DD\_REV 3).

**Note 2:**

The HART module described in this manual is suitable for inclusion in the following Rotork actuators:

CVA range (CVL linear, CVQ quarter-turn)

IQ3 range 3rd generation (IQ3 multi-turn, IQT3 part-turn)

IQ3 Pro range (IQ3 Pro multi-turn, IQT3 Pro part-turn)

CMA range (CML linear, CMQ quarter-turn, CMR rotary)

CK range (Atronik and Centronik control options – see note 4 below)

SI3 and SI4 range

**Note 3:**

For simplicity, IQ3 range 3rd generation and IQ3 Pro range products are referenced within this document as IQ.

**Note 4:**

There are two models of the CK range actuator that can use the HART Network; Those specified or fitted with Atronik or Centronik control modules. These are Atronik (CKA, CKRA) and Centronik (CKC, CKRC, CKQC) models. These models are interchangeable when talking about HART: this manual refers to all of them as 'CK' actuators. Atronik and Centronik are terms applied to a CK actuator that has an optional electronic control system in it. This is required for HART use.

The CK can be fitted with either a DSM (Digital Switching Mechanism) or a MSM (Mechanical Switching Mechanism). The DSM can report analogue torque values (0-120%) and position (0-100%). The MSM will only report torque as minimum (0%) or maximum (tripped), it does not report any intermediate values. It also only reports position as fully closed, fully open or intermediate (mid-travel).

There is an optional potentiometer that can be fitted to the MSM which allows it to report position (0-100%), which means that the position features can be used, however, this does not include the torque.

The optional potentiometer must be fitted for full HART functionality.

If there is any uncertainty about what the model is, please consult the wiring diagram which will show which option is fitted.

## Contents

---

<b>1. Introduction</b> .....	<b>5</b>
1.1 Scope.....	5
1.2 Purpose.....	5
1.3 Who should use this document?.....	5
1.4 Abbreviations and definitions .....	5
<b>2. Product Overview</b> .....	<b>6</b>
2.1 General.....	6
2.2 Mechanical Properties.....	6
<b>3. Connections and Setup</b> .....	<b>7</b>
<b>4. Analogue Control Signal</b> .....	<b>8</b>
4.1 Analogue Control Signal Loss .....	8
<b>5. Device Variables</b> .....	<b>9</b>
5.1 Device Variable 0 Loop current .....	9
5.2 Device Variable 1 Demand .....	9
5.3 Device Variable 2 Position .....	9
5.4 Device Variable 3 Thrust or torque.....	9
5.5 Device Variable 4 Position within factory limits.....	9
5.6 Dynamic Variables.....	9
<b>6. Status Information</b> .....	<b>10</b>
6.1 Field Device Status .....	10
6.2 Extended Device Status (IQ and CMA ONLY) .....	10
6.3 Command 48 Additional Device Status – CVA.....	11
6.4 Command 48 Additional Device Status – IQ .....	12
6.5 Command 48 Additional Device Status – CMA.....	13
6.6 Command 48 Additional Device Status – CK .....	14
6.7 Command 48 Additional Device Status – SI .....	15
<b>7. Universal Commands</b> .....	<b>16</b>
<b>8. Common-practice Commands</b> .....	<b>17</b>
8.1 Supported Commands .....	17
8.2 Unsupported Features.....	18
<b>9. Device-specific Commands</b> .....	<b>19</b>
9.1 Command 128 Read Software Version .....	19
9.2 Command 129 Read Status Bits Version (CVA ONLY) .....	20
9.3 Command 131 Read Current Zero & Span .....	21
9.4 Command 132 Control digitally .....	21
9.5 Command 133 HART Control Mode .....	22
9.6 Command 134 Write Relay Control (IQ and CMA ONLY).....	23
<b>10. DD File, Emerson Handheld Tool Screen Shots – Common Screens</b> .....	<b>24</b>
10.1 Setup .....	24
10.2 Diagnostics .....	26
10.3 Pos / Demand chart .....	29
<b>11. DD File, Emerson Handheld Tool Screen Shots – CVA</b> .....	<b>30</b>
11.1 Top Menu .....	30
11.2 Stroke setup .....	31
11.3 Setup .....	33
11.4 Diagnostics .....	37
<b>12. DD File, Emerson Handheld Tools Screen Shots – IQ</b> .....	<b>39</b>
12.1 Top Menu .....	39
12.2 Setup .....	40
12.3 Diagnostics .....	48
12.4 Control .....	54

## Contents

---

13. DD File, Emerson Handheld Tools Screen Shots – CMA .....	58
13.1 Top Menu .....	58
13.2 Setup .....	59
13.3 Diagnostics .....	63
13.4 Control .....	68
14. DD File, Emerson Handheld Tools Screen Shots – CK .....	72
14.1 Top Menu .....	72
14.2 Setup .....	73
14.3 Diagnostics .....	82
14.4 Control .....	89
14.5 Pos / Demand Chart.....	92
15. DD File, Emerson Handheld Tools Screen Shots – SI .....	93
15.1 Top Menu .....	93
15.2 Setup .....	94
15.3 Diagnostics .....	102
15.4 Control .....	108

### List of Tables

1 Analogue input characteristics.....	8
2 Device Variables .....	9
3 Dynamic Variables.....	9
4 Field Device Status bits .....	10
5 Extended Device bits (IQ and CMA ONLY) .....	10
6 CVA: Alarm status bits .....	11
7 CVA: Digital status bits.....	11
8 HART board: Alarm status bits – IQ.....	12
9 HART board: Alarm status bits – CMA.....	13
10 HART board: Alarm status bits – CK .....	14
11 HART board: Alarm status bits – SI .....	15
12 Universal command list.....	16
13 Supported common-practice commands .....	17
14 Device-specific commands.....	19
15 Actuator Status Register .....	20
16 ACTCON Register.....	21
17 HART control mode enumeration Register .....	22
18 HART Relay Control Register.....	23
19 NE107 Diagnostics Bits, Setup – IQ.....	43
20 NE107 Diagnostics Bits, Example setup – IQ.....	44
21 NE107 Diagnostics Bits, Setup – CMA .....	61
22 NE107 Diagnostics Bits, Setup – CK.....	77
23 NE107 Diagnostics Bits, Example setup – CK .....	78
24 NE107 Diagnostics Bits, Setup – SI.....	97
25 NE107 Diagnostics Bits, Example setup – SI .....	98

### List of Appendices

1 Capability Checklist.....	112
2 Default Configuration .....	112
3 Device Identification.....	112
4 General HART Protocol Summary .....	113

## 1. Introduction

---

### 1.1 Scope

The Rotork actuator HART Field Unit (HFU), device Revision 2, complies with HART Protocol Revision 7.1. This document specifies all the device specific features and documents for the HART Protocol implementation details (for example, the Engineering Unit Codes supported). Field Device functionality is described sufficiently to allow proper application in a process and complete support for HART capable Host Applications.

### 1.2 Purpose

This specification is designed to complement other documentation by providing a complete, unambiguous description of a Field Device from a HART Communication perspective.

### 1.3 Who should use this document?

The specification is designed to be a technical reference for HART capable Host Application Developers, System Integrators and knowledgeable End Users. It also provides functional specifications (for example, commands, enumerations and performance requirements) used during Field Device development, maintenance and testing. This document assumes the reader is familiar with HART Protocol requirements and terminology.

### 1.4 Abbreviations and definitions

<b>ACTCON</b>	Actuator Control
<b>ADC</b>	Analogue to Digital Converter
<b>BD</b>	Back Drive
<b>DD</b>	Device Description
<b>DCS</b>	Distributed Control System
<b>DTM</b>	Device Type Manager
<b>EE</b>	EEPROM
<b>FSK</b>	Frequency Shift Keying
<b>HART</b>	Highway Addressable Remote Terminal
<b>HFU</b>	HART Field Unit
<b>LRV</b>	Lower Range Value
<b>NaN</b>	Not a Number
<b>PDA</b>	Personal Digital Assistant
<b>PV</b>	Primary Variable
<b>QV</b>	Quaternary Variable
<b>SV</b>	Secondary Variable
<b>TV</b>	Tertiary Variable
<b>URV</b>	Upper Range Value

## 2. Product Overview

### 2.1 General

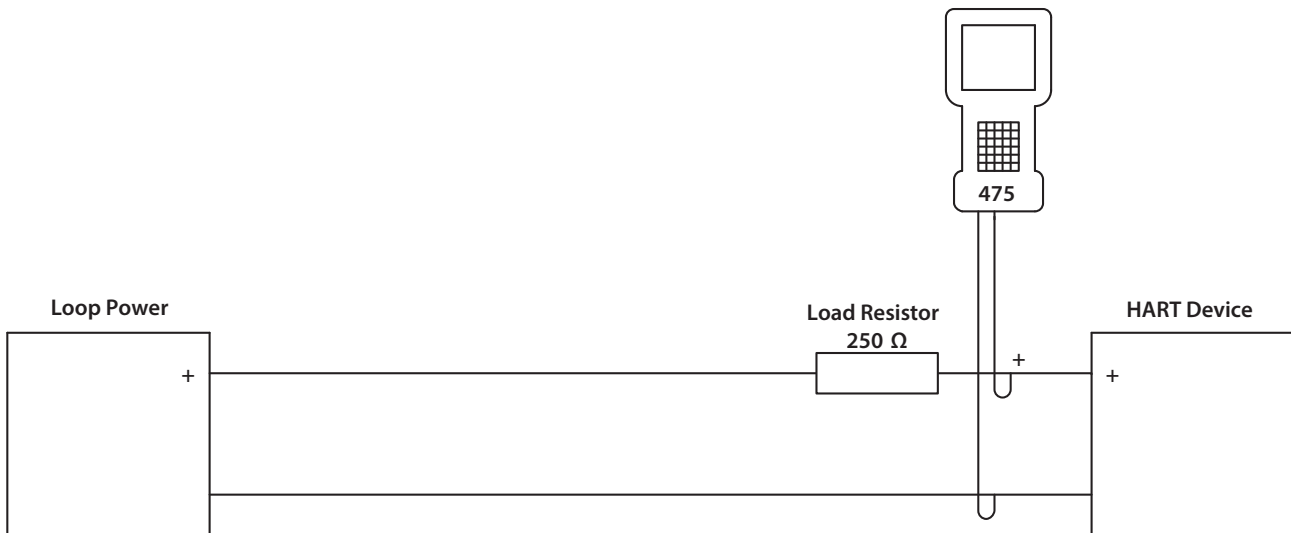
The Rotork actuator HFU enables communication and control of Rotork actuators from a suitable host system with HART capability. Standard shielded twisted pair cable is used to connect the actuators to the host in either point-to-point or multidrop network configurations.

The HFU may be fitted into Rotork CK, CMA, CVA, IQ and SI range actuators. The HFU board is installed within the actuator enclosure and forms an integral part of the actuator. The HFU circuitry does not impinge on the actuator control electronics. The actuator itself remains fully self-protecting. The HFU performs the tasks of network interface, actuator data collection and the issuing of some actuator commands.

Except for CMA range and CKA actuators, there should be no need to open the electrical housing of the actuator once it leaves the factory. For the CVA range, all actuator adjustments and configuration settings may be made using Rotork Enlight PC software or Insight 2 PC software. For the CK, IQ and SI ranges, all actuator adjustments and configuration settings may be made using Rotork Insight 2 PC software or via the actuator HMI using a Rotork setting tool. Software (Enlight and Insight 2) can be downloaded from the Rotork web site. For the CMA, configuration is via the built-in HMI, accessed by removing the cover. Some actuator settings and the HART specific settings of the HFU board may be done over the data highway using a suitable tool, such as an Emerson Handheld tool.

In normal operation, the HFU is controlled by the analogue demand signal, but it can also be controlled by the HART digital signal. Control commands must come from the HART network, generated by a master controller. The actuator behaves as a slave device to this controller. Device Description (DD) Files for the HFU are available on the Rotork web site.

A typical HART configuration system, with a handheld tool is shown below.



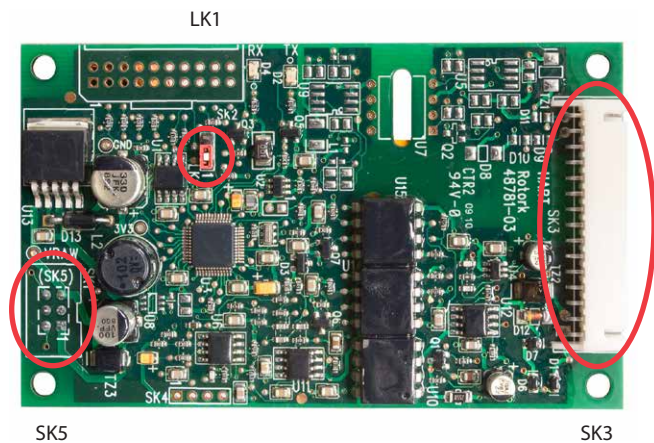
### 2.2 Mechanical Properties

The HFU board is a single printed circuit board connected to the main actuator printed circuit board. It is securely fixed in place with four screws, one in each corner.

Electrical connection to the network is through SK3, pins 1 and 2, at the top of the picture.

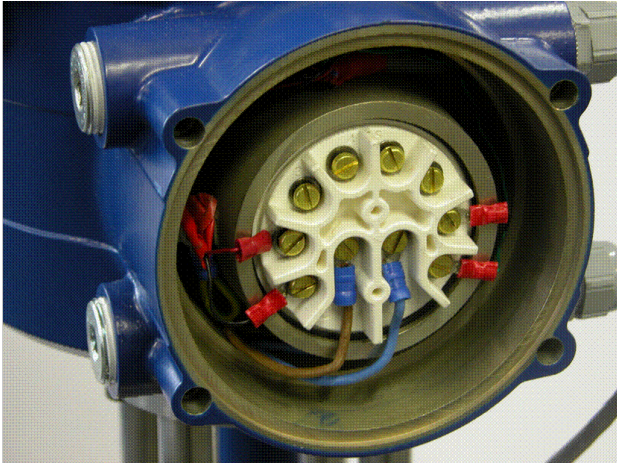
Electrical connection to the main board is through SK5, at the bottom of the picture (fitted to the underside of the PCB).

There is one removable link, LK1, which should be left in the position shown opposite.



### 3. Connections and Setup

---



Network connections are made to the terminals of the actuator. Shown above is a typical arrangement for a CVA range actuator. HART is connected to terminals 1 and 2. Always check the actuator wiring diagram for correct terminal numbering and connection polarity.

Installation and maintenance instructions are provided with every actuator and are also available on the Rotork website using the following references:

- PUB002-039 for IQ
- PUB002-065 for IQT
- PUB042-003 for CVA linear (CVL)
- PUB042-004 for CVA quarter-turn (CVQ)
- PUB094-009 for CMA
- PUB094-019 for CMA linear (CML-1500/3000)
- PUB111-005 for CKc Centronik
- PUB021-057 for SI3 and SI4

Please contact Rotork for assistance with HART module setup on CK<sub>A</sub> Atronik actuators.

Only the HART loop 0% and 100% values can be configured using the standard actuator commissioning tools. The other HFU settings must be made through the network cabling, using a HART master, a configuration tool like the Emerson 475 or by using a generic DTM.

## 4. Analogue Control Signal

The Primary Variable (PV) is the actuator's demand position, measured in percent, and is derived from the loop current. Its range is 0% to 100%.

Table 1 – Analogue input characteristics

	Direction	Values (percent of range)	Values
Linear over-range	Down	-3.125 ± 0.1%	3.5 ± 0.01 mA
	Up	+3.125 ± 0.1%	20.5 ± 0.01 mA
Maximum current			23 mA
Multi-Drop current draw			4.0 mA
Lift-off voltage (voltage required at 20.5 mA)			11 V
Effective input resistance*			280 Ω
Capacitance number (terminal to terminal & case capacitance × 5000 pF)			0.6 max

\* The effective input resistance is calculated as the slope of a voltage vs loop current graph, across the input range of the device. It is not simply V/I, as the device has a theoretical voltage offset of 5.4 V at zero current.

### 4.1 Analogue Control Signal Loss

For a demand input of 4 mA down to 2 mA (this level is not adjustable), the HART card will send a 0% set point command to the Actuator. If the signal drops below 2 mA, after about 1 second, the HART card sends a loss of comms indication to the Actuator. This begins the Actuator Loss of comms timeout timer. When it expires, the configured loss of comms action is initiated. The timeout and action to take are set in the appropriate Actuator settings. If the analogue signal is reapplied (i.e. above 2 mA), the actuator will follow the analogue signal again. Signal / Comms loss only applies to the analogue control signal and not the digital signals.



## 5. Device Variables

The Device Variables are the loop current and the four Dynamic Variables.

Table 2 – Device Variables

Number	Name	Classification	Units
0	Loop current	Current	mA
1	Demand	Analytical	%
2	Position	Analytical	%
3	Thrust or torque, pressure for SI3 and SI4	Analytical	%
4	Position within factory limits	Analytical	%

### 5.1 Device Variable 0 Loop current

The loop current, measured in milliamps. This is calibrated at the factory, but may be recalibrated by the user using Commands 45 and 46.

### 5.2 Device Variable 1 Demand

The actuator position demand, measured in percent, and derived from the loop current. This value is relative to the user limits, and so is dependent on the LRV and URV.

It can be set, allowing manual control of the actuator, by Command 79.

### 5.3 Device Variable 2 Position

The present position of the actuator, measured in percent. This uses the same user-defined range as the demand.

### 5.4 Device Variable 3 Thrust or torque

The actuator thrust (for a linear actuator) or torque (for a quarter-turn, part-turn or multi-turn actuator), measured as a percent of rated thrust or torque.

### 5.5 Device Variable 4 Position within factory limits

This value, measured in percent, indicates the position of the actuator within its full mechanical stroke, determined at the factory. This is only used to set the actuator's limits, and is not available during normal operation.

Command 79 can be used to set this value, allowing the actuator to be moved anywhere within its physical limits. When in this mode, the normal demand (Device Variable 1) will be unavailable; position will continue to show the normal position, not the position within factory limits.

### 5.6 Dynamic Variables

Four Dynamic Variables are implemented, with a fixed mapping to the Device Variables shown below:

Table 3 – Dynamic Variables

	Device Variable number	Meaning
PV	1	Demand
SV	2	Position
TV	3	Thrust or Torque, pressure for SI3 and SI4
QV	4	Position within factory limits (for IQ this is identical to PV)

## 6. Status Information

### 6.1 Field Device Status

The functions of the Field Device Status bits are specified in HCF\_SPEC-99. Further details of their implementation are described in Table 4.

Table 4 – Field Device Status bits

Bit	Name	Notes
7	Device Malfunction	Set on loss of communication with the main board, or on IQ and CMA – when an NE107 failure is triggered
6	Configuration Changed	Set if changes are made to device configuration
5	Cold Start	Set when initially powered-up
4	More Status Available	Set if any Additional Device Status bit is set, or on IQ and CMA - if any of the NE107 diagnostic flags are triggered
3	Loop Current Fixed	Set by Command 40
2	Loop Current Saturated	Set if current goes 0.5 mA outside limits (see Table 1)
1	Non-PV Out of Limits	Not used
0	PV Out of Limits	Set if PV (demand) goes 3.125% outside limits

### 6.2 Extended Device Status (IQ and CMA ONLY)

The functions of the Extended Device Status bits are specified in HCF\_SPEC-127. Further details of their implementation are described in Table 5.

Table 5 – Extended Device bits (IQ and CMA ONLY)

Bit	Name	Notes
7-6	Unused	Unused
5	NE107 Function Check	This bit is set if the status has occurred and the NE107 Function Check mask is set in the actuator
4	NE107 Out of Specification	This bit is set if the status has occurred and the NE107 Out of Specification mask is set in the actuator
3	NE107 Failure	This bit is set if the status has occurred and the NE107 Failure mask is set in the actuator
2	Critical Power Failure	Unused
1	Device Variable Alert	Unused
0	NE107 Maintenance Required	This bit is set if the status has occurred and the NE107 Maintenance Required mask is set in the actuator

## 6. Status Information *continued*

### 6.3 Command 48 Additional Device Status – CVA

Command 48 returns up to 6 bytes of device-specific data. The meaning of the bits in bytes is defined in Tables 6 and 7.

All bits in Bytes 0-3 are for errors only, and are continually updated. Accordingly, if any bit is set, the More Status Available bit (bit 4) of the Field Device Status is set; if all of the error bits are clear (zero), then the More Status Available Bit will be clear too.

Bytes 4-5 are status bits which are useful for diagnostic purposes, these bits being set will not cause the More Status Available bit (bit 4) of the Field Device Status to be set.

The More Status Available bit can also be cleared by reading Command 48 and writing the data back using Command 48. If that is done, any new Additional Device Status bit being set will cause the More Status Available bit to be set.

During normal operation, all bits should be zero. All unused bits are set to zero. Extended Device Status bits are not used, so are not affected by any of these bits.

*Table 6 – CVA: Alarm status bits*

Byte	Bit	Meaning
0	0	Motor Hall sensor: invalid data
	1	Motor Hall sensor: unknown
	2	Thermostat trip
	3	Knob position error
	4	Actuator type unknown
	5	Configuration error
	6	Over back-drive limit: open
1	0	Motor sensor: communications failure
	1	Motor sensor: unknown
	2	Position sensor: magnet failure
	3	Position sensor: communications failure
	4	Position sensor: unknown
	5	Force sensor: out of range
	6	Force sensor: communications failure
7	Force sensor: unknown	
2	0-7	Reserved
3	0	Motor sensor: magnet failure
	1	UPS error
	2	Configuration defaults error
	3	Valve obstruction: opening
	4	Valve obstruction: closing
	5	Actuator stalled
	6	Control Knob in Stop position
7	Control Knob in Test position	

*Table 7 – CVA: Digital status bits*

Byte	Bit	Meaning
4	0	Main board not responding
	1	Close Position Limit
	2	Open Position Limit
	3	Valve Running Close
	4	Valve Running Open
	5	Selector in Run
	6	Selector in Stop (offline)
5	7	Control by Enlight
	0	Actuator Moving
	1	Manual Movement
	2-7	Reserved

## 6. Status Information *continued*

### 6.4 Command 48 Additional Device Status – IQ

Command 48 returns up to 6 bytes of device-specific data. The meaning of the bits in bytes is defined in Table 8.

Bytes 0-3 are for errors only, and are continually updated. Accordingly, if any of these bits are set and the appropriate Namur mask bit is also set to a category (see Section Setup: NE107 Setup), the More Status Available bit (bit 4) of the Field Device Status is set; if all of these error bits are clear (zero), then the More Status Available Bit will be clear too.

During normal operation, all bits should be zero. All unused bits are set to zero. Extended Device Status bits are not used, so are not affected by any of these bits.

Bytes 4-5 are status bits which are useful for diagnostic purposes, these bits being set will not cause the More Status Available bit (bit 4) of the Field Device Status to be set.

The More Status Available bit can be cleared by reading Command 48 and writing the data back using Command 48. If that is done, any new Additional Device Status bit being set will cause the More Status Available bit to be set.

*Table 8 – HART board: Alarm status bits – IQ*

Byte	Bit	Meaning
0	0	Battery low
	1	Local control fault
	2	Power supply fault
	3	Thermostat tripped
	4	Contactors operations high
	5	Service Required
	6	High High Torque level exceeded
1	0	Valve obstructed
	1	Maximum output turns limit set reached
	2	Remote operation unavailable
	3	Control signal present
	4	Actuator inhibited
	5	Network communications lost
	6	Option configuration fault
2	0	Motor starts limit set exceeded
	1	Actuator stalled
	2	Positioner fault
	3	End timer expired
	4	Network fault
	5	Output supply fault
	6	Valve time exceeded
3	0-7	Reserved
4	0	Actuator moving
	1	Close position limit
	2	Open position limit
	3	Valve running close
	4	Valve running open
	5	Selector in remote
	6	Selector in local stop
5	0	Manual movement of hand wheel
	1	Partial stroke in progress
	2	Main board communications loss
	3	Reserved
	4	Digital input 1 status
	5	Digital input 2 status
	6	Digital input 3 status
7	Digital input 4 status	

## 6. Status Information *continued*

### 6.5 Command 48 Additional Device Status – CMA

Command 48 returns up to 6 bytes of device-specific data. The meaning of the bits in bytes is defined in Table 9.

Bytes 0-3 are for errors only, and are continually updated. Accordingly, if any of these bits are set and the appropriate Namur mask bit is also set to a category (see Section Setup: NE107 Setup), the More Status Available bit (bit 4) of the Field Device Status is set; if all of these error bits are clear (zero), then the More Status Available Bit will be clear too.

During normal operation, all bits should be zero. All unused bits are set to zero. Extended Device Status bits are not used, so are not affected by any of these bits.

Bytes 4-5 are status bits which are useful for diagnostic purposes, these bits being set will **not** cause the More Status Available bit (bit 4) of the Field Device Status to be set.

The More Status Available bit can be cleared by reading Command 48 and writing the data back using Command 48. If that is done, any new Additional Device Status bit being set will cause the More Status Available bit to be set.

Table 9 – HART board: Alarm status bits – CMA

Byte	Bit	Meaning
0	0	General Fault
	1	Loss Of Demand
	2	Loss Of Feedback
	3	Stall Open
	4	Stall Close
	5	Over Torque Open
	6	Over Torque Close
	7	Over Temperature
1	0	Comms Lost
	1	Critical Fault
	2	Monitor Relay
	3	Factory EE fault
	4	Customer EE fault
	5	Current EE fault
	6	Local Mode
	7	Close Limit
2	0	Open Limit
	1	Stop Selected (at actuator)
	2	Remote Selected (at actuator)
	3	Local Selected (at actuator)
	4	ESD Active
	5	Relay 1 Energized
	6	Relay 2 Energized
	7	Relay 5 Energized
3	0	Relay 6 Energized
	1	Relay 7 Energized
	2	Relay 8 Energized
	3	Digital Input 1
	4	Digital Input 2
	5	Digital Input 3
	6	Digital Input 4
	7	Non-Critical Fault
4	0	Actuator Moving
	1	Close position limit
	2	Open position limit
	3	Valve running close
	4	Valve running open
	5	Selector in remote
	6	Selector in local stop
	7	Selector in local
5	0-7	Reserved

## 6. Status Information *continued*

### 6.6 Command 48 Additional Device Status – CK

Command 48 returns up to 6 bytes of device-specific data. The meaning of the bits in bytes is defined in Table 10.

Bytes 0-3 are for errors only, and are continually updated. Accordingly, if any of these bits are set and the appropriate Namur mask bit is also set to a category (see section Setup: NE107 Setup), the More Status Available bit (bit 4) of the Field Device Status is set; if all of these error bits are clear (zero), then the More Status Available Bit will be clear too.

During normal operation, all bits should be zero. All unused bits are set to zero. Extended Device Status bits are not used, so are not affected by any of these bits.

Bytes 4-5 are status bits which are useful for diagnostic purposes, these bits being set will **not** cause the More Status Available bit (bit 4) of the Field Device Status to be set.

The More Status Available bit can be cleared by reading command 48 and writing the data back using command 48. If that is done, any new Additional Device Status bit being set will cause the More Status Available bit to be set.

Table 10 – HART board: Alarm status bits – CK

Byte	Bit	Meaning
0	0	Reserved
	1	Local Control Fault
	2	Power Fault
	3	Thermostat Tripped
	4	Reserved
	5	Reserved
	6	Hi Hi Trip Service Alarm (Hi Hi Torque level exceeded)
	7	Hi Trip Service Alarm (Hi Torque level exceeded)
1	0	Valve Error
	1	Reserved
	2	Monitor Relay
	3	Control Fail
	4	Actuator Fail
	5	Communications Fail
	6	Hardware Option Fail
	7	Partial Stroke Error
2	0	Reserved
	1	Actuator Stalled
	2	DSM Service Required
	3	End of Travel Timer (expired)
	4	Fieldbus Fault
	5	24VDC Customer Supply Fail
	6	Reserved
	7	Wrong Direction
3	0-7	Reserved
4	0	Output Moving
	1	Close Limit Switch active
	2	Open Limit Switch active
	3	Moving Closed
	4	Moving Open
	5	Remote Control mode
	6	Local Stop
	7	Local Control Mode
5	0	Hand Operation
	1	Partial Stroke (in progress)
	2	Main board communications loss
	3	Reserved
	4	Digital input 1 status
	5	Digital input 2 status
	6	Digital input 3 status
	7	Digital input 4 status

## 6. Status Information *continued*

### 6.7 Command 48 Additional Device Status – SI

Command 48 returns up to 6 bytes of device-specific data. The meaning of the bits in bytes is defined in Table 11.

Bytes 0-3 are for errors only, and are continually updated. Accordingly, if any of these bits are set and the appropriate Namur mask bit is also set to a category (see Section Setup: NE107 Setup), the More Status Available bit (bit 4) of the Field Device Status is set; if all of these error bits are clear (zero), then the More Status Available Bit will be clear too.

During normal operation, all bits should be zero. All unused bits are set to zero. Extended Device Status bits are not used, so are not affected by any of these bits.

Bytes 4-5 are status bits which are useful for diagnostic purposes, these bits being set will **not** cause the More Status Available bit (bit 4) of the Field Device Status to be set.

The More Status Available bit can be cleared by reading Command 48 and writing the data back using Command 48. If that is done, any new Additional Device Status bit being set will cause the More Status Available bit to be set.

Table 11 – HART board: Alarm status bits – SI

Byte	Bit	Meaning
0	0-7	Reserved
1	0-7	Reserved
2	0-7	Reserved
3	0-7	Reserved
4	0	Actuator Moving
	1	Close position limit
	2	Open position limit
	3	Valve running close
	4	Valve running open
	5	Selector in remote
	6	Selector in local stop
	7	Selector in local
5	0	Reserved
	1	Partial stroke in progress
	2	Main board communications loss
	3	Reserved
	4	Digital input 1 status
	5	Digital input 2 status
	6	Digital input 3 status
	7	Reserved

## 7. Universal Commands

---

The universal commands are supported as listed below, for example: Command 3 returns the loop current and all four Dynamic Variables with their unit code, for a total of 24 bytes of response data.

*Table 12 – Universal command list*

<b>Command</b>	<b>Description</b>
0	Read Unique Identifier
1	Read Primary Value
2	Read PV Current and percentage of range
3	Read dynamic variable and PV current
4	Reserved
5	Reserved
6	Write polling address
7	Read loop configuration
8	Read dynamic variable class
9	Read device variables with status
10	Reserved
11	Read unique identifier associated with tag
12	Read message
13	Read tag, descriptor and date
14	Read primary variable transducer information
15	Read Device Information
16	Read final assembly number
17	Write message
18	Write tag, descriptor and date
19	Write final assembly number
20	Read long Tag
21	Read unique identifier associated with long tag
22	Write long Tag
38	Reset configuration changed flag
48	Read Additional device Status



## 8. Common-practice Commands

### 8.1 Supported Commands

The following common-practice commands are implemented:

Table 13 – Supported common-practice commands

Command	Description
34	Write Primary Variable Damping Values (CMA does not support)
35	Write Primary Variable Range Values
40	Enter/Exit Fixed Current Mode (CMA does not support)
42	Perform Device Reset (HART option card only)
45	Trim Loop Current Zero
46	Trim Loop Current Gain
49	Write Primary Variable Transducer Serial Number
79	Write Device Variable
523	Read Condensed Status Mapping Array
524	Write Condensed Status Mapping Array
525	Reset Condensed Status Map
526	Write status simulation mode
527	Simulate status bit

Command 34 (Write Primary Variable Damping Value) accepts a damping value of up to 250 s.

Command 40 (Enter/Exit Fixed Current Mode) simulates a specified input current to the actuator. This mode is cleared by power loss or device reset.

Command 42 (Perform Device Reset) resets the HFU card, but not the main board.

Command 79 (Write Device Variable) only supports Device Variables 1 (demand) and 4 (position within factory limits), and only one of these can be fixed at a time. Refer to the HART specification for more details. For this function, the request bytes are as follows:

Byte	Format	Description
0	U8	Device variable code = 01 (demand)
1	U8	Write variable command code: 0 = normal mode (control by analogue), 1 = fixed value – you have to put this back to 0 to return to normal analogue control.
2	Enum	Units code, for % = 57dec (39hex)
3-6	Float	Floating point number representing 0.00% to 100.00% For example: 0% = 00 00 00 00 25% = 41 C8 00 00 hex 50% = 42 48 00 00 hex 75% = 42 96 00 00 hex 100% = 42 C8 00 00 hex
7	Bits	Device Variable Status

Once you have enabled control via Command 79, you can check it is under control of this digital command by reading the control mode using Command 133, it is also possible to revert back to analogue control use Command 132. For details of these 2 commands see Page 21.

Command 523 (Read Condensed Status Mapping Array) Reads the status for the Indexes 0-63.

Command 524 (Write Condensed Status Mapping Array) only supports writing to Indexes 8-39 inclusive.

Command 525 (Write Status Simulation mode) Sets the device into simulation mode.

Command 526 (Simulate Status Bit) allows the Indexes 8-39 inclusive to be written and simulated.

## 8. Common-practice Commands *continued*

---

### 8.2 Unsupported Features

This Field Device does not support Burst Mode.

This Field Device does not support Catch Device Variable.

This Field Device does not support Perform Self-Test.

This Field Device does not support Extended Device Status.

## 9. Device-specific Commands

The following device-specific commands are implemented:

Table 14 – Device-specific commands

Command	Description
128	Read Software Version
129	Read Status Data (CVA only)
130	Do Not Use
131	Read Current Zero & Span
132	Command digitally – for multi-drop HART applications
133	Read Control mode
134	Write Relay control (IQ and CMA ONLY)

### 9.1 Command 128 Read Software Version

Reads the software version and build numbers of the HART board's software. The string has the form: CVA "M.mm (bbbb)", IQ "vMmm+( bbbb)" where "M" is the major revision number (currently 1), "mm" is the minor version number (incremented each time a new version of the software is released), and "bbbb" is the build number (used within Rotork as a reference for each build of the software).

#### Request Data Bytes

Byte	Format	Description
None		

#### Response Data Bytes

Byte	Format	Description
0-11	Latin-1	String containing software version and build numbers

#### Command-Specific Response Codes

Code	Class	Description
0	Success	No Command-Specific Errors
1-127		Reserved

## 9. Device-specific Commands *continued*

### 9.2 Command 129 Read Status Bits Version (CVA ONLY)

Reads the actuator status bits within the HFU. The data is returned in a 16 bit register described in Table 15.

#### Request Data Bytes

Byte	Format	Description
0-1	Unsigned 16bit	Functional block: Value 0200
2	Unsigned 8bit	Data index: Value 00

#### Response Data Bytes

Byte	Format	Description
0-1	Unsigned 16bit	Functional block: Value 0201
2	Unsigned 8bit	Data index: Value 00
3-4	16 Bits	Data read

#### Command-Specific Response Codes

Code	Class	Description
0	Success	No Command-Specific Errors
2	Error	Invalid selection
72	Error	Time out
73	Error	Communications loss
1, 3-71 and 74-127	-	Reserved

Table 15 – Actuator Status Register

Bit	Meaning
0	Set high when the relay is energised
1	Set high when the valve is obstructed whilst closing
2	Set high when the valve is obstructed whilst opening
3	Set high when a fault (non-critical) is present
4	Set high when a fault is present
5	Set high when the closing back drive limit is seen
6	Set high when the opening back drive limit is seen
7	Set high when the thrust limit whilst closing is seen
8	Set high when the thrust limit whilst opening is seen
9	Set high when the actuator is at the open limit
10	Set high when the actuator is at the closed limit
11	Set high when the local controls are in the stop position
12	Set high when the local controls are set to the run position
13	Set high when the local controls are set to the test position
14	Set high when the 4-20 mA signal is lost (below 1 mA)
15	Set high when the actuator is stalled - has moved less than 1% for 10 seconds

## 9. Device-specific Commands *continued*

### 9.3 Command 131 Read Current Zero & Span

This reads the current zero (lower endpoint value) and span (upper endpoint value), in milliamps. These are the values set by Commands 45 and 46, respectively, and so correspond to the currents used to calibrate the actuator's ADC, typically 4 and 20 mA.

#### Request Data Bytes

Byte	Format	Description
None		

#### Response Data Bytes

Byte	Format	Description
0-3	Float	Current zero (lower endpoint) value in mA
4-7	Float	Current span (upper endpoint) value in mA

#### Command-Specific Response Codes

Code	Class	Description
0	Success	No Command-Specific Errors
1-127		Reserved

### 9.4 Command 132 Control digitally

Enables the actuator to be controlled with a digital input.

#### Request Data Bytes

Byte	Format	Description
0	Unsigned 8bit	ACTCON register (see below)

#### Response Data Bytes

Byte	Format	Description
0	Unsigned 8bit	ACTCON register (see below)

Table 16 – ACTCON Register

Bit	Command	Description
0	Stop	This will Stop the actuator
1	Close	This will operate the actuator in the close direction
2	Open	This will operate the actuator in the open direction
3	ESD	This will cause the actuator to ESD
4	Partial stroke	This will initiate a partial stroke test (IQ and SI only)
5	Force Digital Position	This bit must be set to allow digital control bits above to operate the actuator. It <b>must</b> be reset once digital control is no longer required. The reset of this bit could cause movement of the actuator if the demand current is not equal to the present position.

For example, a value of 0x22 will send the actuator closed. To reset back to analogue control, send 0x00.

## 9. Device-specific Commands *continued*

### 9.5 Command 133 HART Control Mode

Reads the present control mode of the HART board.

#### Request Data Bytes

Byte	Format	Description
None		

#### Response Data Bytes

Byte	Format	Description
1	Enum	HART control mode enumeration – see Table 17.

#### Command-Specific Response Codes

Code	Class	Description
0	Success	No Command-Specific Errors
2	Error	Invalid poll address selection
5	Error	Too few data bytes received
6	Error	Transmitter specific command error
73	Error	Incorrect function response

The response is an enumerated value indicating the mode of control see Table 17.

Table 17 – HART control mode enumeration Register

Mode		
Value	Mode	Comment
0	AI Control	This is the normal operating mode in which the actuator responds to changes in value of the 4-20mA analogue input.
1	Digital Position	This mode is entered and exited using Command 79. The actuator enters this mode when the primary variable is put into forced mode. The actuator will respond to the forced primary value. It leaves this mode when the primary value is returned to normal. When in this mode, the primary variable returns a NaN value.
2	Digital position within factory limits.	This mode is entered and exited using Command 79. The actuator enters this mode when the quaternary variable is put into forced mode. The actuator will respond to the forced quaternary value. It leaves this mode when the quaternary value is returned to normal. In this mode, the primary value returns a NaN value.
3	Discrete	This mode is entered and exited using Command 132. When in this mode, the actuator responds to the commands issued using Command 132. When in this mode, the primary variable returns a NaN value.

## 9. Device-specific Commands *continued*

### 9.6 Command 134 Write Relay Control (IQ and CMA ONLY)

This command can be used to digitally control the relays within the actuator using the transmitted data. IQ actuators are fitted with relays 1-4 as standard, 5 to 12 are optional extras – refer to the wiring diagram to check how many are fitted. CMA actuators are fitted with relays 1 and 2 as standard, 5 to 8 are optional extras – refer to the wiring diagram to check how many are fitted. Relays 3, 4 and 9 to 12 are not available on the CMA.

The relays need to be set up as Digital Inputs.

#### Request Data Bytes

Byte	Format	Description
1	Unsigned-8	Set Relays register Low (see Table 18)
2	Unsigned-8	Set Relays register High (see Table 18)
3	Unsigned-8	Reset Relays register Low (see Table 18)
4	Unsigned-8	Reset Relays register High (see Table 18)

#### Response Data Bytes

Byte	Format	Description
1	Unsigned-8	Set Relays register Low
2	Unsigned-8	Set Relays register High
3	Unsigned-8	Reset Relays register Low
4	Unsigned-8	Reset Relays register High

#### Command-Specific Response Codes

Code	Class	Description
0	Success	No Command-Specific Errors
1		Undefined
2	Error	Invalid selection
3-4		Undefined
5	Error	Too few data bytes
6-72		Undefined
73	Error	Incorrect function response
74	Error	Invalid Data
75	Error	Wrong number of data bytes

Table 18 – HART Relay Control Register

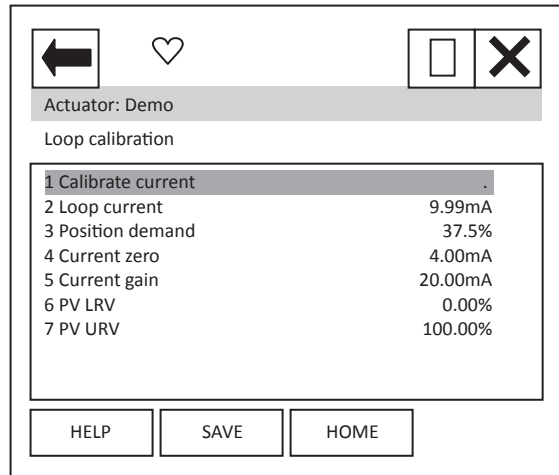
Relay Control Data		
Byte No.	Function	Comment
1	Set Relays 1-8	Setting one of these bits will cause the corresponding relay to be set as long as the same bit is not set in the Reset relay data. (Note that the relay must be set for digital control in the actuator).
2	Set Relays 9-16	Setting one of these bits will cause the corresponding relay to be set as long as the same bit is not set in the Reset relay data. (Note that the relay must be set for digital control in the actuator).
3	Reset Relays 1-8	Setting one of these bits will cause the corresponding relay to be reset as long as the same bit is not set in the Set relay data. (Note that the relay must be set for digital control in the actuator).
4	Reset Relays 9-16	Setting one of these bits will cause the corresponding relay to be reset as long as the same bit is not set in the Set relay data. (Note that the relay must be set for digital control in the actuator).

## 10. DD File, Emerson Handheld Tool Screen Shots – Common Screens

The DD file describes the HART device. There are 2 sets of DD files available on the Rotork web site, for use by a DCS and for use by the Emerson handheld tools. The following pages show screen shots from the Emerson handheld tools, indicating the data and functions that can be accessed using the DD files.

### 10.1 Setup

Setup: **Loop calibration**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'Calibrate current' displays the function to calibrate the loop current.

Item 2 'Loop current' displays the instantaneous value of the current as measured by the HFU.

Item 3 'Position demand' displays the percent (%) demand that the current is representing.

Item 4 'Current zero' displays current zero setting; not modifiable.

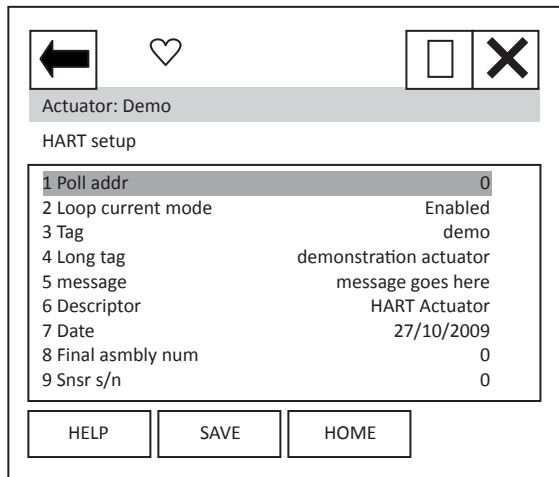
Item 5 'Current gain' displays current gain settings; not modifiable.

Item 6 'PV LRV' shows the HART Primary Value Lower Range Value; can be modified.

Item 7 'PV URV' shows the HART Primary Value Upper Range Value; can be modified.



Setup: **HART setup**



Each item can be selected, viewed, and modified where appropriate.

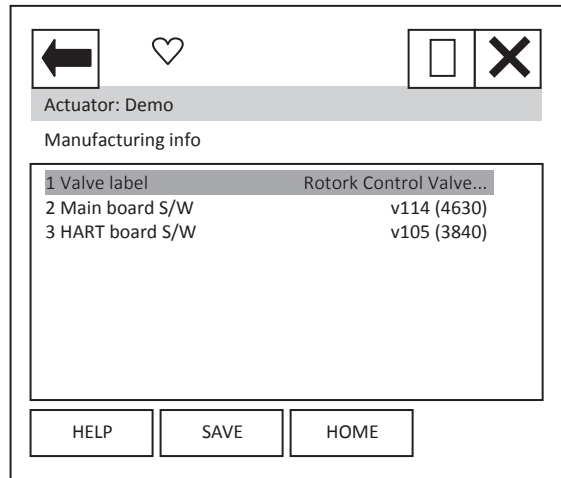
Item 1 'Poll addr' displays the HART address of the device; can be changed in the range 0-63.

Item 2 'Loop current mode' can be enabled or disabled. When disabled the actuator will not position to the analogue signal, but the unit can be commanded to a position via Command 79 – see Section 8. Care should be taken when changing to Disabled, as the actuator may move.

Items 3 to 9 are all text fields that can be modified by the user.

## 10.2 Diagnostics

Dagnostic: **Manufacturing info**



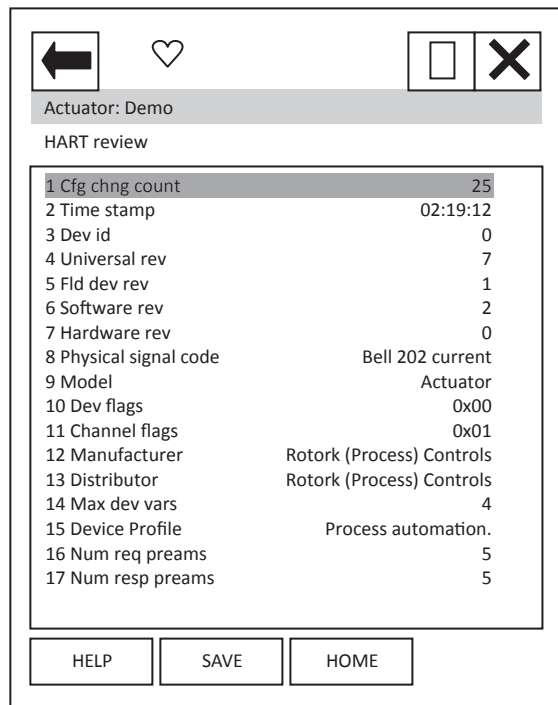
Each item can be selected and viewed.

Item 1 is the valve label.

Item 2 is the main board software version number.

Item 3 is the HART board software version number.

Diagnostic: **HART review**



Each item can be selected and viewed.

Item 1 indicates the number of times a configuration change has been made.

Item 2 'Time Stamp' this timer is reset to zero every time the HART device is reset. Every 24 hours it rolls over.

Items 3-7 indicate revisions of the HART device.

Item 8 shows the physical layer code.

Item 9 'Model' indicates the model type for the device – 'Actuator'.

Items 10 and 11 are HART related flags.

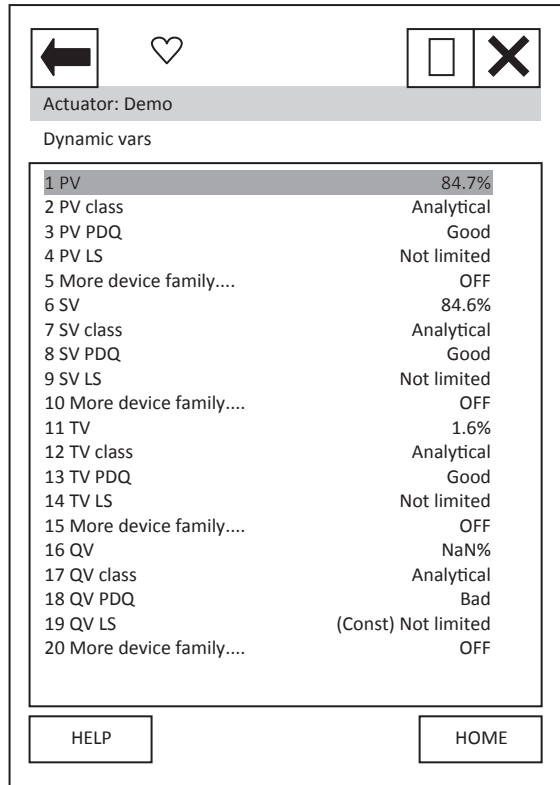
Items 12 and 13 indicate the manufacturer and the distributor of the device.

Item 14 indicates the maximum number of variables on the HART device i.e. PV etc.

Item 15 indicates the device profile.

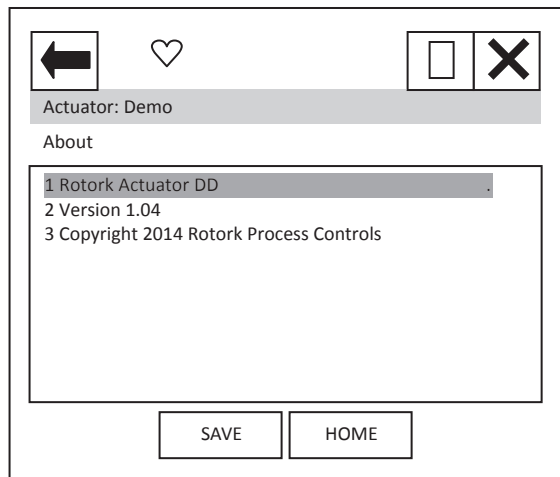
Items 16 and 17 indicate the number of pre-ambls expected for request and response messages.

Diagnostic: **Dynamic vars**



This page details information about the dynamic variables. Each item can be selected and viewed.

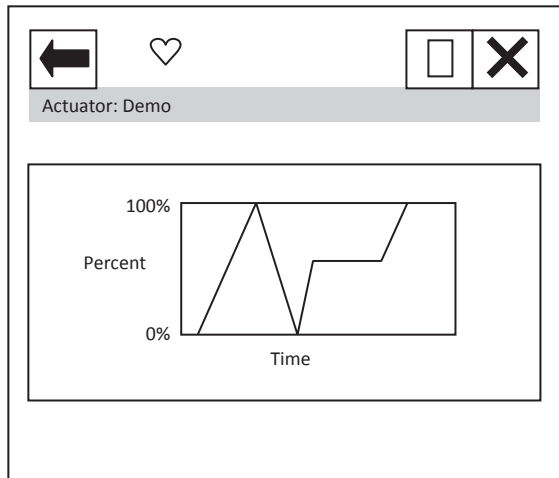
Diagnostic: **About**



Device Description About box.

### 10.3 Pos / Demand chart

From the top menu, selecting 'Pos./demand chart' will display the chart of position demand or valve position against time. This will only display if the handheld tool has a graphics licence.

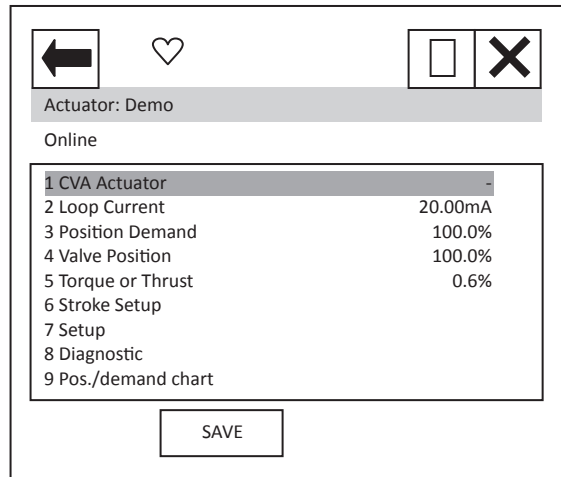


## 11. DD File, Emerson Handheld Tool Screen Shots – CVA

The DD file describes the HART device. There are 2 sets of DD files available on the Rotork web site, for use by a DCS and for use by the Emerson handheld tools. The following pages show screen shots from the Emerson handheld tools, indicating the data and functions that can be accessed using the DD files. Refer to the CVA technical manuals PUB042-003 (CVL) and PUB042-004 (CVQ) for more details of the features shown. The DD file pages have the same functions as the pages in Enlight described in the CVA technical manuals.

### 11.1 Top Menu

When the items 2 to 5 are selected, the display changes to show the data selected.



Item 1 'CVA Actuator' indicates the type of actuator. CVL for Linear CVA and CVQ for quarter turn.

Item 2 'Loop current' displays the instantaneous value of the current, as measured by the HFU.

Item 3 'Position demand' displays the percent (%) demand that the current is representing.

Item 4 'Valve position' displays the valve position.

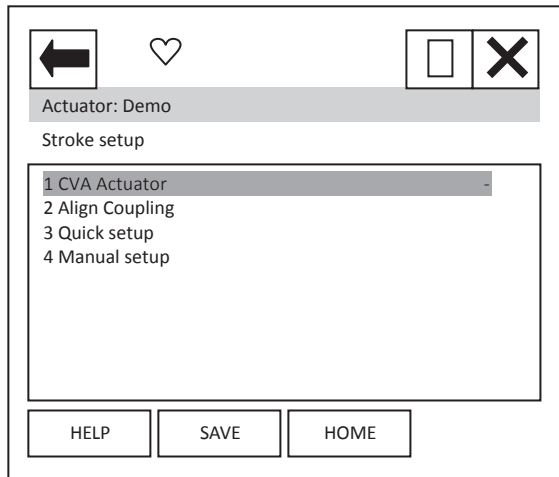
Item 5 'Torque or Thrust' displays the torque or thrust present at the output of the actuator.

Selection of items 6 to 9 will bring up new menus, detailed in the following sections.

For item 9 see Section 10.3.

### 11.2 Stroke setup

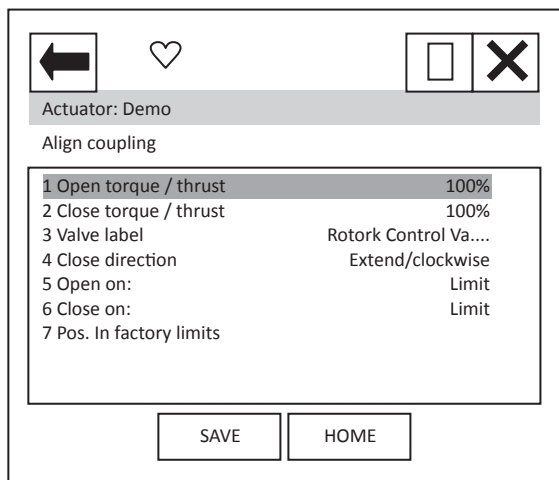
From the top menu, selecting 'Stroke setup' will display the following menu:



Item 1 'CVA Actuator' indicates the type of actuator.

When the items 2 to 4 are selected, new pages are displayed.

#### Stroke setup: **Align coupling**



Each item can be selected, viewed, and modified where appropriate:

Items 1 and 2 Open and Close torque / thrust; can be modified between 41 and 100%.

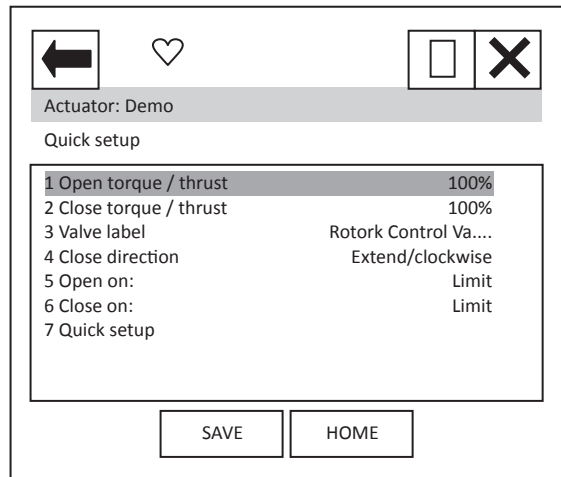
Items 3 and 7 cannot be modified.

Item 4 can be modified between Extend/clockwise or Retract/ anti-clock.

Items 5 and 6 can be modified between Limit or Torque / Thrust.

## 11. DD File, Emerson Handheld Tool Screen Shots – CVA *continued*

Stroke setup: **Quick setup**

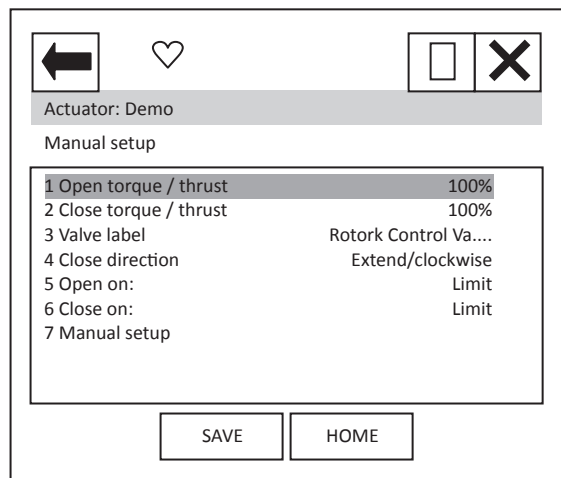


Each item can be selected, viewed, and modified where appropriate:

Items 1 to 6 are as per 'Align coupling'.

Item 7 'Quick setup', follow the on-screen instructions for setting up the device.

Stroke setup: **Manual setup**



Each item can be selected, viewed, and modified where appropriate:

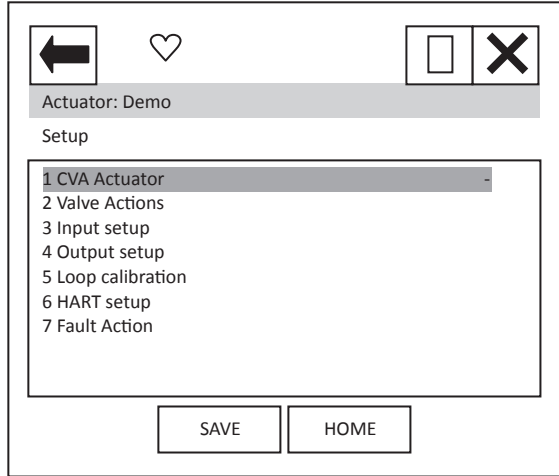
Items 1 to 6 are as per 'Align coupling'.

Item 7 'Manual setup', follow on - screen instructions for setting up the device.



### 11.3 Setup

From the top menu, selecting 'Setup' will display the following menu:

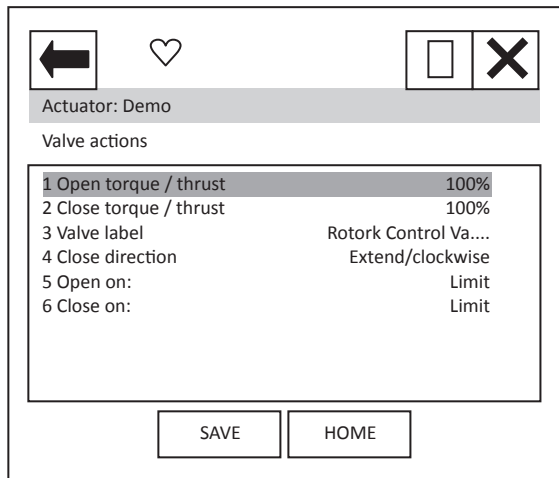


Item 1 'CVA Actuator' indicates the type of actuator.

When the items 2 to 7 are selected, new pages are displayed.

For items 5 and 6 see Section 10.1.

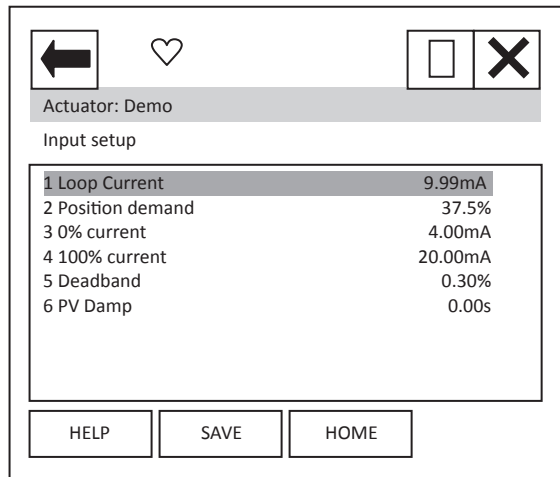
#### Setup: **Valve actions**



Each item can be selected, viewed, and modified where appropriate:

Items 1 to 6 are as per 'Align coupling'.

Setup: **Input setup**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'Loop current' displays the instantaneous value of the loop current as measured by the HFU.

Item 2 'Position demand' displays the % demand that the current input signal is representing.

Item 3 '0% current' displays the mA demand signal required for positioning to 0%; can be modified.

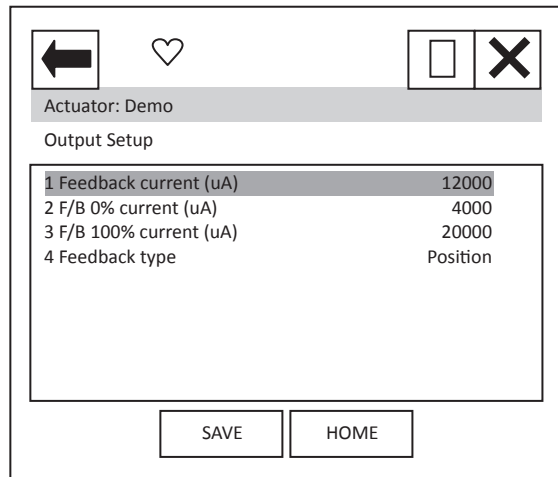
Item 4 '100% current' displays the mA demand signal required for positioning to 100%; can be modified.

Item 5 'Deadband' – displays the deadband applied to the demand signal; can be modified between the range 0.00% and 15.00% in 0.01% increments.

Item 6 'PV damp' – displays the Primary Value Damping value; when selected can be modified in 0.01s increments.

## 11. DD File, Emerson Handheld Tool Screen Shots – CVA *continued*

Setup: **Output setup**



Each item can be selected, viewed, and modified where appropriate.

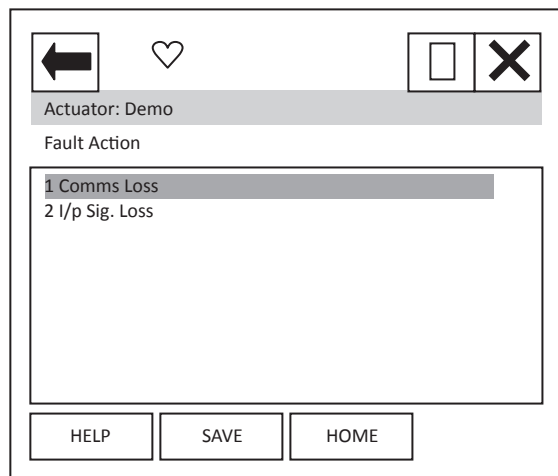
Item 1 'Feedback current' displays the instantaneous value of the feedback signal.

Item 2 'F/B 0% current' displays the value of the Feedback current for 0% position; can be modified.

Item 3 'F/B 100% current' displays the value of the Feedback current for 100% position; can be modified.

Item 4 'Feedback type' displays the feedback source; can be modified between Position or Torque / Thrust.

Setup: **Fault Action**



When the items 1 or 2 are selected, new pages are displayed.

Select menu item 1 for CVA software version V114 and newer.

Select menu item 2 for CVA software version older than V114.

The software version can be found in the Manufacturing info menu, found from the main menu by selecting the Diagnostics menu.

If in doubt, change the settings as required in both locations.

## 11. DD File, Emerson Handheld Tool Screen Shots – CVA *continued*

### Setup: **Comms Loss**

	No Action
1 Loss Action	No Action
2 Fault Time out	1000
3 Loss Position (x0.01%)	5000

Use this setting for CVA firmware V114 and newer.

Each item can be selected, viewed, and modified where appropriate

Item 1 'Loss Action' enables the loss of 4-20 mA signal action to be set up. Choices are No Action, Open, Close, Stop and Position.

Item 2 'Fault Time out' sets the timeout for the loss of 4-20 mA signal action. Range is 0 to 65,535 ms.

Item 3 'Loss Position' enables the position value to be entered, for use when the Loss Action of 'Position' is set. Range is 0.00 to 100.00%.

### Setup: **I/p Sig Loss**

	No Action
1 Sig. Loss Action	No Action
2 Sig. Fault Time out	1 000
3 Sig. Loss Position (x0.01%)	5000

Use this setting for CVA firmware older than V114.

Each item can be selected, viewed, and modified where appropriate

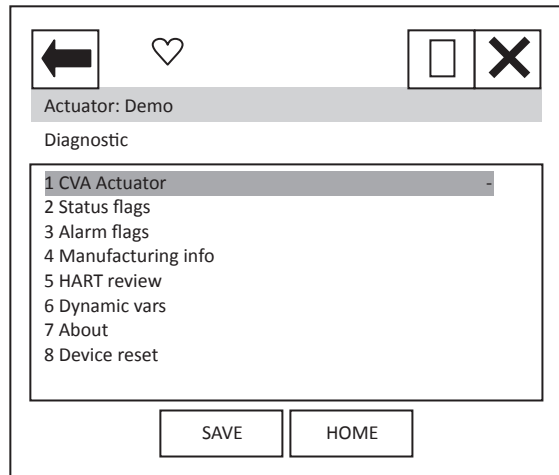
Item 1 'Sig. Loss Action' enables the loss of 4-20 mA signal action to be set up. Choices are No Action, Open, Close, Stop and Position.

Item 2 'Sig. Fault Time out' enables the timeout for the action to be taken on loss of 4-20 mA signal to be set up. Range is 0 to 65,535 ms.

Item 3 'Sig. Loss Position' enables the position value to be entered, for use when the Loss Action of 'Position' has been selected. Range is 0.00 to 100.00%.

### 11.4 Diagnostics

From the top menu, selecting 'Diagnostics' will display the following menu:



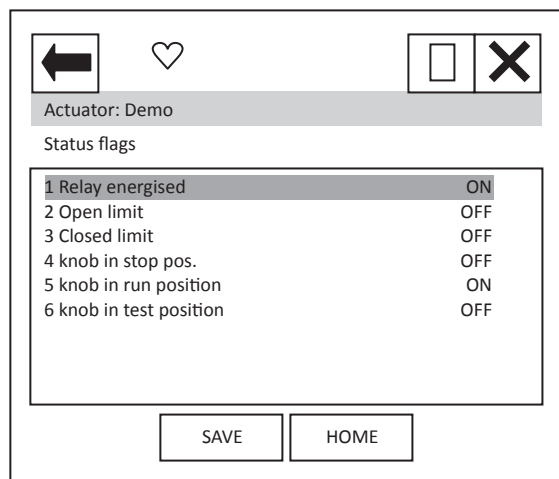
Item 1 'CVA Actuator' indicates the type of actuator.

When the items 2 to 7 are selected, new pages are displayed.

For items 4 to 7 see Section 10.2.

Item 8 'Device reset' will cause a device reset (HART option card only).

Diagnostics: **Status flags**



Each item can be selected and viewed.

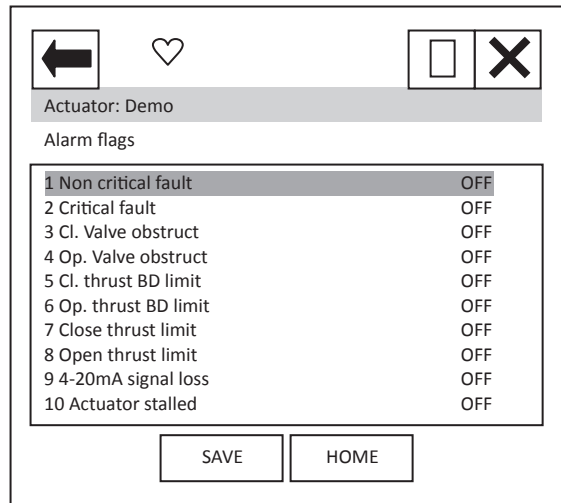
Item 1 'Relay energised' when this item is 'ON' it indicates that the CVA is capable of being remotely controlled.

Item 2 'Open limit' indicates if the actuator is at its open limit.

Item 3 'Closed limit' indicates if the actuator is at its close limit.

Items 4-6 indicate the locally mounted control knob position.

Diagnostic: **Alarm flags**



Each item can be selected and viewed.

Items 1 and 2 indicate if the fault is non-critical or critical.

Items 3 and 4 indicate if the valve is obstructed in the close or open directions.

Items 5 and 6 indicate if the close or open back drive thrust limit is reached.

Items 7 and 8 indicate if the close or open back thrust limit is reached.

Item 9 indicates if the 4-20mA signal has been lost. This is unlikely to be seen as loss of signal and will result in the loss of HART communications.

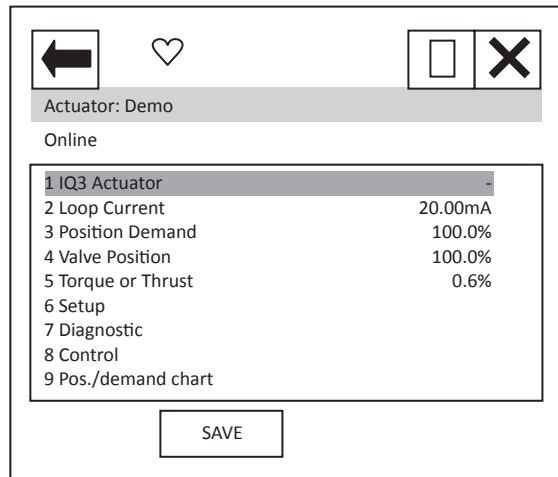
Item 10 indicates if the actuator has stalled.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ

The DD file describes the HART device. There are 2 sets of DD files available on the Rotork web site, for use by a DCS and for use by the Emerson handheld tools. The following pages show screen shots from the Emerson handheld tools, indicating the data and functions that can be accessed using the DD files.

### 12.1 Top Menu

When the items 2 to 6 are selected, the display changes to show the data selected.



Item 1 'IQ3 Actuator' indicates the type of actuator.

Item 2 'Loop current' displays the instantaneous value of the current, as measured by the HFU.

Item 3 'Position demand' displays the percent (%) demand that the current is representing.

Item 4 'Valve position' displays the valve position.

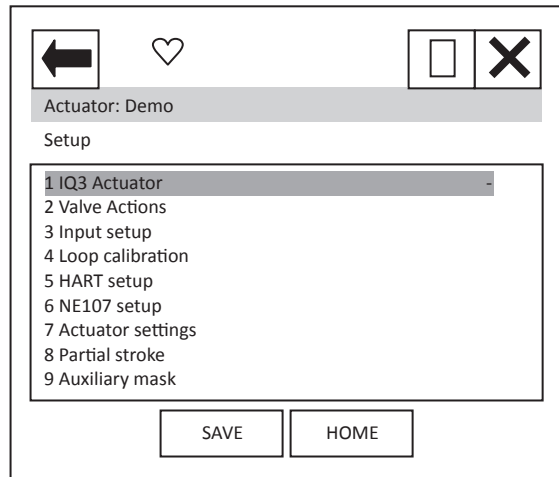
Item 5 'Torque or Thrust' displays the torque or thrust present at the output of the actuator.

Selection of items 6 to 9 will bring up new menus, detailed in the following sections.

For item 9 see Section 10.3.

## 12.2 Setup

From the top menu, selecting 'Setup' will display the following menu:

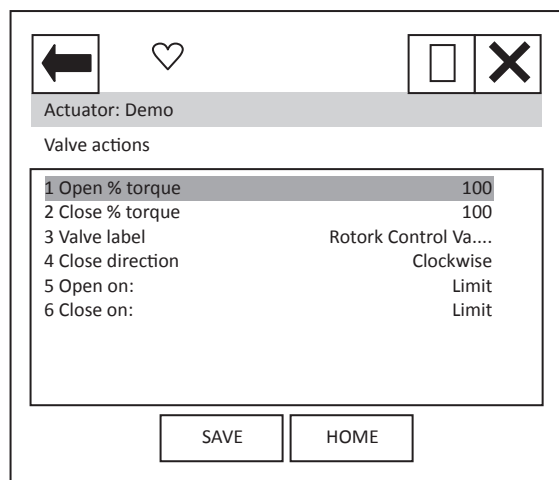


Item 1 'IQ3 Actuator' indicates the type of actuator.

When the items 2 to 8 are selected, new pages are displayed.

For items 4 and 5 see Section 10.1.

Setup: **Valve actions**



Each item can be selected, viewed, and modified where appropriate:

Items 1 and 2 Open and Close torque; can be modified between 40 and 100%.

Item 3 cannot be modified.

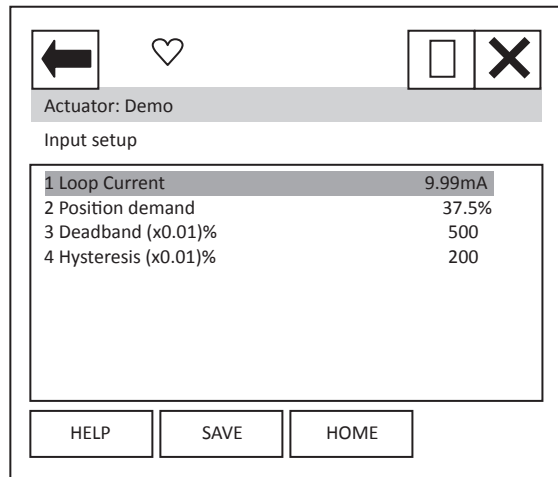
Item 4 can be modified between clockwise or anti-clockwise.

Items 5 and 6 can be modified between Limit and Torque.



## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Setup: **Input setup**



Each item can be selected, viewed, and modified where appropriate.

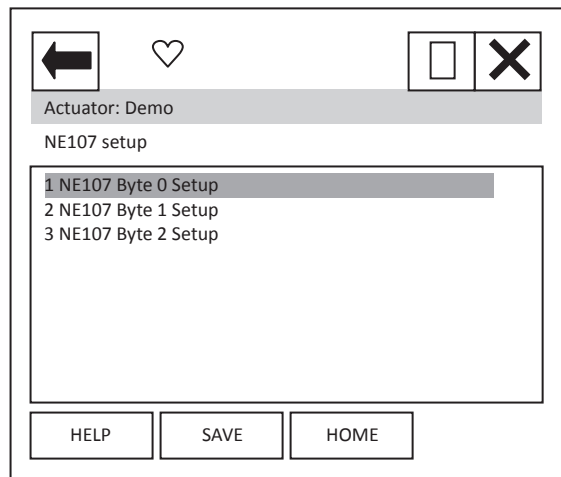
Item 1 'Loop current' displays the instantaneous value of the loop current as measured by the HFU.

Item 2 'Position demand' displays the % demand that the current input signal is representing.

Item 3 'Deadband' – displays the deadband applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

Item 4 'Hysteresis' – displays the hysteresis applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

Setup: **NE107 Setup**



When the items 1 to 4 are selected, new pages are displayed.

These 4 pages are used to set up which alarms bits will cause the NE107 status bits to be set. For each bit listed in the table following, the user is able to select one of the following actions:

- 1) No effect – default
- 2) **Maintenance required**
- 3) Reserved
- 4) **Failure**
- 5) **Out Of Spec.**
- 6) **Function Check**
- 7) Not defined
- 8) Reserved

The four actions highlighted are NE107 status bits.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Table 19 – NE107 Diagnostics Bits, Setup – IQ

	Bit	Description
<b>Byte 0 Setup</b>	1	Battery Low
	2	Local Control Fault
	3	Power supply Fault
	4	Thermostat Tripped
	5	Contactors Operations Exceeded
	6	Service Required
	7	Hi Hi Torque level
	8	High Torque Level
<b>Byte 1 Setup</b>	1	Valve obstructed
	2	Total Turns Exceeded
	3	Monitor relay
	4	Control Failure
	5	Actuator failure
	6	Network Comms lost
	7	Option not detected
	8	Partial stroke Fail
<b>Byte 2 Setup</b>	1	Motor Starts Exceeded
	2	Actuator Stalled
	3	Position Limp Home
	4	End Travel Movement
	5	Network Fault
	6	Output Supply Fault
	7	Valve Time Exceeded
	8	Drive Direction Fault

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

For example: A user requires NE107 Failure indication for faults within the actuator positioner and in the local controls, but treats the actuator being in Local, valve obstructed or High torque as requiring someone to go and check the device. If the thermostat trips or the motor starts are exceeded the user would like an Out of spec alarm to be raised as the device is being used out of its specification and finally for Hi Hi torque the user wants to call in maintenance. For this setup the following setup would apply:

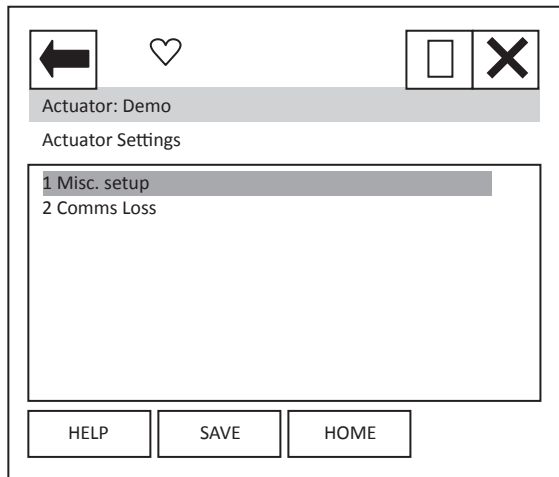
Table 20 – NE107 Diagnostics Bits, Example setup – IQ

	Description	Action
<b>Byte 0 Setup</b>	Battery Low	No effect
	Local Control Fault	<b>Failure</b>
	Power Supply Fault	No effect
	Thermostat Tripped	<b>Out of Spec</b>
	Contactors Operations Exceeded	No effect
	Service Required	No effect
	Hi Hi Torque level	<b>Maintenance</b>
	High Torque Level	<b>Function Check</b>
<b>Byte 1 Setup</b>	Valve Obstructed	<b>Out of Spec</b>
	Total Turns Exceeded	No effect
	Monitor Relay	<b>Function Check</b>
	Control Failure	No effect
	Actuator Failure	No effect
	Network Comms Lost	No effect
	Option Not Detected	No effect
	Partial Stroke Fail	No effect
<b>Byte 2 Setup</b>	Motor Starts Exceeded	Function Check
	Actuator Stalled	No effect
	Position Limp Home	<b>Failure</b>
	End Travel Movement	No effect
	Network Fault	No effect
	Output Supply Fault	No effect
	Valve Time Exceeded	No effect
	Drive Direction Fault	No effect

With these settings, the bits defined in the Diagnostics page condensed data (see later) will be set if one of the enabled bits above is set i.e. NE107 Failure will be ON if either there is a local control fault OR an actuator positioner fault.

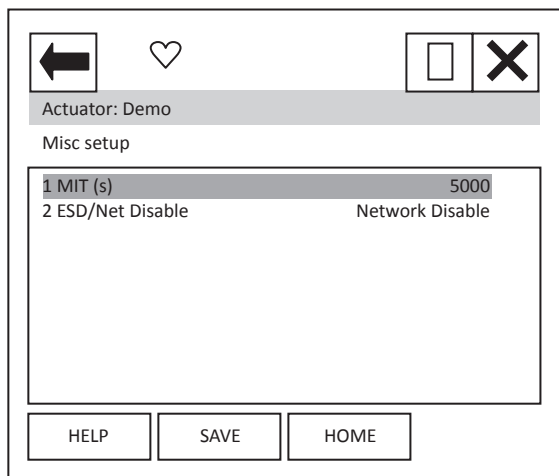
## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Setup: **Actuator Settings**



When the items 1 to 2 are selected, new pages are displayed.

Setup: **Actuator Settings, Misc setup**



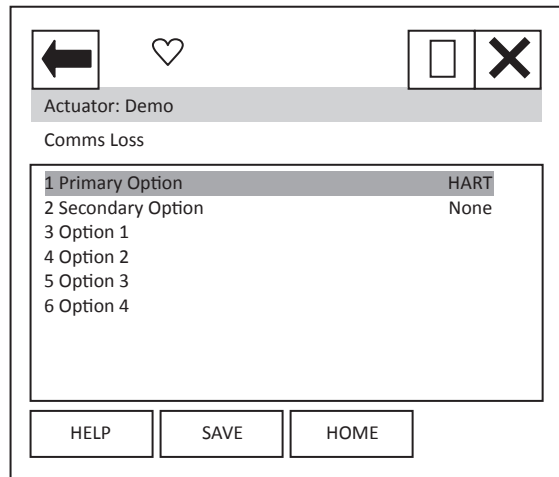
Each item can be selected, viewed, and modified where appropriate.

Item 1 'MIT' displays the Motion Inhibit Timer used in positioning, can be modified between 0 and 255 seconds, **the scale is milliseconds** therefore 5000 is 5 seconds.

Item 2 'ESD/Net Disable' displays the function setting for the ESD auxiliary input. Can be set to either the ESD function OR to operate as a network command disable signal.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Setup: **Actuator Settings, Comms Loss**

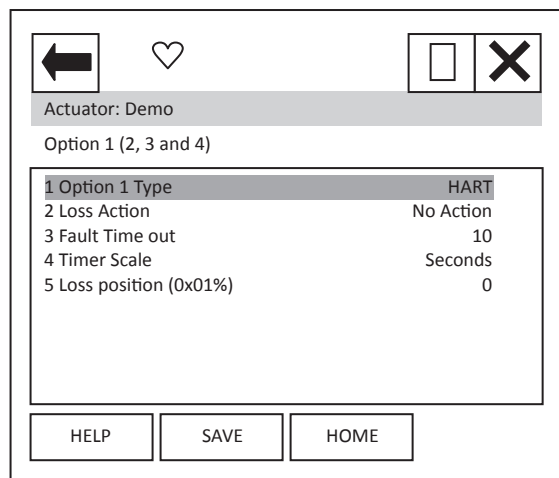


Item 1 'Primary Option' shows the option card that has been selected as source 1 in the IQ menu.

Item 2 'Secondary Option' shows the option card that has been selected as source 2 in the IQ menu.

When the items 3 to 6 are selected, new pages are displayed to show the Comms loss settings of the option cards fitted. The IQ can have up to 4 option cards fitted. It should be noted that only the card that is in control, as defined by the control source selection parameter in the IQ, will cause the action to be taken on loss of signal.

Setup: **Actuator Settings, Comms Loss, Option 1 (2, 3 and 4)**



Item 1 'Option 1 Type' shows the option card that is listed as option 1 in the IQ options fitted menu.

Item 2 'Loss Action' enables the loss of 4-20mA signal action to be set up. Choices are No Action, Open, Close, Stop and Position.

Item 3 'Fault Time out' enables the timeout for the action to be taken on loss of 4-20mA signal to be set up. Range dependant on item 4.

Item 4 'Timer Scale' enables the timeout scale to be set to either Seconds or milli-Seconds.

Item 4 'Loss position' enables the position value to be entered, for use when the Loss Action of 'Position' has been selected. Range is 0.00 to 100.00%.

Menus for Options 2, 3 and 4 are identical.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

### Setup: **Partial Stroke**

Item	Value
1 PS Enable	Enabled
2 PS travel (x0.01)%	9000
3 PS Stroke Limit	Open Limit
4 PS Timeout 1 (x0.0001s)	150000
5 PS Timeout 2 (x0.0001s)	150000

Each item can be selected, viewed, and modified where appropriate.

Item 1 'PS Enable' enables the Partial Stroke feature to be enabled and disabled.

Item 2 'PS travel (x0.01)%' enables the position to which the unit will travel on activation of a partial stroke command to be set up. Range is 0-100% in 0.01% steps.

Item 3 'PS Stroke Limit' enables the position of the actuator from which the partial stroke command can be activated to be set up. Either the open or the close limit.

Item 4 and 5 'PS Timeout 1 / 2 (x0.0001s)' enables the timeout for reaching the position (Timeout 1) then returning to the limit (Timeout 2) to be set up.

### Setup: **Auxiliary Mask**

Item	Value
1 Aux 1 Function	Open Command
2 Aux 2 Function	Close Command
3 Aux 3 Function	Digital Input
4 Aux 4 Function	Digital Input
5 Aux 1 I/P Type	NO Contact
6 Aux 2 I/P Type	NO Contact
7 Aux 3 I/P Type	NC Contact
8 Aux 4 I/P Type	NC Contact

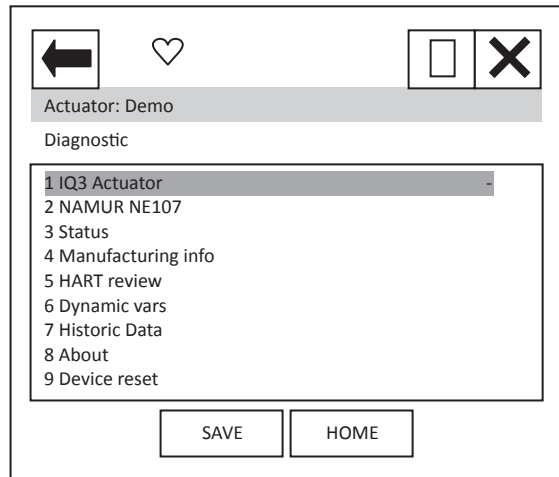
Each item can be selected, viewed, and modified where appropriate.

Items 1 to 4 'Aux 1/2/3/4 Function' enables the function of the Auxiliary inputs to be set up. Either to be a digital input or to be a command.

Items 5 to 8 'Aux 1/2/3/4 I/P Type' enables the contact type of the Auxiliary inputs to be set up. Either NO (Normally Open) or NC (Normally Closed).

### 12.3 Diagnostics

From the top menu, selecting 'Diagnostics' will display the following menu:



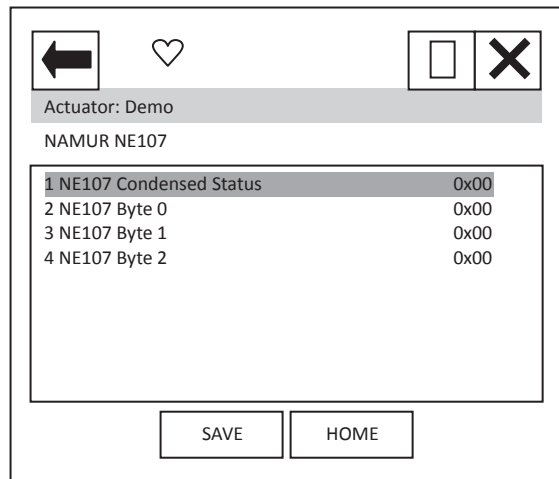
Item 1 'IQ3 Actuator' indicates the type of actuator.

When the items 2 to 8 are selected, new pages are displayed.

For items 4 to 6 and 8 see Section 10.2.

Item 9 'Device reset' will cause a device reset (HART option card only).

Diagnostics: **NAMUR NE107**



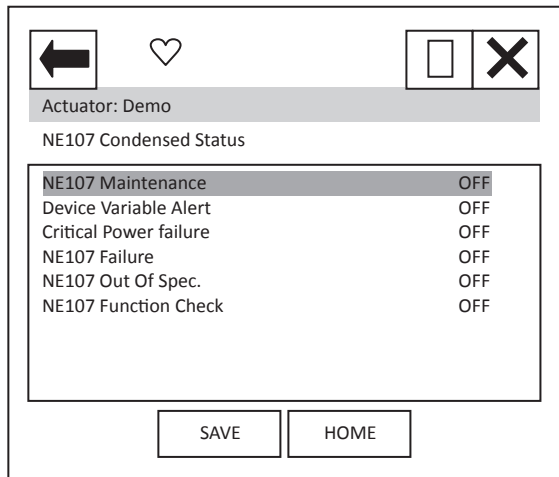
When the items 1 to 4 are selected, new pages are displayed.

Items 2 to 4 select pages which are identical to Status NE107 Alarm Status 0 to 2 – see status section below.



## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

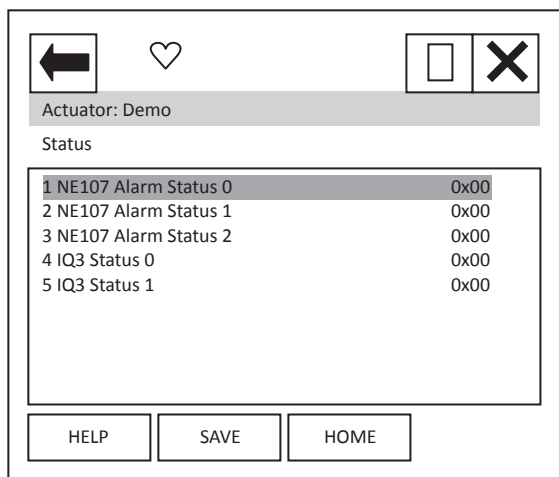
Diagnostic: **NAMUR NE107, NE107 Condensed Status**



These items indicate the status of the alarms bits.

The NE107 bits will be set as 'ON', if one of the alarm bits, that has been associated to the alarm in the NE107 setup section, has activated.

Diagnostic: **Status**



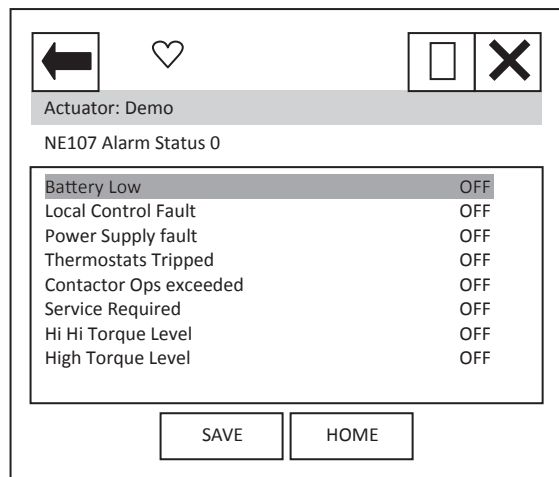
When the items 1 to 5 are selected, new pages are displayed.

The NE107 items show the status of the alarms bits that are associated to the NE107 diagnostics function.

IQ3 Status 0 and 1 are status indication bits.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Diagnostic: **Status, NE107 Alarm Status 0**



'Battery Low' indicates that the actuator battery used to maintain the display, is either flat or low.

'Local Control Fault' indicates that there is a fault in the actuator's local controls.

'Power Supply Fault' indicates that there is a fault in the actuator's power supply.

'Thermostats Tripped' indicates that the actuator motor thermostat has tripped.

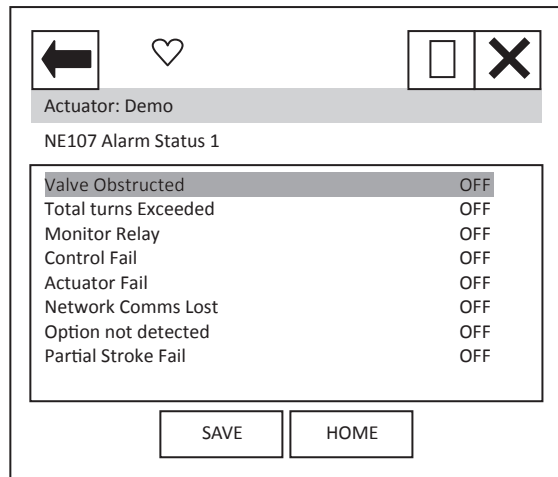
'Contactor Ops exceeded' indicates the limit for contactor operations set has been exceeded.

'Service Required' indicates that the time interval set for servicing the actuator has expired.

'Hi Hi Torque Level' and 'High Torque Level' indicates that the levels set for the Hi Hi and High torque levels have been exceeded.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Diagnostic: **Status, NE107 Alarm Status 1**



'Valve Obstructed' indicates that the actuator has tripped/stopped on torque due to an obstruction in the valve.

'Total turns Exceeded' indicates that the level set for the total number of turns that the actuator is to do in its life time has been exceeded.

'Monitor Relay' indicates that the actuator monitor relay has tripped – see actuator manual for details.

'Control Fail' and 'Actuator Fail' indicates the actuator has experienced a control or actuator failure.

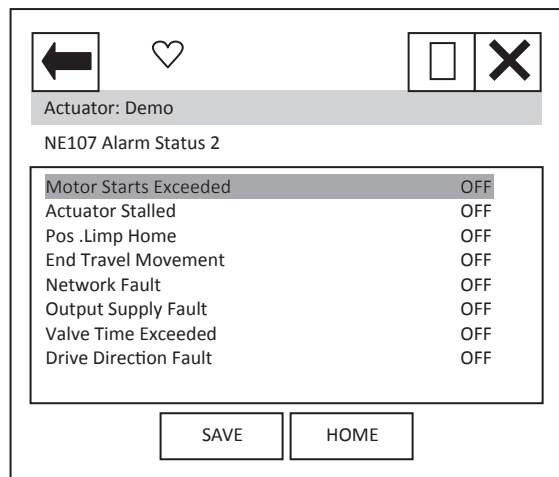
'Network Comms Lost' indicates that the network card is not able to communicate on the network – this is unlikely to be seen.

'Option not detected' indicates a problem with the option card.

'Partial Stroke Fail' indicates a failure in the partial stroke test.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Diagnostic: **Status, NE107 Alarm Status 2**



'Motor Starts Exceeded' indicates that the limit for the number for motor starts expected in the actuator life has been exceeded.

'Actuator Stalled' indicates that the actuator has stalled.

'Pos .Limp Home' indicates a fault in the absolute encoder, which has caused the 'limp home mode' to be activated.

'End Travel Movement' indicates that there has been excessive travel beyond a limit.

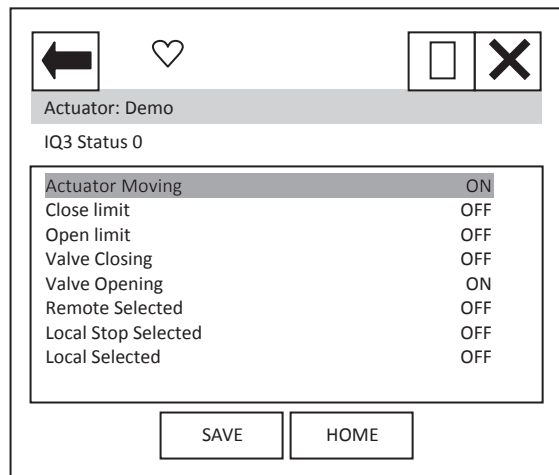
'Network Fault' indicates a fault with the network card.

'Output Supply Fault' indicates a fault with the supply available to the customer.

'Valve Time Exceeded' indicates that the expected travel time of the valve has been exceeded.

'Drive Direction Fault' indicates that the actuator has operated in the incorrect direction.

Diagnostic: **Status, IQ3 Status0**



'Actuator Moving' indicates that the actuator is currently moving.

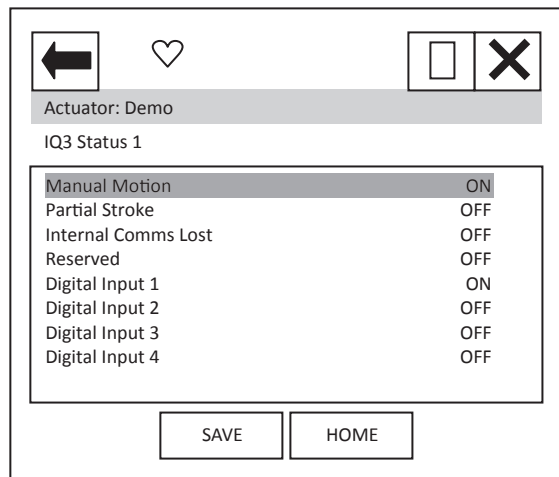
'Close limit' and 'Open limit' indicate if the actuator is at its close or open position limit.

'Valve Closing' and 'Valve Opening' indicates if the actuator is operating the valve in the closing or opening direction.

'Remote Selected', 'Local Stop Selected' and 'Local Selected' indicate the position that the actuator control selection knob is in.

## 12. DD File, Emerson Handheld Tools Screen Shots – IQ *continued*

Diagnostic: **Status, IQ3 Status1**



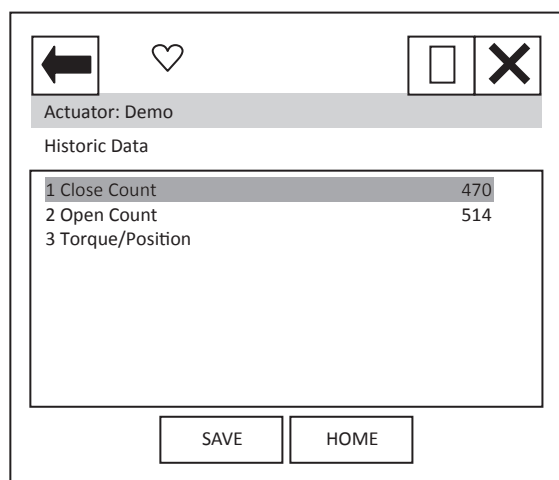
'Manual Motion' indicates that the actuator is currently moving under manual control.

'Partial Stroke' indicates whether the actuator is performing a partial stroke test.

'Internal Comms Lost' indicates an internal actuator communication problem.

'Digital Input x' indicates the status of the actuator hardwired digital inputs.

Diagnostic: **Historic Data**



Each item can be selected, viewed.

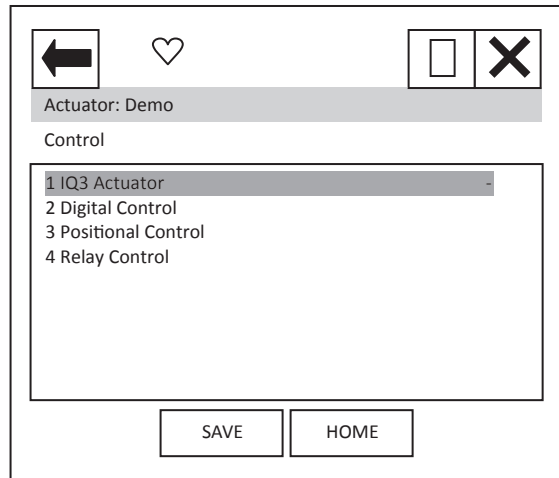
Item 1 'Close Count' shows the number of times the unit has been operated in the close direction.

Item 2 'Open Count' shows the number of times the unit has been operated in the open direction.

Item 3 shows a graph of the torque versus position for the open and close directions.

### 12.4 Control

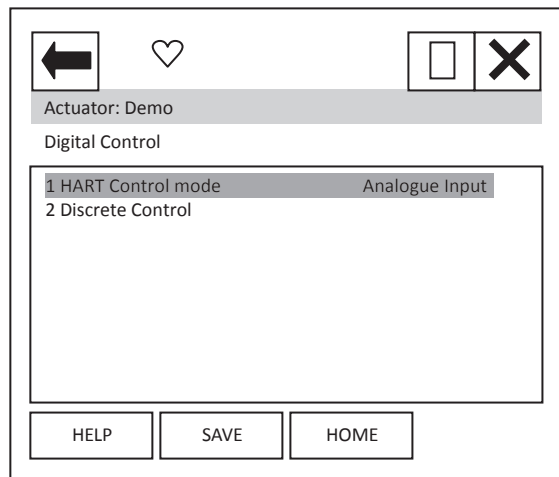
From the top menu, selecting 'Control' will display the following menu:



Item 1 'IQ3 Actuator' indicates the type of actuator.

When the items 2 to 4 are selected, new pages are displayed.

Control: **Digital Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' displays the mode that is currently in control. It can either be 'Analogue Input', 'Discrete' or 'Digital position'.

Analogue Input indicates that the unit is being controlled with the 4-20 mA analogue input supply.

Discrete indicates that the discrete mode of control is enabled and the actuator can be controlled using discrete open/close/stop etc. commands.

Digital position indicates that control is via a digital position command and the actuator can be controlled using a digital position command in the range 0.0 to 100.0%.

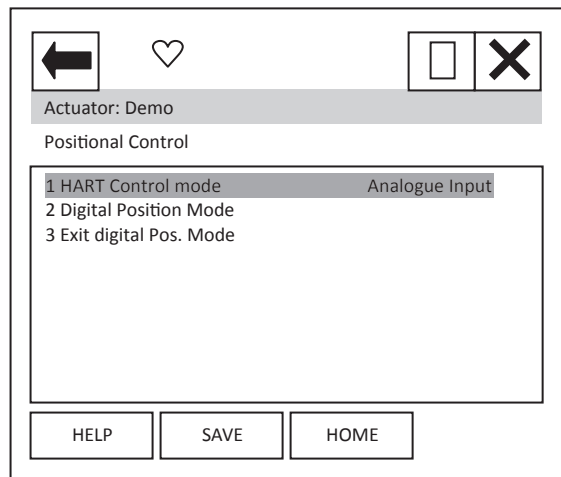
Item 2 selects a new page where the actuator can be operated discretely. Only one command should be selected at one time. The commands available are: Stop, Close, Open, ESD, Partial Stroke Test and Enable Digital Control. Commands will not action unless the 'Enable Digital Control' item is also selected. For example, to operate the actuator in the open direction:

- 1) Select the Discrete Control page.
- 2) Set the Open row item to 'ON' using the touch screen button displayed at the bottom of the screen.
- 3) Set the 'Enable Digital Control' row item to 'ON' using the same button.
- 4) Ensure all other rows are 'OFF'.
- 5) Select the Enter button to return you to the previous screen.
- 6) You will notice a '\*' next to the Discrete Control item – this indicates there is data to send for this feature. Select the 'SEND' button.
- 7) The actuator will operate and you will notice that the HART control mode will change to Discrete.

To operate in the close direction, repeat above instructions ensuring that Open is set to 'OFF' and Close is set to 'ON'.

To exit Discrete control mode, the Enable Digital Control row item must be set to 'OFF', the data entered and sent. NOTE that the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.

Control: **Positional Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' as previous menu item.

Item 2 'Digital Position Mode' Selecting this item will start a method which guides the user to enter the digital positioning mode. The sequence is:

On selection, the display changes to 'Entering Forced Mode' at this point the user can Abort or select OK to enter this mode.

On selection of OK the user is warned that the card will be removed from automatic mode – this means that the analogue Input is no longer in control. Again, the user can choose to Abort or select OK to carry on.

The final page, again has the option to Abort, but selecting OK will enable the user to enter a position value. The Actuator will run to the position selected.

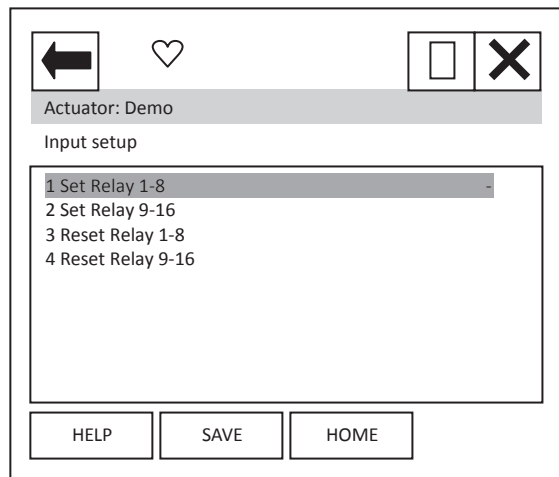
To exit this mode, select Abort at any page.

**NOTE: On Aborting, the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.**

Item 3 'Exit digital Pos. Mode' may be required to exit the digital positioning mode should the handheld tool be disconnected at any time, resulting in the HART card remaining in the digital positioning mode. Selecting this item will return the unit to Analogue Input mode.



Control: **Relay Control**



Each item can be selected, viewed, and modified where appropriate.

Items 1 to 4 enable the user to operate the 'extra' relays (if fitted) within the actuator. There are 2 sets of items to select for each relay, to activate the relay select the 'Set Relay' item that contains the relay to be set, then change the relays state to 'ON'. To reset the relay the same item will need to be set to 'OFF' and the associated 'Reset Relay' item must be set to 'ON'. To again operate the same relay the 'Reset Relay' item needs to be returned to 'OFF' before selecting 'ON' for the 'Set Relay' item.

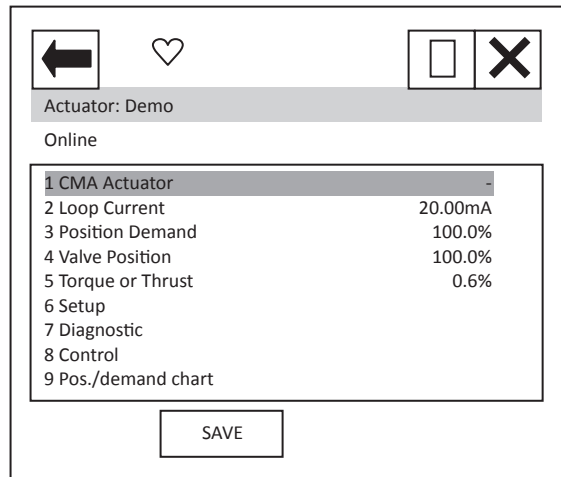
**NOTE: The wiring diagram should be checked to confirm which relays are present within the actuator. The IQ can have up to 12 relays fitted.**

## 13. DD File, Emerson Handheld Tools Screen Shots – CMA

The DD file describes the HART device. There are 2 sets of DD files available on the Rotork web site, for use by a DCS and for use by the Emerson handheld tools. The following pages show screen shots from the Emerson handheld tools, indicating the data and functions that can be accessed using the DD files.

### 13.1 Top Menu

When the items 2 to 6 are selected, the display changes to show the data selected.



Item 1 'CMA Actuator' indicates the type of actuator.

Item 2 'Loop Current' displays the instantaneous value of the current, as measured by the HFU.

Item 3 'Position Demand' displays the percent (%) demand that the current is representing.

Item 4 'Valve Position' displays the valve position.

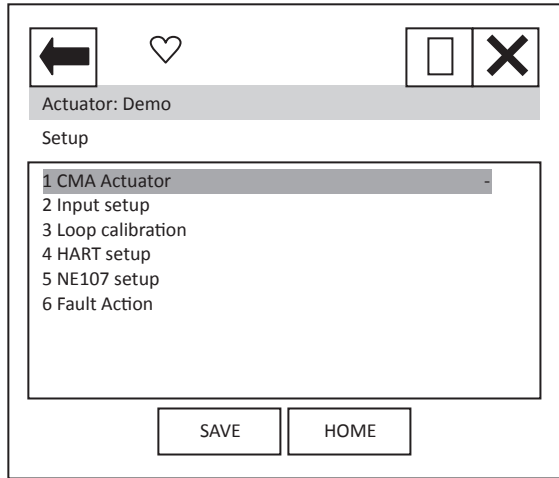
Item 5 'Torque or Thrust' displays the torque or thrust present at the output of the actuator.

Selection of items 6 to 9 will bring up new menus, detailed in the following sections.

For item 9 see Section 10.3.

### 13.2 Setup

From the top menu, selecting 'Setup' will display the following menu:

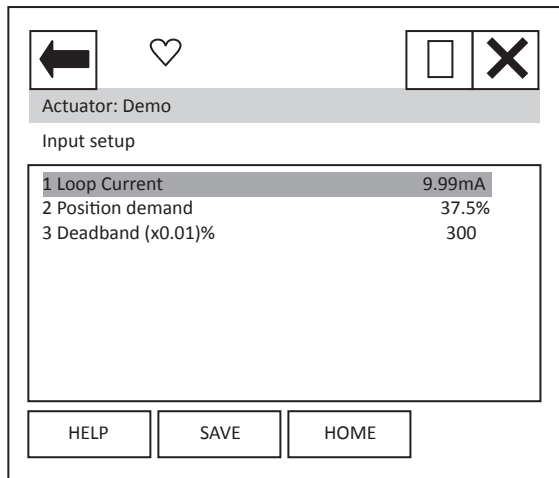


Item 1 'CMA Actuator' indicates the type of actuator.

When the items 2 to 6 are selected, new pages are displayed.

For items 3 and 4 see Section 10.1.

#### Setup: **Input setup**



Each item can be selected, viewed, and modified where appropriate.

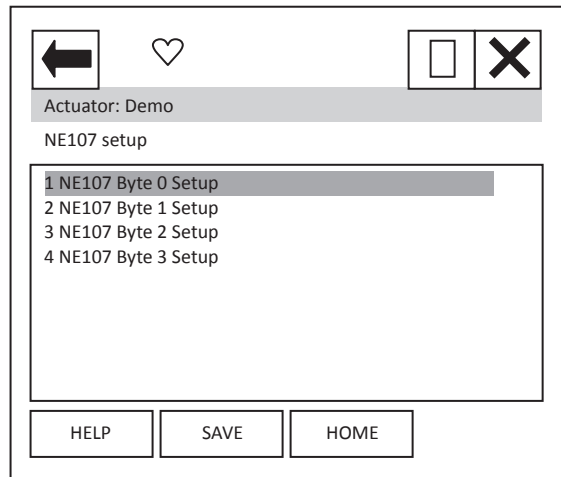
Item 1 'Loop Current' displays the instantaneous value of the loop current as measured by the HFU.

Item 2 'Position demand' displays the % demand that the current input signal is representing.

Item 3 'Deadband (x0.01)%' – displays the deadband applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

### 13. DD File, Emerson Handheld Tools Screen Shots – CMA *continued*

Setup: **NE107 Setup**



When the items 1 to 4 are selected, new pages are displayed.

These four pages are used to set up which alarms bits will cause the NE107 status bits to be set. For each bit listed in the table following, the user is able to select one of the following actions:

- 9) No effect – default
- 10) **Maintenance required**
- 11) Reserved
- 12) **Failure**
- 13) **Out Of Spec.**
- 14) **Function Check**
- 15) Not defined
- 16) Reserved

The four actions highlighted are NE107 status bits.

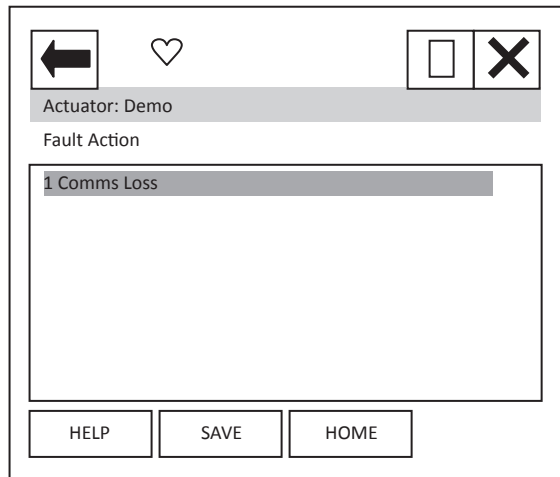
### 13. DD File, Emerson Handheld Tools Screen Shots – CMA *continued*

Table 21 – NE107 Diagnostics Bits, Setup – CMA

	Bit	Description
<b>Byte 0 Setup</b>	1	General Fault
	2	Loss of Demand
	3	Loss of Feedback
	4	Stall Open
	5	Stall Closed
	6	Over Torque Open
	7	Over Torque Close
	8	Over Temperature
<b>Byte 1 Setup</b>	1	Comms Lost (network)
	2	Critical Fault
	3	Monitor relay
	4	Factory data checksum (EE) fault
	5	Customer data checksum (EE) fault
	6	Config. data checksum (EE) fault
	7	In local control mode
	8	At Close Limit
<b>Byte 2 Setup</b>	1	At Open Limit
	2	Local-Stop Knob Selected
	3	Remote Knob Selected
	4	Local Knob Selected
	5	ESD Active
	6	Relay 1 Energized (Main Control PCB)
	7	Relay 2 Energized (Main Control PCB)
	8	Relay 5 Energized (RIRO)
<b>Byte 3 Setup</b>	1	Relay 6 Energized (RIRO)
	2	Relay 7 Energized (RIRO)
	3	Relay 8 Energized (RIRO)
	4	Digital Input 1 (RIRO)
	5	Digital Input 2 (RIRO)
	6	Digital Input 3 (RIRO)
	7	Digital Input 4 (RIRO)
	8	Non-Critical Fault

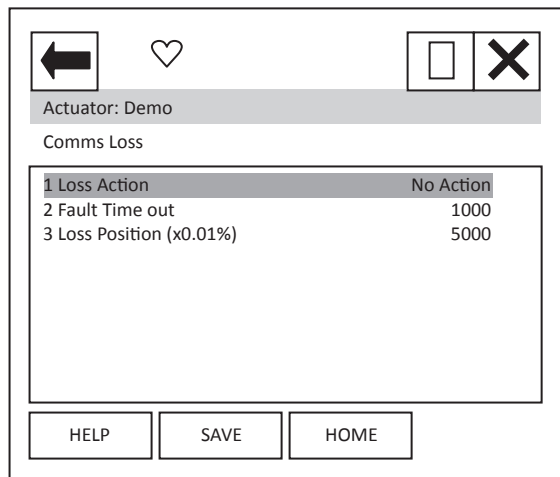
See example in IQ section Table 20.

Setup: **Fault Action**



When item 1 is selected, a new page is displayed.

Setup: **Comms Loss**



Each item can be selected, viewed, and modified where appropriate.

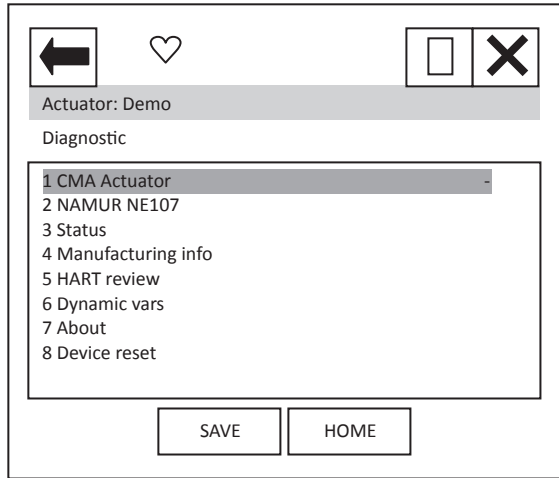
Item 1 'Loss Action' enables the loss of 4-20 mA signal action to be set up. Choices are No Action, Open, Close, Stop and Position.

Item 2 'Fault Time out' enables the timeout for the action to be taken on loss of 4-20 mA signal to be set up. Range is 0 to 65,535 ms.

Item 3 'Loss Position' enables the position value to be entered, for use when the Loss Action of 'Position' has been selected. Range is 0.00 to 100.00%.

### 13.3 Diagnostics

From the top menu, selecting 'Diagnostics' will display the following menu:



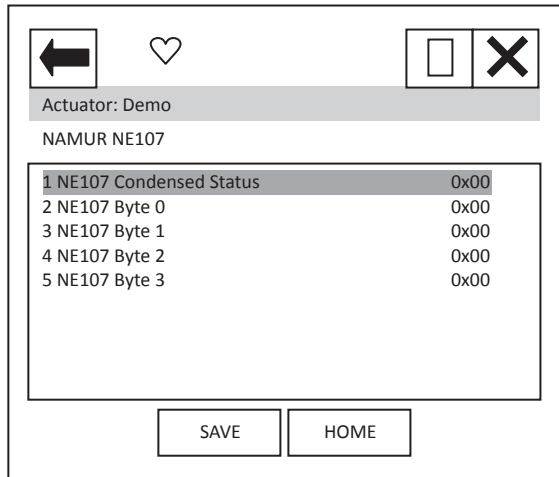
Item 1 'CMA Actuator' indicates the type of actuator.

When the items 2 to 7 are selected, new pages are displayed.

For items 4 to 7 see Section 10.2.

Item 8 'Device reset' will cause a device reset (HART option card only).

Diagnostics: **NAMUR NE107**

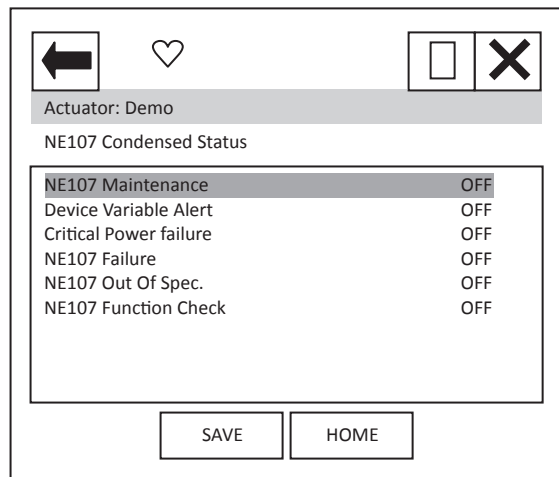


When the items 1 to 4 are selected, new pages are displayed.

Items 2 to 5 select pages which are identical to Status NE107 Alarm Status 0 to 3. – see status section below.

### 13. DD File, Emerson Handheld Tools Screen Shots – CMA *continued*

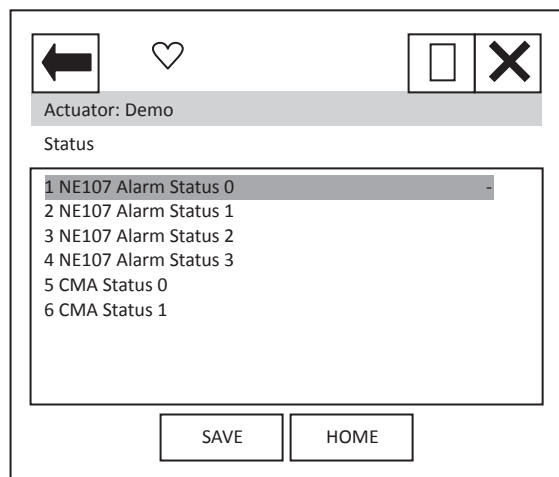
Diagnostics: **NAMUR NE107, NE107 Condensed Status**



These items indicate the status of the alarms bits.

The NE107 bits will be set as 'ON', if one of the alarm bits, that has been associated to the alarm in the NE107 setup section, has activated.

Diagnostics: **Status**



When the items 1 to 5 are selected, new pages are displayed.

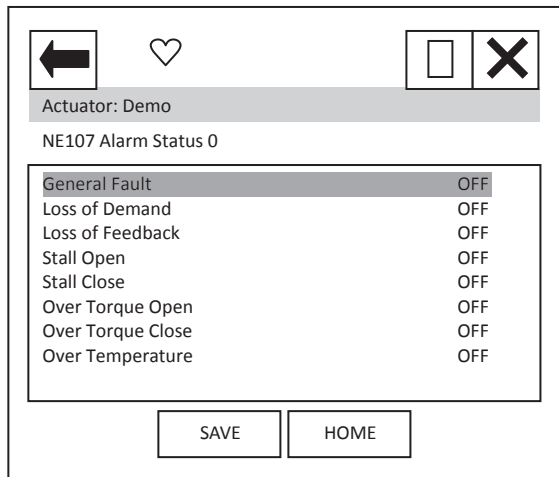
The NE107 items show the status of the alarms bits that are associated to the NE107 diagnostics function.

CMA Status 0 and 1 contain status indication bits.



### 13. DD File, Emerson Handheld Tools Screen Shots – CMA *continued*

Diagnostic: **Status, NE107 Alarm Status 0**



'General Fault' indicates that any fault is present.

'Loss of Demand' indicates that the 4-20 mA signal is not present (note in this state there would be no digital HART communications).

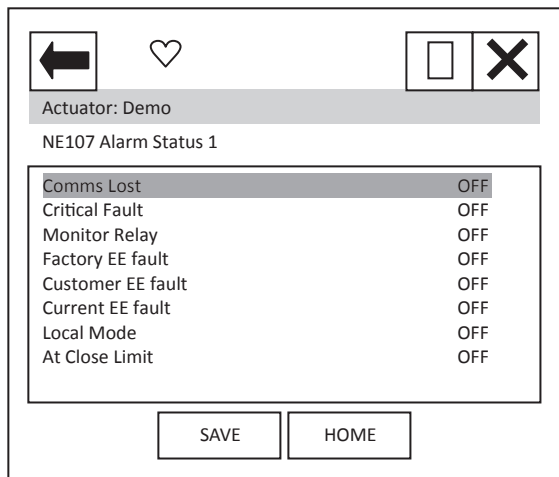
'Loss of Feedback' indicates that the feedback from the position encoder is not present.

'Stall Open' and 'Stall Close' indicate that the actuator has stalled in the stated direction.

'Over Torque Open' and 'Over Torque Close' indicate that an over torque condition has occurred in the stated direction.

'Over Temperature' indicates that the internal actuator temperature has exceeded its limit.

Diagnostic: **Status, NE107 Alarm Status 1**



'Comms Lost' indicates that the network card is not able to communicate on the network – this is unlikely to be seen.

'Critical Fault' indicates that the actuator is disabled under these conditions: Loss of feedback, EEPROM fault, Loss of Demand.

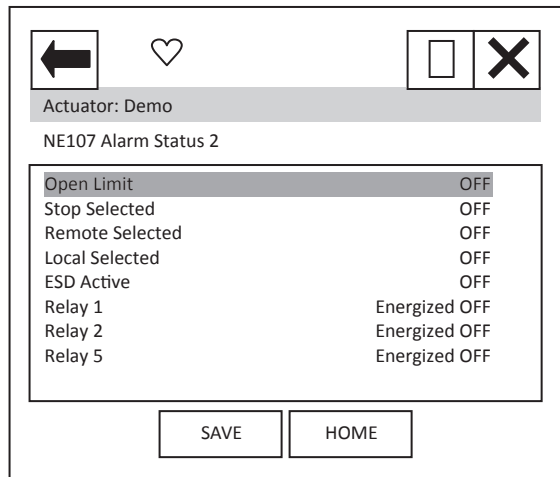
'Monitor Relay' indicates that the actuator monitor relay has tripped – see actuator manual for details.

'Factory EE Fault', 'Customer EE Fault' and 'Current EE Fault' indicates an EEPROM checksum fault in the area indicated.

'Local Mode' indicates that the actuator is in local control mode.

'At Close Limit' indicates that the actuator is at the close limit.

Diagnostic: **Status, NE107 Alarm Status 2**



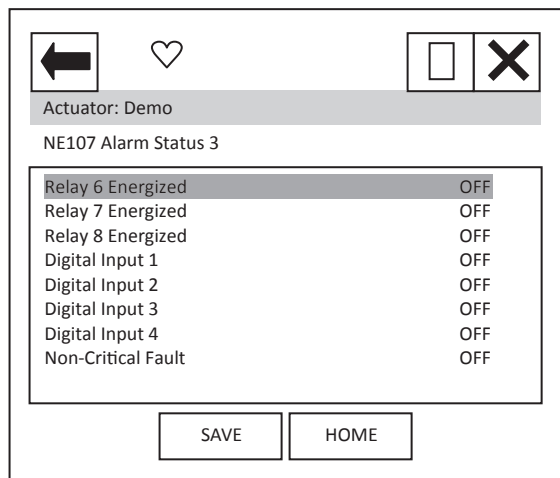
'Open Limit' indicates that the actuator is at the open limit.

'Stop Selected', 'Remote Selected', and 'Local Selected' indicate the status of the external hand control knob.

'ESD Active' indicates that an ESD signal is present.

'Relay x Energised' indicates the status of the relays stated.

Diagnostic: **Status, NE107 Alarm Status 3**



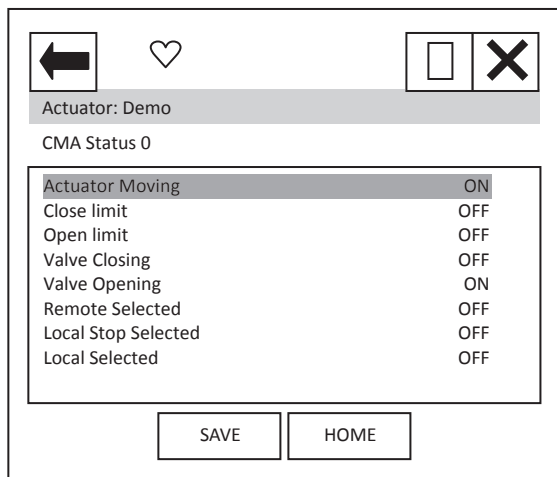
'Relay x Energised' indicates the status of the relays stated.

'Digital Input x', indicates the status of the digital input stated.

'Non-Critical Fault' indicates that a fault is present, but the actuator is not disabled.

### 13. DD File, Emerson Handheld Tools Screen Shots – CMA *continued*

Diagnostic: **Status, CMA Status0**



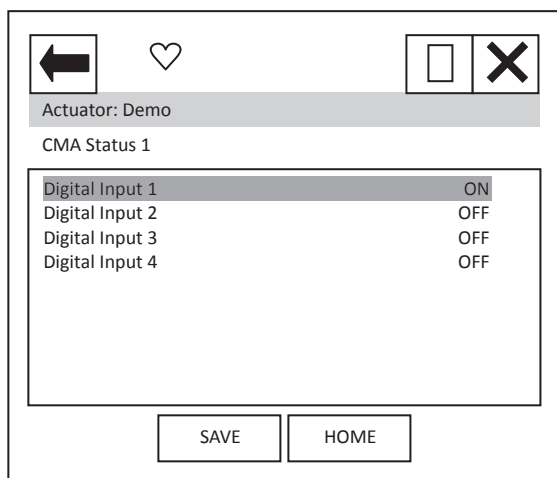
'Actuator Moving' indicates that the actuator is currently moving.

'Close limit' and 'Open limit' indicate if the actuator is at its close or open position limit.

'Valve Closing' and 'Valve Opening' indicate if the actuator is operating the valve in the closing or opening direction.

'Remote Selected', 'Local Stop Selected' and 'Local Selected' indicate the position that the actuator control selection knob is in.

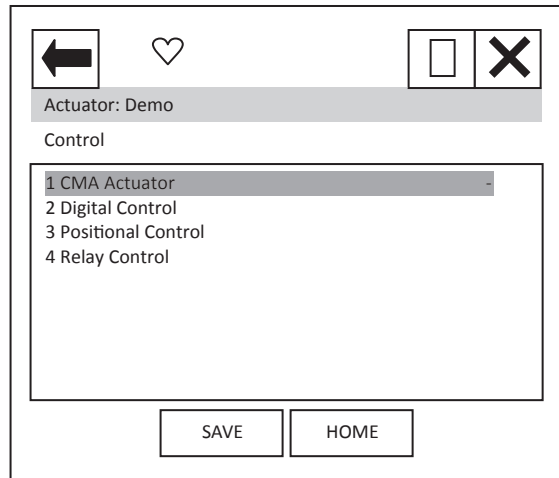
Diagnostic: **Status, CMA Status1**



'Digital input x' indicates the status of the actuator hardwired digital inputs.

### 13.4 Control

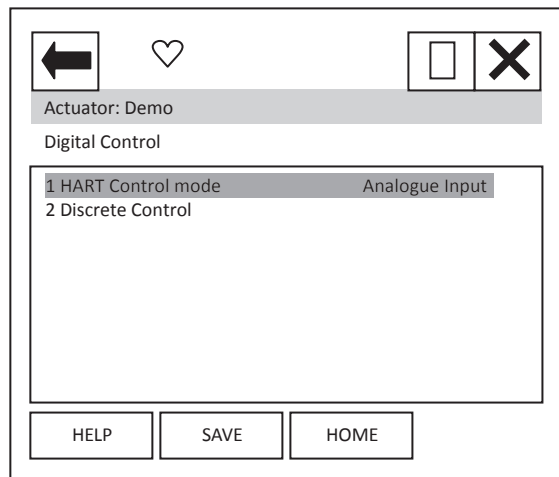
From the top menu, selecting 'Control' will display the following menu:



Item 1 'CMA Actuator' indicates the type of actuator.

When the items 2 to 4 are selected, new pages are displayed.

Control: **Digital Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' displays the mode that is currently in control. It can either be 'Analogue Input', 'Discrete' or 'Digital position'.

Analogue Input indicates that the unit is being controlled with the 4-20 mA analogue input supply.

Discrete indicates that the discrete mode of control is enabled and the actuator can be controlled using discrete open/close/stop etc. commands.

Digital position indicates that control is via a digital position command and the actuator can be controlled using a digital position command in the range 0.0 to 100.0%.

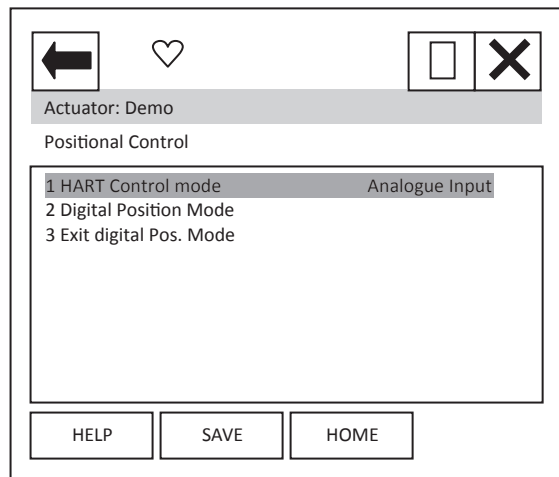
Item 2 selects a new page where the actuator can be operated discretely. Only one command should be selected at one time. The commands available are: Stop, Close, Open, ESD and Enable Digital Control. Commands will not action unless the 'Enable Digital Control' item is also selected. For example, to operate the actuator in the open direction:

- 1) Select the Discrete Control page.
- 2) Set the Open row item to 'ON' using the touch screen button displayed at the bottom of the screen.
- 3) Set the 'Enable Digital Control' row item to 'ON' using the same button.
- 4) Ensure all other rows are 'OFF'.
- 5) Select the Enter button to return you to the previous screen.
- 6) You will notice a '\*' next to the Discrete Control item – this indicates there is data to send for this feature. Select the 'SEND' button.
- 7) The actuator will operate and you will notice that the HART control mode will change to Discrete.

To operate in the close direction, repeat above instructions ensuring that Open is set to 'OFF' and Close is set to 'ON'.

To exit Discrete control mode, the Enable Digital Control row item must be set to 'OFF', the data entered and sent. NOTE that the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.

Control: **Positional Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' as previous menu item.

Item 2 'Digital Position Mode' Selecting this item will start a method which guides the user to enter the digital positioning mode. The sequence is:

On selection, the display changes to 'Entering Forced Mode'. At this point, the user can Abort or select OK to enter this mode.

On selection of OK, the user is warned that the card will be removed from automatic mode – this means that the analogue Input is no longer in control. Again, the user can choose to Abort or select OK to carry on.

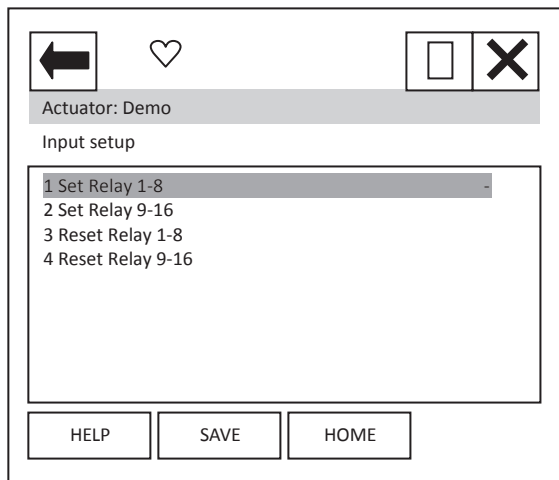
The final page, again has the option to Abort, but selecting OK will enable the user to enter a position value. The Actuator will run to the position selected.

To exit this mode, select Abort at any page.

**NOTE: On Aborting, the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.**

Item 3 'Exit digital Pos. Mode' may be required to exit the digital positioning mode should the handheld tool be disconnected at any time, resulting in the HART card remaining in the digital positioning mode. Selecting this item will return the unit to Analogue Input mode.

Setup: **Relay Control**



Each item can be selected, viewed, and modified where appropriate.

Items 1 to 4 enable the user to operate the 'extra' relays (if fitted) within the actuator. There are 2 sets of items to select for each relay, to activate the relay select the 'Set Relay' item that contains the relay to be set, then change the relay state to 'ON'. To reset the same relay the same item will need to be set to 'OFF' AND, the associated 'Reset Relay' item must be set to 'ON'. To again operate the same relay the 'Reset Relay' item needs to be returned to 'OFF' before selecting 'ON' for the 'Set Relay' item.

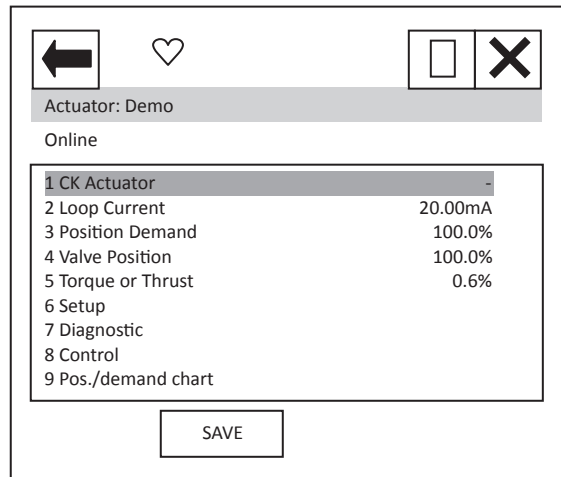
**NOTE: the wiring diagram should be checked to confirm which relays are present within the actuator. The CMA is capable of having Relays 1-2 and 5-8 fitted.**

## 14. DD File, Emerson Handheld Tools Screen Shots – CK

The DD file describes the HART device. There are 2 sets of DD files available; for use by a DCS and for use by the Emerson handheld tools. The following pages show screen shots from the Emerson handheld tools, indicating the data and functions that can be accessed using the DD files. Also shown are views likely to be seen using the DCS.

### 14.1 Top Menu

When the items 2 to 6 are selected, the display changes to show the data selected.



Item 1 'CK Actuator' indicates the type of actuator.

Item 2 'Loop Current' displays the instantaneous value of the current, as measured by the HFU.

Item 3 'Position Demand' displays the percent (%) demand that the current is representing.

Item 4 'Valve Position' displays the valve position.

Item 5 'Torque or Thrust' displays the torque or thrust present at the output of the actuator.

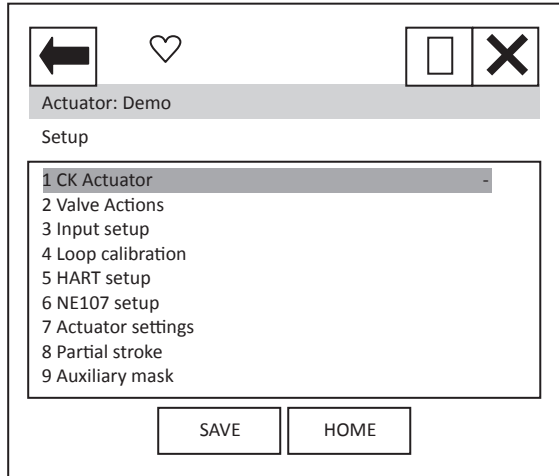
Selection of items 6 to 9 will bring up new menus, detailed in the following sections.

For item 9 see Section 10.3.



### 14.2 Setup

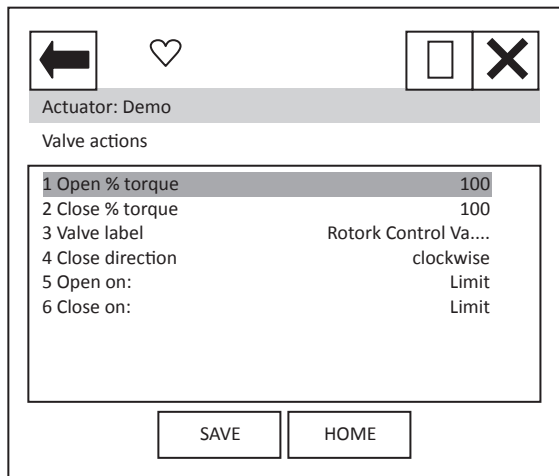
From the top menu, selecting 'Setup' will display the following menu:



Item 1 'CK Actuator' indicates the type of actuator.

When the items 2 to 9 are selected, new pages are displayed.

Setup: **Valve actions**



Each item can be selected, viewed, and modified where appropriate:

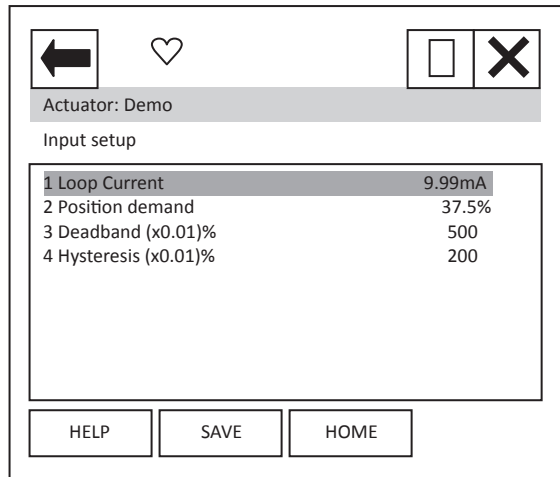
Items 1 and 2 Open and Close torque; can be modified between 40 and 100%.

Item 3 cannot be modified.

Item 4 can be modified between clockwise or anti-clockwise.

Items 5 and 6 can be modified between Limit and Torque

Setup: **Input setup**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'Loop current' displays the instantaneous value of the loop current as measured by the HFU.

Item 2 'Position demand' displays the % demand that the current input signal is representing.

Item 3 'Deadband' – displays the deadband applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

Item 4 'Hysteresis' – displays the hysteresis applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Setup: **Loop calibration**

Loop calibration	
1 Calibrate current	
2 Loop current	9.99mA
3 Position demand	37.5%
4 Current zero	4.00mA
5 Current gain	20.00mA
6 PV LRV	0.00%
7 PV URV	100.00%

Each item can be selected, viewed, and modified where appropriate.

Item 1 'Calibrate current' displays the function to calibrate the loop current.

Item 2 'Loop current' displays the instantaneous value of the current as measured by the HFU.

Item 3 'Position demand' displays the percent (%) demand that the current is representing.

Item 4 'Current zero' displays current zero setting; not modifiable.

Item 5 'Current gain' displays current gain settings; not modifiable.

Item 6 'PV LRV' shows the HART Primary Value Lower Range Value; can be modified.

Item 7 'PV URV' shows the HART Primary Value Upper Range Value; can be modified.

Setup: **HART setup**

HART setup	
1 Poll addr	0
2 Loop current mode	Enabled
3 Tag	demo
4 Long tag	demonstration actuator
5 message	message goes here
6 Descriptor	HART Actuator
7 Date	27/10/2009
8 Final assembly num	0
9 Snsr s/n	0

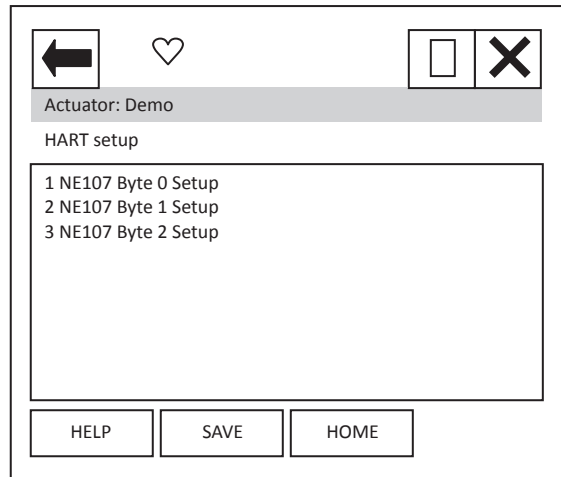
Each item can be selected, viewed, and modified where appropriate.

Item 1 'Poll addr' displays the HART address of the device; can be changed in the range 0-63.

Item 2 'Loop current mode' can be enabled or disabled. When disabled the actuator will not position to the analogue signal, but the unit can be commanded to a position via command 79 – see Section 8. Care should be taken when changing to enabled as the actuator may move.

Items 3 to 9 are all text fields that can be modified by the user.

Setup: **NE107 Setup**



When the items 1 to 3 are selected, new pages are displayed.

These 3 pages are used to set up which alarms bits will cause the NE107 status bits to be set. For each bit listed in Table 22, the user is able to select one of the following actions:

1. No effect – default
2. **Maintenance required**
3. Reserved
4. **Failure**
5. **Out Of Spec.**
6. **Function Check**
7. Not defined
8. Reserved

The 4 actions highlighted are the NE107 status bits.

14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Table 22 – NE107 Diagnostics Bits, Setup – CK

	Bit	Description
<b>Byte 0 Setup</b>	1	reserved
	2	Local Control Fault
	3	Power Fault
	4	Thermostat Tripped
	5	reserved
	6	reserved
	7	Hi Hi Trip Service Alarm (Hi Hi Torque level exceeded)
	8	Hi Trip Service Alarm (Hi Torque level exceeded)
<b>Byte 1 Setup</b>	1	Valve Error
	2	reserved
	3	Monitor Relay
	4	Control Fail
	5	Actuator Fail
	6	Communications Fail
	7	Hardware Option Fail
	8	Partial Stroke Error
<b>Byte 2 Setup</b>	1	reserved
	2	Actuator Stalled
	3	DSM Service Required
	4	End of Travel Timer (expired)
	5	Fieldbus Fault
	6	24VDC Customer Supply Fail
	7	reserved
	8	Wrong Direction

## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

For example: A user requires NE107 Failure indication for faults within the actuator positioner and in the local controls, but treats the actuator being in Local, valve obstructed or High torque as requiring someone to go and check the device. If the thermostat trips the user would like an Out of spec alarm to be raised as the device is being used out of its specification and finally for Hi Hi torque the user wants to call in maintenance. For this setup, the following setup would apply:

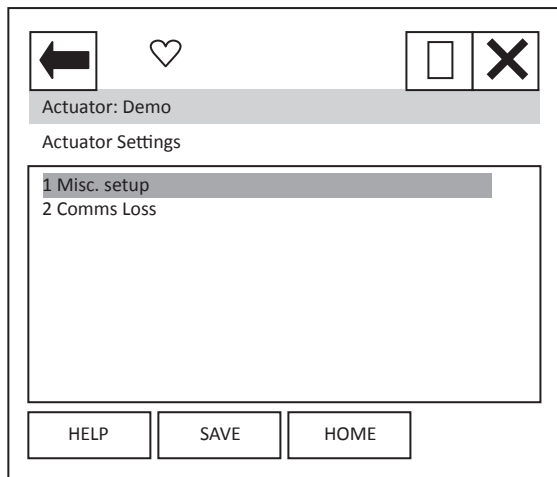
*Table 23 – NE107 Diagnostics Bits, Example setup – CK*

	Description	Action
Byte 0 Setup	reserved	No effect
	Local Control Fault	<b>Failure</b>
	Power Fault	No effect
	Thermostat Tripped	<b>Out of Spec</b>
	reserved	No effect
	reserved	No effect
	Hi Hi Trip Service Alarm (Hi Hi Torque level exceeded)	<b>Maintenance</b>
	Hi Trip Service Alarm (Hi Torque level exceeded)	<b>Function Check</b>
Byte 1 Setup	Valve Error	<b>Function Check</b>
	reserved	No effect
	Monitor relay	<b>Function Check</b>
	Control Fail	No effect
	Actuator Fail	No effect
	Communications Fail	No effect
	Hardware Option Fail	No effect
	Partial Stroke Error	No effect
Byte 2 Setup	reserved	No effect
	Actuator Stalled	No effect
	DSM Service Required	<b>Failure</b>
	End of Travel Timer (expired)	No effect
	Fieldbus Fault	No effect
	24VDC Customer Supply Fail	No effect
	reserved	No effect
	Wrong Direction	No effect

With these settings the bits defined in the Diagnostics page condensed data (see later) will be set if one of the enabled bits above is set i.e. NE107 Failure will be ON if either there is a local control fault OR an actuator positioner fault.

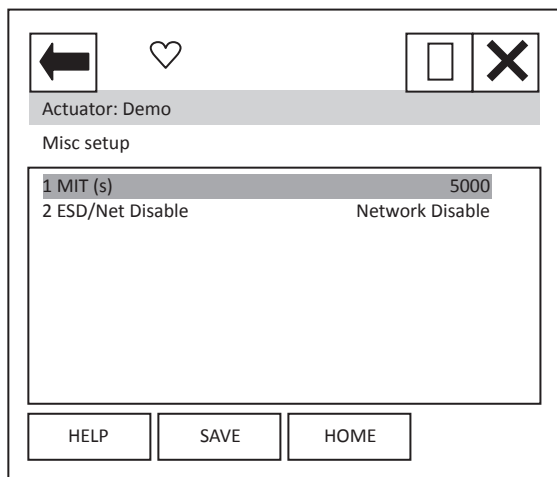
## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Setup: **Actuator Settings**



When the items 1 to 2 are selected, new pages are displayed.

Setup: **Actuator Settings, Misc setup**

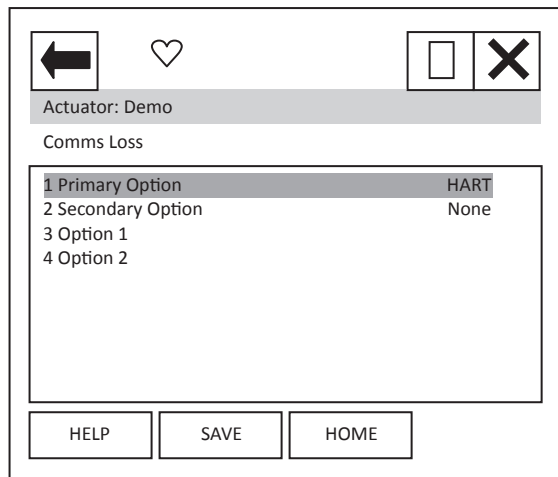


Each item can be selected, viewed, and modified where appropriate.

Item 1 'MIT' displays the Motion Inhibit Timer used in positioning, can be modified between 0 and 255 seconds, **the scale is milli seconds** therefore 5000 is 5 seconds.

Item 2 'ESD/Net Disable' displays the function setting for the ESD auxiliary input. Can be set to either the ESD function OR to operate as a network command disable signal.

Setup: **Actuator Settings, Comms Loss**

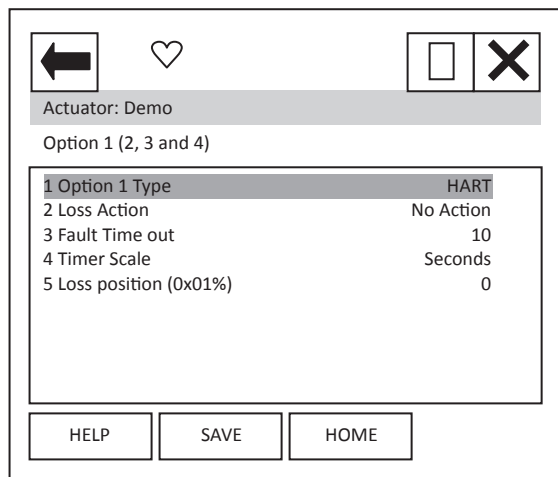


Item 1 'Primary Option' shows the option card that has been selected as source 1 in the CK menu.

Item 2 'Secondary Option' shows the option card that has been selected as source 2 in the CK menu.

When the items 3 to 4 are selected, new pages are displayed to show the Comms loss settings of the option cards fitted. The CK can have up to 2 option cards fitted. It should be noted that only the card that is in control, as defined by the control source selection parameter in the CK, will cause the action to be taken on loss of signal.

Setup: **Actuator Settings, Comms Loss (Option 1 and 2)**



Item 1 'Option 1 Type' shows the option card that is listed as option 1 in the CK options fitted menu.

Item 2 'Loss Action' enables the loss of 4-20mA signal action to be set up. Choices are No Action, Open, Close, Stop and Position.

Item 3 'Fault Time out' enables the timeout for the action to be taken on loss of 4-20mA signal to be set up. Range dependent on item 4.

Item 4 'Timer Scale' enables the timeout scale to be set to either Seconds or milli-Seconds.

Item 5 'Loss Position' enables the position value to be entered, for use when the Loss Action of 'Position' has been selected. Range is 0.00 to 100.00%.

The menu for Option 2 is identical.



## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Setup: **Partial Stroke**

Item	Value
1 PS Enable	Enabled
2 PS travel (x0.01)%	9000
3 PS Stroke Limit	Open Limit
4 PS Timeout 1 (x0.0001s)	150000
5 PS Timeout 2 (x0.0001s)	150000

Each item can be selected, viewed, and modified where appropriate.

Item 1 'PS Enable' enables the Partial Stroke feature to be enabled and disabled.

Item 2 'PS travel (x0.01)%' enables the position to which the unit will travel on activation of a partial stroke command to be set up. Range is 0-100% in 0.01% steps.

Item 3 'PS Stroke Limit' enables the position of the actuator from which the partial stroke command can be activated to be set up. Either the open or the close limit.

Item 4 and 5 'PS Timeout 1/2 (x0.0001s)' enables the timeout for reaching the position (Timeout 1) then returning to the limit (Timeout 2) to be set up.

Setup: **Auxiliary Mask**

Item	Value
1 Aux 1 Function	Open Command
2 Aux 2 Function	Close Command
3 Aux 3 Function	Digital Input
4 Aux 4 Function	Digital Input
5 Aux 1 I/P Type	NO Contact
6 Aux 2 I/P Type	NO Contact
7 Aux 3 I/P Type	NC Contact
8 Aux 4 I/P Type	NC Contact

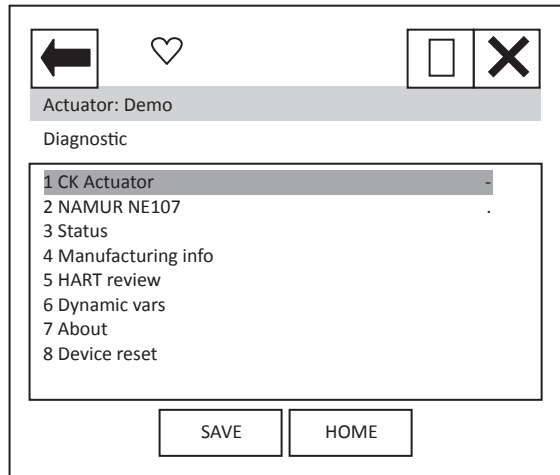
Each item can be selected, viewed, and modified where appropriate.

Items 1 to 4 'Aux 1/2/3/4 Function' enables the function of the Auxiliary inputs to be set up. Either to be a digital input or to a command.

Items 5 to 8 'Aux 1/2/3/4 I/P Type' enables the contact type of the Auxiliary inputs to be set up. Either NO (Normally Open) or NC (Normally Closed).

### 14.3 Diagnostics

From the top menu, selecting 'Diagnostics' will display the following menu:

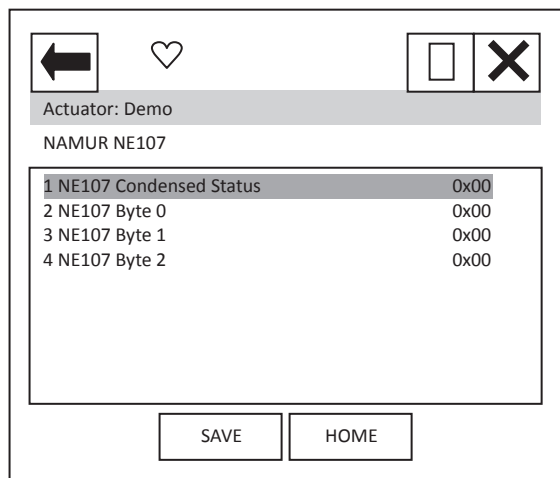


Item 1 'CK Actuator' indicates the type of actuator

When the items 2 to 7 are selected, new pages are displayed.

Item 8 'Device reset' will cause a device reset (HART option card only).

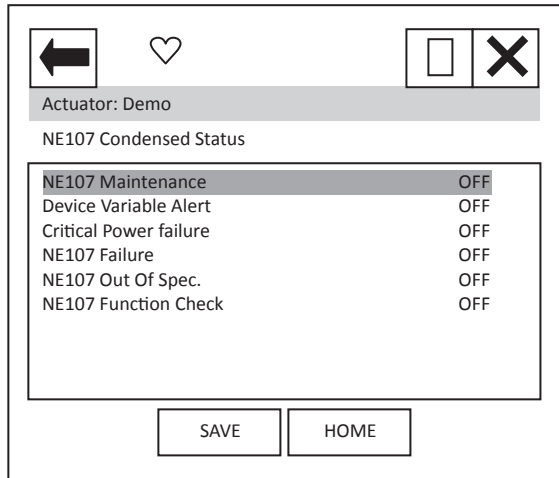
Dagnostic: **NAMUR NE107**



When the items 1 to 4 are selected, new pages are displayed.

Items 2 to 4 select pages which are identical to Status NE107 Alarm Status 0 to 2 – see status section.

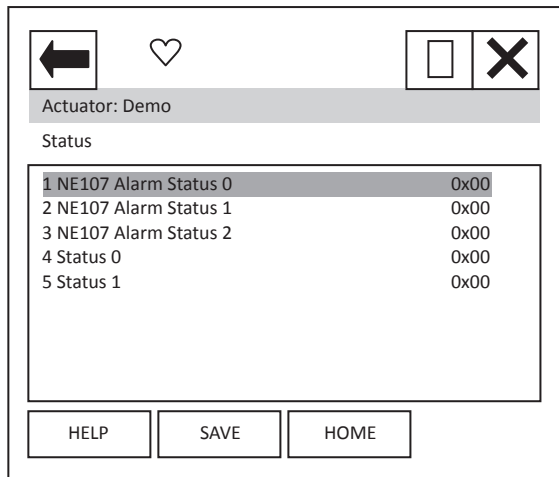
Diagnostic: **NAMUR NE107, NE107 Condensed Status**



These items indicate the status of the alarms bits.

The NE107 bits will be set as 'ON', if one of the alarm bits, that has been associated to the alarm in the NE107 setup section, has activated.

Diagnostic: **Status**



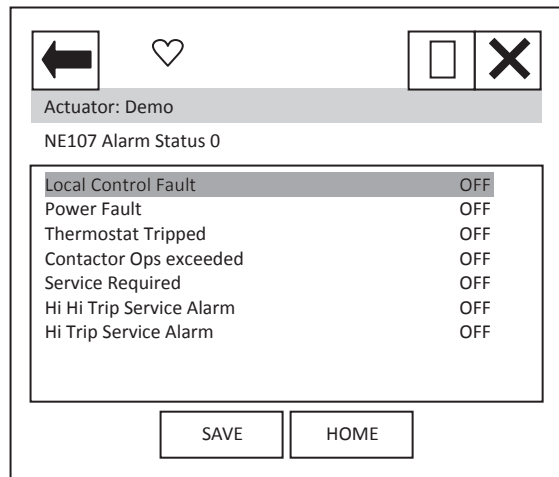
When the items 1 to 5 are selected, new pages are displayed.

The NE107 items show the status of the alarms bits that are associated to the NE107 diagnostics function.

Status 0 and 1 are status indication bits.

## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Diagnostic: **Status, NE107 Alarm Status 0**



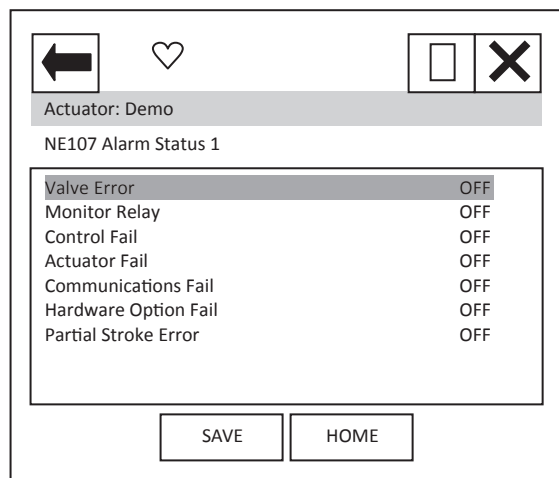
'Local Control Fault' indicates that there is a fault in the actuator's local controls.

'Power Fault' indicates that there is a fault in the actuator's power supply.

'Thermostat Tripped' indicates that the actuators motor thermostat has tripped.

'Hi Hi Trip Service Alarm' and 'Hi Trip Service Alarm' indicates that the levels set for the Hi Hi and Hi torque levels have been exceeded.

Diagnostic: **Status, NE107 Alarm Status 1**



'Valve Error' indicates that the actuator has tripped/stopped on torque due to an obstruction in the valve.

'Monitor Relay' indicates that the actuator monitor relay has tripped – see actuator manual for details.

'Control Fail' and 'Actuator Fail' indicates that the actuator has experienced a control or actuator failure.

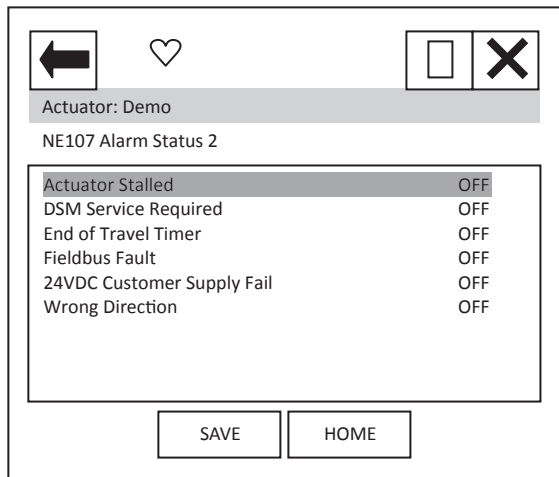
'Communications Fail' indicates that the network card is not able to communicate on the network.

'Hardware Option Fail' indicates a problem with the option card.

'Partial Stroke Error' indicates a failure in the partial stroke test.

## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Diagnostic: **Status, NE107 Alarm Status 2**



'Actuator Stalled' indicates that the actuator has stalled.

'DSM Service Required' indicates a fault in the Digital Switch Mechanism.

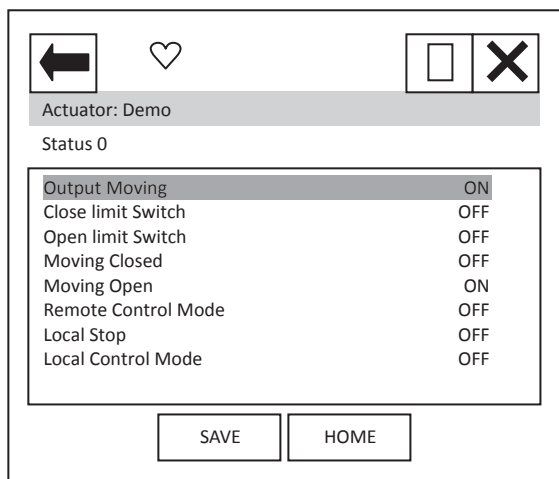
'End of Travel Timer' indicates that there has been excessive travel beyond a limit.

'Fieldbus Fault' indicates a fault with the network card.

'24VDC Customer Supply Fail' indicates a fault with the supply available to the customer.

'Wrong Direction' indicates that the actuator has operated in the incorrect direction.

Diagnostic: **Status, Status0**



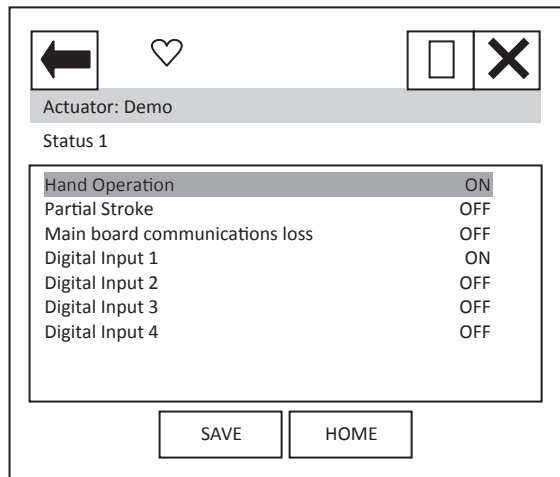
'Output Moving' indicates that the actuator is currently moving.

'Close limit Switch' and 'Open limit Switch' indicate if the actuator is at its close or open position limit.

'Moving Closed' and 'Moving Open' indicates if the actuator is operating the valve in the closing or opening direction.

'Remote Control Mode', 'Local Stop' and 'Local Control Mode' indicate the position that the actuator control selection knob is in.

Diagnostic: **Status, Status1**



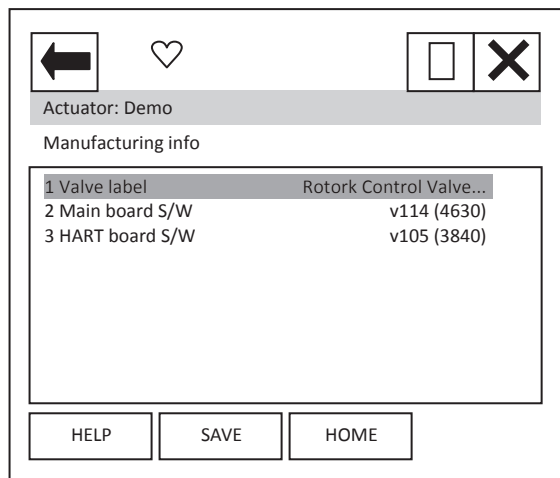
'Hand Operation' indicates that the actuator is currently moving under manual / hand control.

'Partial Stroke' indicates the actuator is performing a partial stroke test.

'Main board communications loss' indicates an internal actuator communication problem.

'Digital Input 1/2/3/4' indicates the status of the actuator hardwired digital inputs.

Diagnostic: **Manufacturing info**



Each item can be selected and viewed.

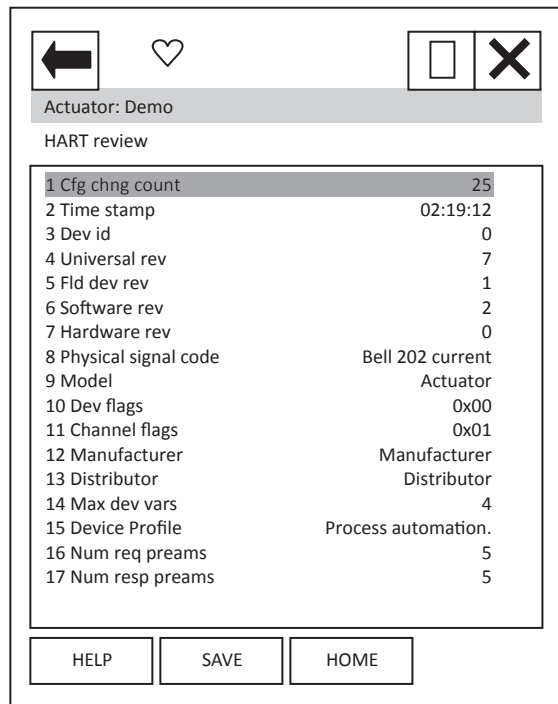
Item 1 is the valve label.

Item 2 is the main board software version number.

Item 3 is the HART board software version number.

## 14. DD File, Emerson Handheld Tools Screen Shots – CK *continued*

Diagnostic: **HART review**



Each item can be selected and viewed.

Item 1 indicates the number of times a configuration change has been made.

Item 2 'Time Stamp' this timer is reset to zero every time the HART device is reset. Every 24 hours it rolls over.

Items 3-7 indicate revisions of the HART device.

Item 8 shows the physical layer code.

Item 9 'Model' indicates the model type for the device – 'Actuator'.

Items 10 and 11 are HART related flags.

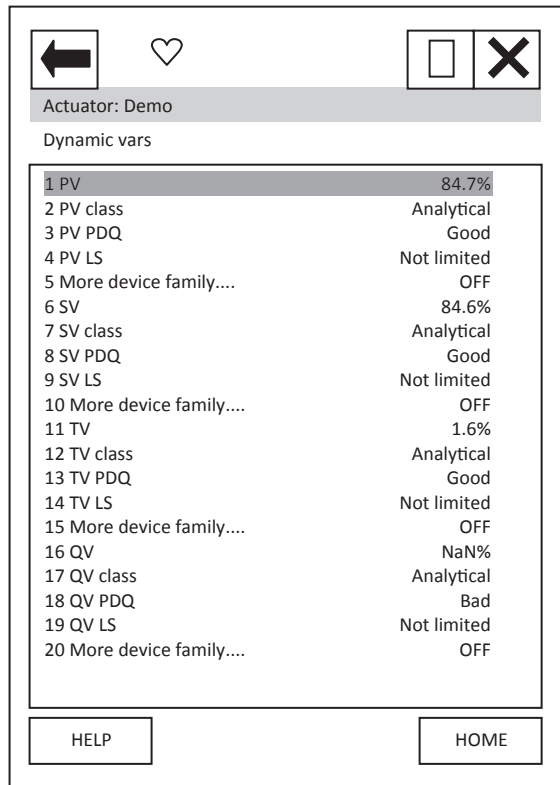
Items 12 and 13 indicate the manufacturer and the distributor of the device.

Item 14 indicates the maximum number of variables on the HART device i.e. PV etc.

Item 15 indicates the device profile.

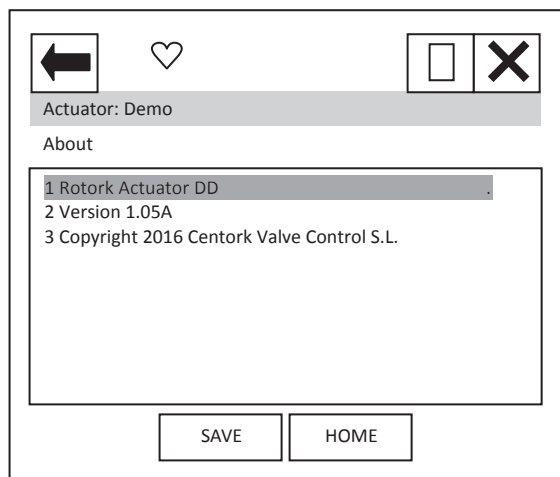
Items 16 and 17 indicate the number of pre-ambls expected for request and response messages.

Diagnostic: **Dynamic vars**



This page details information about the dynamic variables. Each item can be selected and viewed.

Diagnostic: **About**

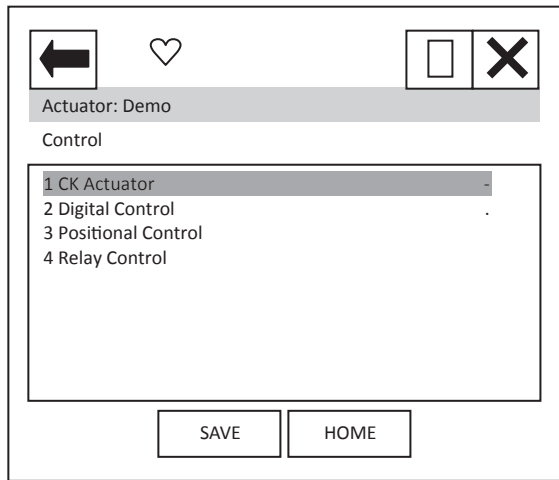


Device Description About box.



### 14.4 Control

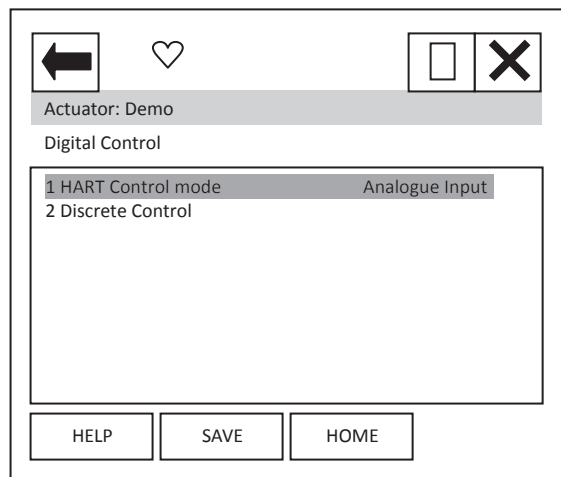
From the top menu, selecting 'Control' will display the following menu:



Item 1 'CK Actuator' indicates the type of actuator

When the items 2 to 4 are selected, new pages are displayed.

Control: **Digital Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' displays the mode that is currently in control. It can either be 'Analogue Input', 'Discrete' or Digital position'.

Analogue Input indicates that the unit is being controlled with the 4-20mA analogue input supply.

Discrete indicates that the discrete mode of control is enabled and the actuator can be controlled using discrete open/close/stop etc. commands.

Digital position indicates that control is via a digital position command and the actuator can be controlled using a digital position command in the range 0.0 to 100.0%.

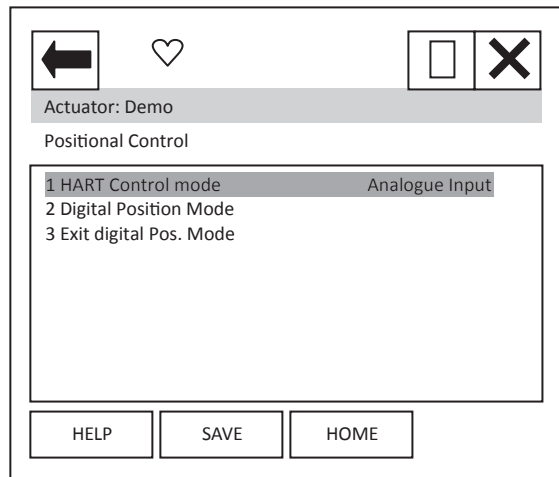
Item 2 selects a new page where the actuator can be operated discretely. Only one command should be selected at one time. The commands available are: Stop, Close, Open, ESD, Partial Stroke Test and Enable Digital Control. Commands will not action unless the 'Enable Digital Control' item is also selected. For example, to operate the actuator in the open direction:

1. Select the Discrete Control page
2. Set the Open row item to 'ON' using the touch screen button displayed at the bottom of the screen
3. Set the 'Enable Digital Control' row item to 'ON' using the same button
4. Ensure all other rows are 'OFF'
5. Select the Enter button to return you to the previous screen
6. You will notice a '\*' next to the Discrete Control item – this indicates there is data to send for this feature. Select the 'SEND' button.
7. The actuator will operate and you will notice that the HART control mode will change to Discrete.

To operate in the close direction repeat above instructions ensuring that Open is set to 'OFF' and Close is set to 'ON'

To exit Discrete control mode, the Enable Digital Control row item must be set to 'OFF', the data entered and sent. NOTE that the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.

Control: **Positional Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' as previous menu item.

Item 2 Selecting this item will start a method which guides the user to enter the digital positioning mode. The sequence is:

1. On selection, the display changes to 'Entering Forced Mode' at this point the user can Abort or select OK to enter this mode.

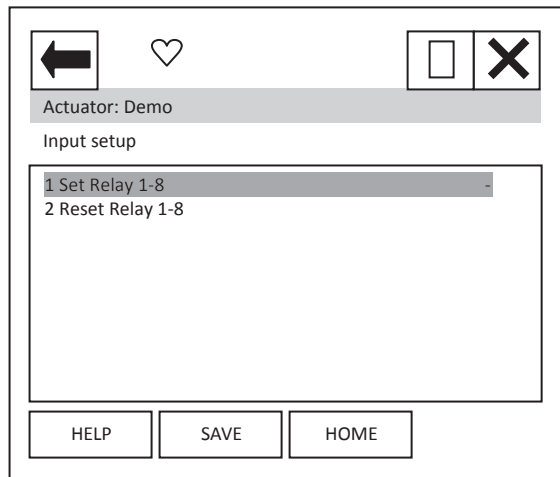
On selection of OK the user is warned that the card will be removed from automatic mode – this means that the analogue Input is no longer in control. Again the user can choose to Abort or select OK to carry on.

2. The final page, again has the option to Abort, but selecting OK will enable the user to enter a position value. The Actuator will run to the position selected.
3. To exit this mode select Abort at any page.

**NOTE: On Aborting, the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.**

Item 3 may be required to exit the digital positioning mode should the handheld tool be disconnected at any time, resulting in the HART card remaining in the digital positioning mode. Selecting this item will return the unit to Analogue Input mode.

Control: **Relay Control**



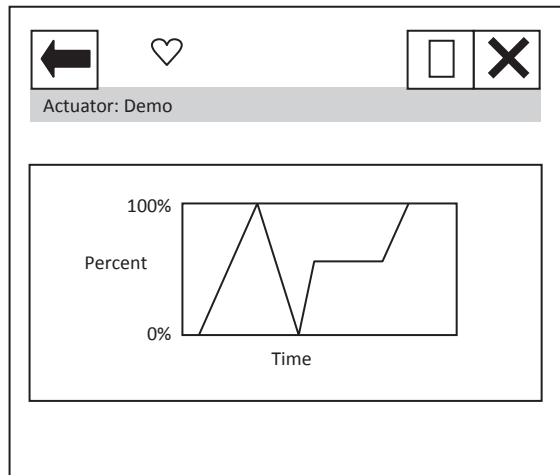
Each item can be selected, viewed, and modified where appropriate.

Items 1 to 2 enable the user to operate the 'extra' relays (if fitted) within the actuator. There are 2 sets of items to select for each relay, to activate the relay select the 'Set Relay' item that contains the relay to be set, then change the relays state to 'ON'. To reset the same relay the same item will need to be set to 'OFF' AND, the associated 'Reset Relay' item must be set to 'ON'. To again operate the same relay the 'Reset Relay' item needs to be returned to 'OFF' before selecting on for the 'Set Relay' item.

**NOTE: The wiring diagram should be checked to confirm which relays are present within the actuator. The CK can have up to 8 relays fitted.**

### 14.5 Pos / Demand Chart

From the top menu, selecting 'Pos./demand chart' will display the chart of position demand or valve position against time. This will only display if the handheld tool has a graphics licence.

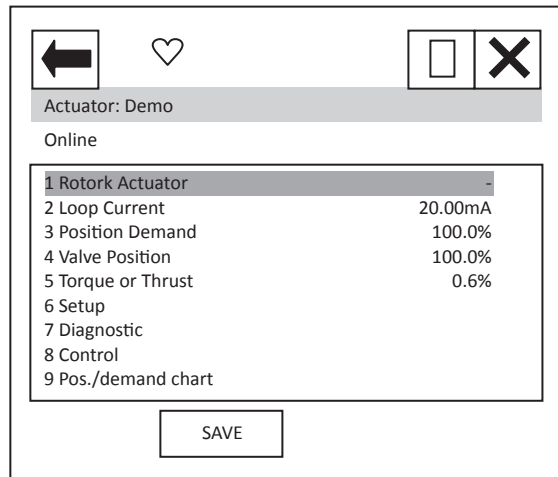


## 15. DD File, Emerson Handheld Tools Screen Shots – SI

The DD file describes the HART device. There are 2 sets of DD files available on the Rotork web site, for use by a DCS and for use by the Emerson handheld tools. The following pages show screen shots from the Emerson handheld tools, indicating the data and functions that can be accessed using the DD files.

### 15.1 Top Menu

When the items 2 to 6 are selected, the display changes to show the data selected.



Item 1 'Rotork Actuator' indicates the type of actuator.

Item 2 'Loop current' displays the instantaneous value of the current, as measured by the HFU.

Item 3 'Position demand' displays the percent (%) demand that the current is representing.

Item 4 'Valve position' displays the valve position.

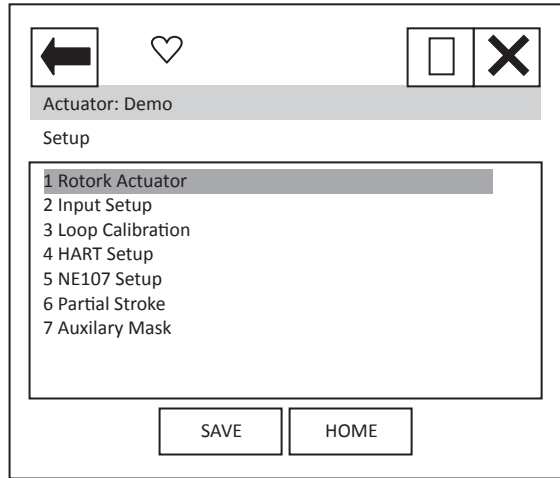
Item 5 'Torque or Thrust' displays the torque or thrust present at the output of the actuator.

Selection of items 6 to 9 will bring up new menus, detailed in the following sections.

For item 9 see Section 10.3.

### 15.2 Setup

From the top menu, selecting 'Setup' will display the following menu:

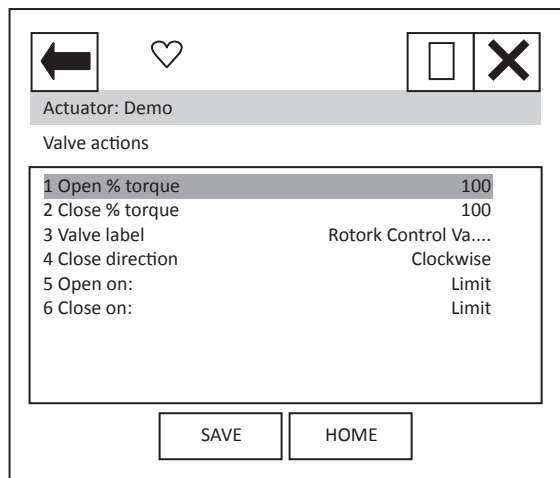


Item 1 'Rotork Actuator' indicates the type of actuator.

When the items 2 to 7 are selected, new pages are displayed.

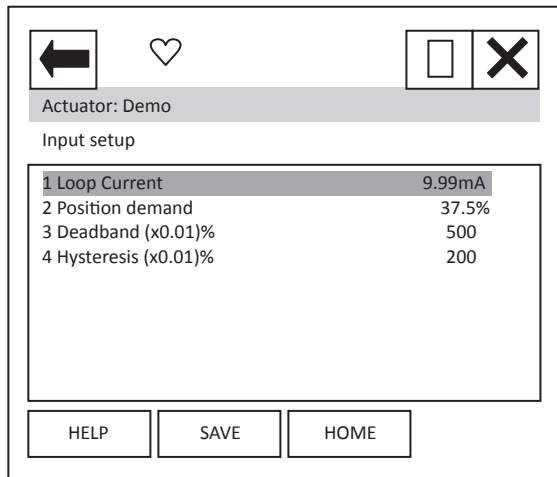
For items 3 and 4 see Section 10.1.

Setup: **Valve actions** (Not applicable for SI3 and SI4, although the menu appears)



## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Setup: **Input setup**



Each item can be selected, viewed, and modified where appropriate.

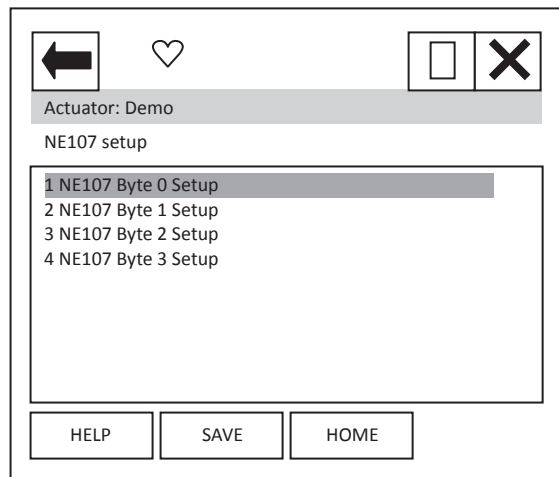
Item 1 'Loop current' displays the instantaneous value of the loop current as measured by the HFU.

Item 2 'Position demand' displays the % demand that the current input signal is representing.

Item 3 'Deadband' – displays the deadband applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

Item 4 'Hysteresis' – displays the hysteresis applied to the demand signal; can be modified between the range 0 (0%) and 1500 (15.00%) in 0.01% increments.

Setup: **NE107 Setup**



When the items 1 to 4 are selected, new pages are displayed.

These 4 pages are used to set up which alarms bits will cause the NE107 status bits to be set. For each bit listed in the table following, the user is able to select one of the following actions:

- 1) No effect – default
- 2) **Maintenance required**
- 3) Reserved
- 4) **Failure**
- 5) **Out Of Spec.**
- 6) **Function Check**
- 7) Not defined
- 8) Reserved

The four actions highlighted are NE107 status bits.



15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Table 24 – NE107 Diagnostics Bits, Setup – SI

	Bit	Description
<b>Byte 0 Setup</b>	1	Battery Low
	2	Local Control Fault
	3	Power supply Fault
	4	Thermostat Tripped
	5	Contactors Operations Exceeded
	6	Service Required
	7	Hi Hi Torque level
	8	High Torque Level
<b>Byte 1 Setup</b>	1	Valve obstructed
	2	Total Turns Exceeded
	3	Monitor relay
	4	Control Failure
	5	Actuator failure
	6	Network Comms lost
	7	Option not detected
	8	Partial stroke Fail
<b>Byte 2 Setup</b>	1	Motor Starts Exceeded
	2	Actuator Stalled
	3	Position Limp Home
	4	End Travel Movement
	5	Network Fault
	6	Output Supply Fault
	7	Valve Time Exceeded
	8	Drive Direction Fault

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

For example: A user requires NE107 Failure indication for faults within the actuator positioner and in the local controls, but treats the actuator being in Local, valve obstructed or High torque as requiring someone to go and check the device. If the thermostat trips or the motor starts are exceeded the user would like an Out of spec alarm to be raised as the device is being used out of its specification and finally for Hi Hi torque the user wants to call in maintenance. For this setup the following setup would apply:

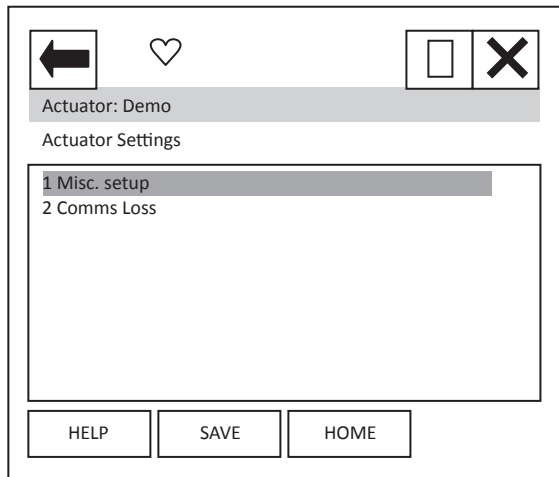
Table 25 – NE107 Diagnostics Bits, Example setup – SI

	Description	Action
<b>Byte 0 Setup</b>	Battery Low	No effect
	Local Control Fault	<b>Failure</b>
	Power Supply Fault	No effect
	Thermostat Tripped	<b>Out of Spec</b>
	Contactors Operations Exceeded	No effect
	Service Required	No effect
	Hi Hi Torque level	<b>Maintenance</b>
	High Torque Level	<b>Function Check</b>
<b>Byte 1 Setup</b>	Valve Obstructed	<b>Out of Spec</b>
	Total Turns Exceeded	No effect
	Monitor Relay	<b>Function Check</b>
	Control Failure	No effect
	Actuator Failure	No effect
	Network Comms Lost	No effect
	Option Not Detected	No effect
	Partial Stroke Fail	No effect
<b>Byte 2 Setup</b>	Motor Starts Exceeded	Function Check
	Actuator Stalled	No effect
	Position Limp Home	<b>Failure</b>
	End Travel Movement	No effect
	Network Fault	No effect
	Output Supply Fault	No effect
	Valve Time Exceeded	No effect
	Drive Direction Fault	No effect

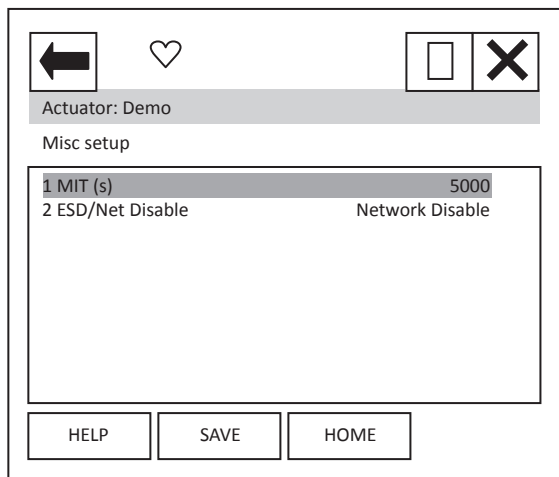
With these settings, the bits defined in the Diagnostics page condensed data (see later) will be set if one of the enabled bits above is set i.e. NE107 Failure will be ON if either there is a local control fault OR an actuator positioner fault.

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Setup: **Actuator Settings** (Not applicable for SI3 or SI4)

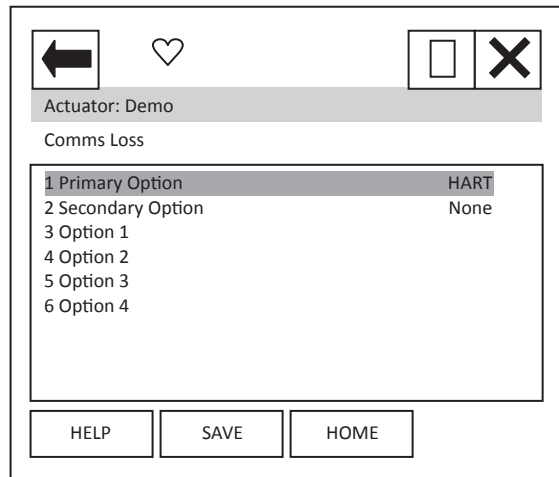


Setup: **Actuator Settings, Misc setup** (Not applicable for SI3 or SI4)



## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Setup: **Actuator Settings, Comms Loss**

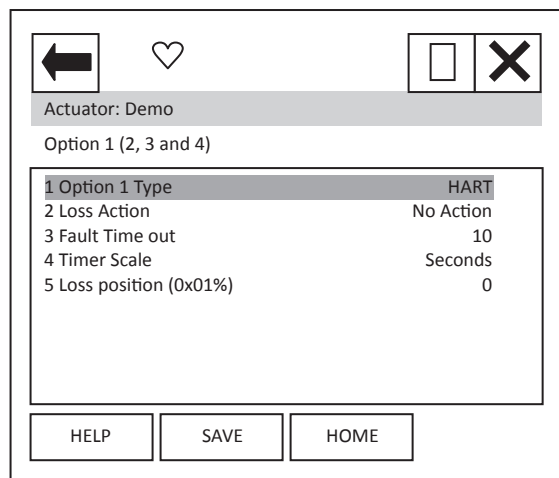


Item 1 'Primary Option' shows the option card that has been selected as source 1 in the SI menu.

Item 2 'Secondary Option' shows the option card that has been selected as source 2 in the SI menu.

When the items 3 to 6 are selected, new pages are displayed to show the Comms loss settings of the option cards fitted. The SI can have up to 4 option cards fitted. It should be noted that only the card that is in control, as defined by the control source selection parameter in the SI, will cause the action to be taken on loss of signal.

Setup: **Actuator Settings, Comms Loss, Option 1 (2, 3 and 4)** (Not applicable for SI3 or SI4)



Item 1 'Option 1 Type' shows the option card that is listed as option 1 in the SI options fitted menu.

Item 2 'Loss Action' enables the loss of 4-20mA signal action to be set up. Choices are No Action, Open, Close, Stop and Position.

Item 3 'Fault Time out' enables the timeout for the action to be taken on loss of 4-20 mA signal to be set up. Range dependent on item 4.

Item 4 'Timer Scale' enables the timeout scale to be set to either Seconds or milli-Seconds.

Item 4 'Loss position' enables the position value to be entered, for use when the Loss Action of 'Position' has been selected. Range is 0.00 to 100.00%.

Menus for Options 2, 3 and 4 are identical.

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

### Setup: **Partial Stroke**

Item	Value
1 PS Enable	Enabled
2 PS travel (x0.01)%	9000
3 PS Stroke Limit	Open Limit
4 PS Timeout 1 (x0.0001s)	150000
5 PS Timeout 2 (x0.0001s)	150000

Each item can be selected, viewed, and modified where appropriate.

Item 1 'PS Enable' enables the Partial Stroke feature to be enabled and disabled.

Item 2 'PS travel (x0.01)%' enables the position to which the unit will travel on activation of a partial stroke command to be set up. Range is 0-100% in 0.01% steps.

Item 3 'PS Stroke Limit' enables the position of the actuator from which the partial stroke command can be activated to be set up. Either the open or the close limit.

Item 4 and 5 'PS Timeout 1 / 2 (x0.0001s)' enables the timeout for reaching the position (Timeout 1) then returning to the limit (Timeout 2) to be set up.

### Setup: **Auxiliary Mask**

Item	Value
1 Aux 1 Function	Open Command
2 Aux 2 Function	Close Command
3 Aux 3 Function	Digital Input
4 Aux 4 Function	Digital Input
5 Aux 1 I/P Type	NO Contact
6 Aux 2 I/P Type	NO Contact
7 Aux 3 I/P Type	NC Contact
8 Aux 4 I/P Type	NC Contact

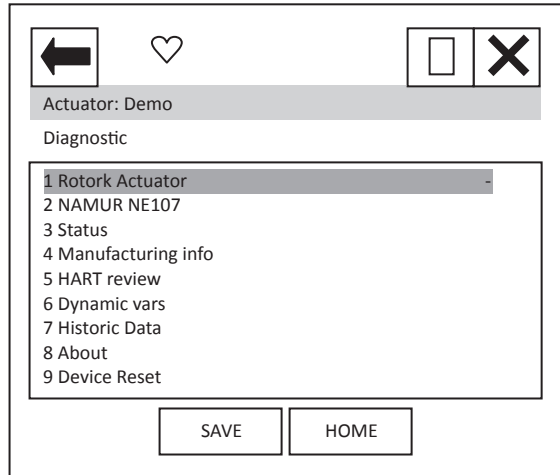
Each item can be selected, viewed, and modified where appropriate.

Items 1 to 4 'Aux 1/2/3/4 Function' enables the function of the Auxiliary inputs to be set up. Either to be a digital input or to be a command.

Items 5 to 8 'Aux 1/2/3/4 I/P Type' enables the contact type of the Auxiliary inputs to be set up. Either NO (Normally Open) or NC (Normally Closed).

### 15.3 Diagnostics

From the top menu, selecting 'Diagnostics' will display the following menu:



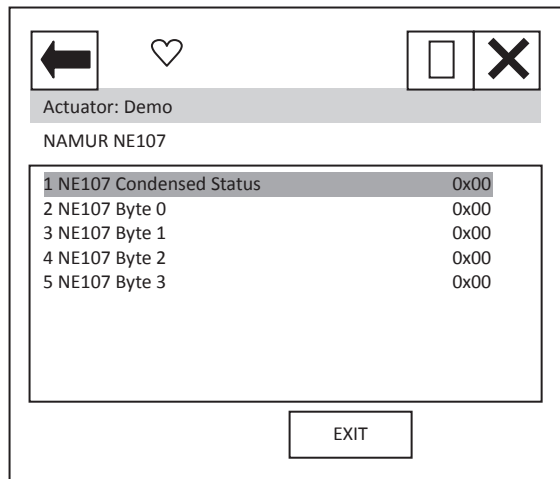
Item 1 indicates the type of actuator. Note, for SI actuators (SI3 and SI4), this will display "Rotork Actuator".

When the items 2 to 8 are selected, new pages are displayed.

For items 4 to 6 and 8 see Section 10.2.

Item 9 'Device reset' will cause a device reset (HART option card only).

Diagnostics: **NAMUR NE107** (Not applicable for SI3 or SI4)

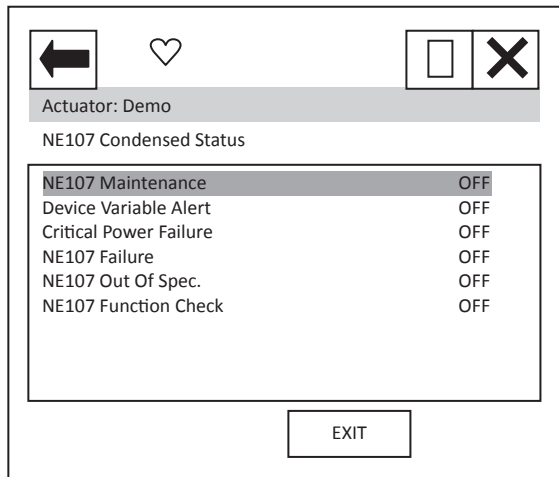


When the items 1 to 4 are selected, new pages are displayed.

Items 2 to 4 select pages which are identical to Status NE107 Alarm Status 0 to 2 – see status section below.

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

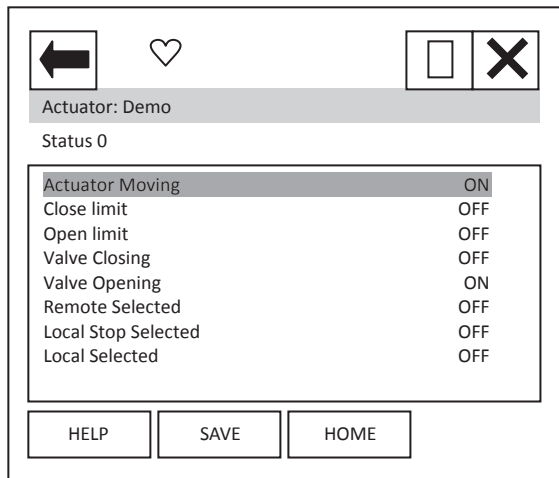
Diagnostic: **NAMUR NE107, NE107 Condensed Status**



These items indicate the status of the alarms bits.

The NE107 bits will be set as 'ON', if one of the alarm bits, that has been associated to the alarm in the NE107 setup section, has activated.

Diagnostic: **Status**



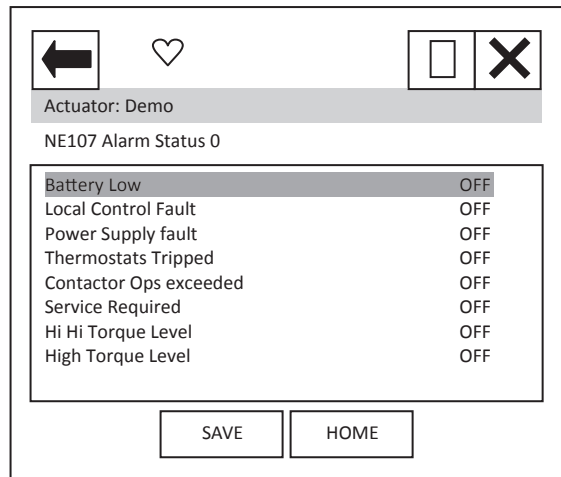
When the items 1 to 5 are selected, new pages are displayed.

The NE107 items show the status of the alarms bits that are associated to the NE107 diagnostics function.

IQ3 Status 0 and 1 are status indication bits.

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Diagnostic: **Status, NE107 Alarm Status 0**



'Battery Low' indicates that the actuator battery used to maintain the display, is either flat or low.

'Local Control Fault' indicates that there is a fault in the actuator's local controls.

'Power Supply Fault' indicates that there is a fault in the actuator's power supply.

'Thermostats Tripped' indicates that the actuator motor thermostat has tripped.

'Contactor Ops exceeded' indicates the limit for contactor operations set has been exceeded.

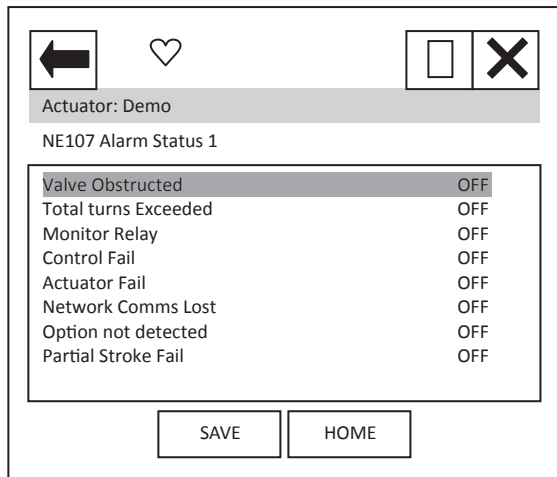
'Service Required' indicates that the time interval set for servicing the actuator has expired.

'Hi Hi Torque Level' and 'High Torque Level' indicates that the levels set for the Hi Hi and High torque levels have been exceeded.



## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Diagnostic: **Status, NE107 Alarm Status 1**



'Valve Obstructed' indicates that the actuator has tripped/stopped on torque due to an obstruction in the valve.

'Total turns Exceeded' indicates that the level set for the total number of turns that the actuator is to do in its life time has been exceeded.

'Monitor Relay' indicates that the actuator monitor relay has tripped – see actuator manual for details.

'Control Fail' and 'Actuator Fail' indicates the actuator has experienced a control or actuator failure.

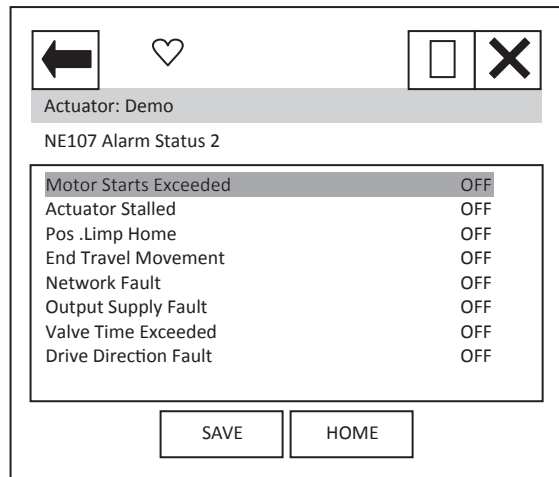
'Network Comms Lost' indicates that the network card is not able to communicate on the network – this is unlikely to be seen.

'Option not detected' indicates a problem with the option card.

'Partial Stroke Fail' indicates a failure in the partial stroke test.

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Diagnostic: **Status, NE107 Alarm Status 2**



'Motor Starts Exceeded' indicates that the limit for the number for motor starts expected in the actuator life has been exceeded.

'Actuator Stalled' indicates that the actuator has stalled.

'Pos .Limp Home' indicates a fault in the absolute encoder, which has caused the 'limp home mode' to be activated.

'End Travel Movement' indicates that there has been excessive travel beyond a limit.

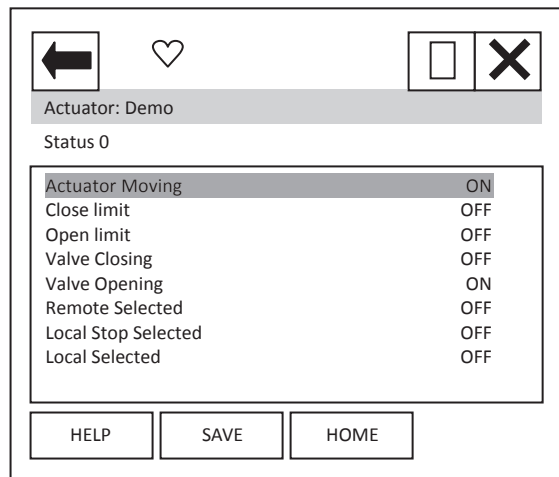
'Network Fault' indicates a fault with the network card.

'Output Supply Fault' indicates a fault with the supply available to the customer.

'Valve Time Exceeded' indicates that the expected travel time of the valve has been exceeded.

'Drive Direction Fault' indicates that the actuator has operated in the incorrect direction.

Diagnostic: **Status, Status0**



'Actuator Moving' indicates that the actuator is currently moving.

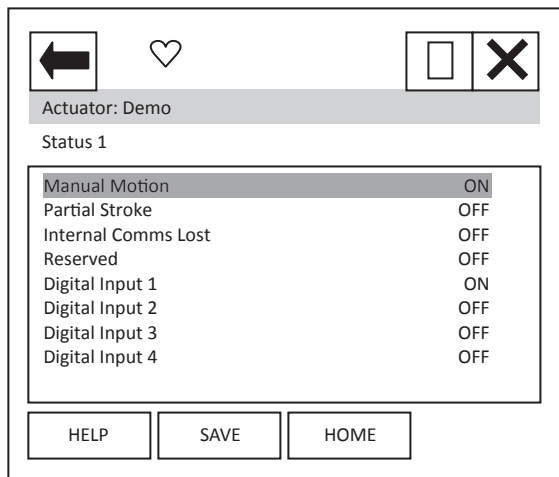
'Close limit' and 'Open limit' indicate if the actuator is at its close or open position limit.

'Valve Closing' and 'Valve Opening' indicates if the actuator is operating the valve in the closing or opening direction.

'Remote Selected', 'Local Stop Selected' and 'Local Selected' indicate the position that the actuator control selection knob is in.

## 15. DD File, Emerson Handheld Tools Screen Shots – SI *continued*

Diagnostic: **Status, Status1**



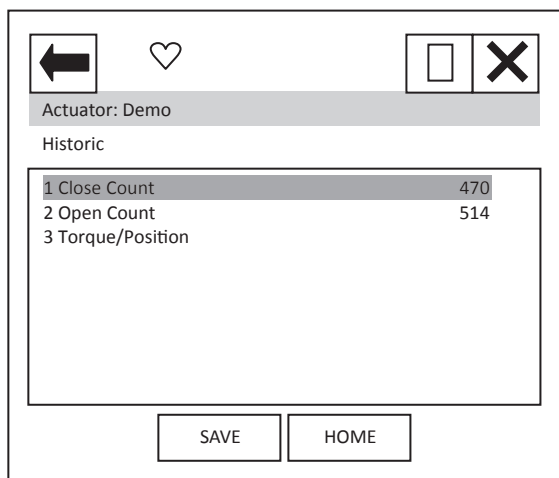
'Manual Motion' indicates that the actuator is currently moving under manual control.

'Partial Stroke' indicate if the actuator is performing a partial stroke test.

'Internal Comms Lost' indicates an internal actuator communication problem.

'Digital Input x' indicates the status of the actuator hardwired digital inputs.

Diagnostic: **Historic Data**



Each item can be selected, viewed.

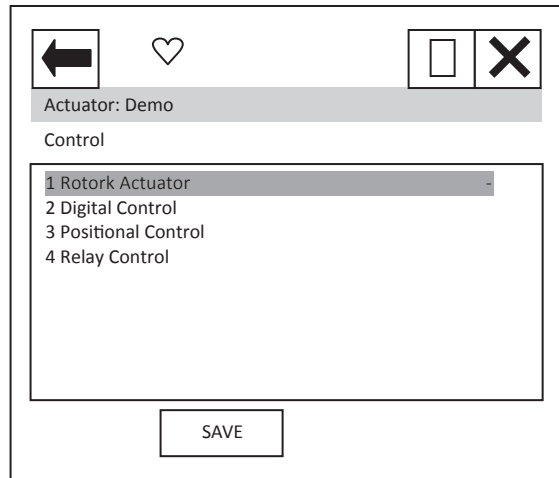
Item 1 'Close Count' shows the number of times the unit has been operated in the close direction.

Item 2 'Open Count' shows the number of times the unit has been operated in the open direction.

Item 3 shows a graph of the torque versus position for the open and close directions.

### 15.4 Control

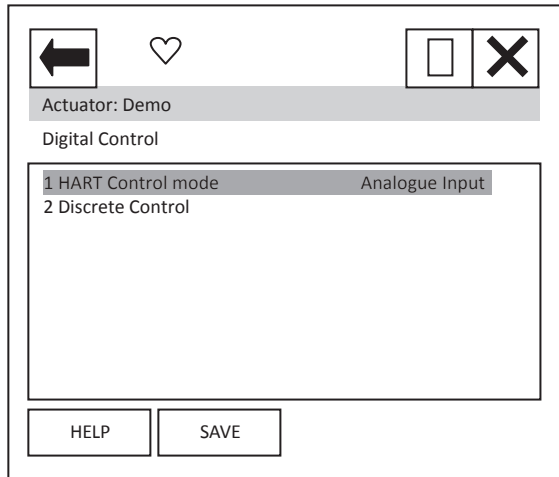
From the top menu, selecting 'Control' will display the following menu:



Item 1 'Rotork Actuator' indicates the type of actuator.

When the items 2 to 4 are selected, new pages are displayed.

Control: **Digital Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' displays the mode that is currently in control. It can either be 'Analogue Input', 'Discrete' or 'Digital position'.

Analogue Input indicates that the unit is being controlled with the 4-20 mA analogue input supply.

Discrete indicates that the discrete mode of control is enabled and the actuator can be controlled using discrete open/close/stop etc. commands.

Digital position indicates that control is via a digital position command and the actuator can be controlled using a digital position command in the range 0.0 to 100.0%.

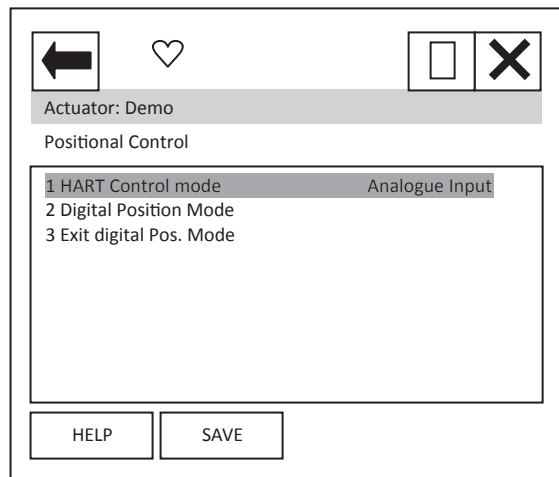
Item 2 selects a new page where the actuator can be operated discretely. Only one command should be selected at one time. The commands available are: Stop, Close, Open, ESD, Partial Stroke Test and Enable Digital Control. Commands will not action unless the 'Enable Digital Control' item is also selected. For example, to operate the actuator in the open direction:

- 1) Select the Discrete Control page.
- 2) Set the Open row item to 'ON' using the touch screen button displayed at the bottom of the screen.
- 3) Set the 'Enable Digital Control' row item to 'ON' using the same button.
- 4) Ensure all other rows are 'OFF'.
- 5) Select the Enter button to return you to the previous screen.
- 6) You will notice a '\*' next to the Discrete Control item – this indicates there is data to send for this feature. Select the 'SEND' button.
- 7) The actuator will operate and you will notice that the HART control mode will change to Discrete.

To operate in the close direction, repeat above instructions ensuring that Open is set to 'OFF' and Close is set to 'ON'.

To exit Discrete control mode, the Enable Digital Control row item must be set to 'OFF', the data entered and sent. NOTE that the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.

Control: **Positional Control**



Each item can be selected, viewed, and modified where appropriate.

Item 1 'HART Control mode' as previous menu item.

Item 2 'Digital Position Mode' Selecting this item will start a method which guides the user to enter the digital positioning mode. The sequence is:

On selection, the display changes to 'Entering Forced Mode' at this point the user can Abort or select OK to enter this mode.

On selection of OK the user is warned that the card will be removed from automatic mode – this means that the analogue Input is no longer in control. Again, the user can choose to Abort or select OK to carry on.

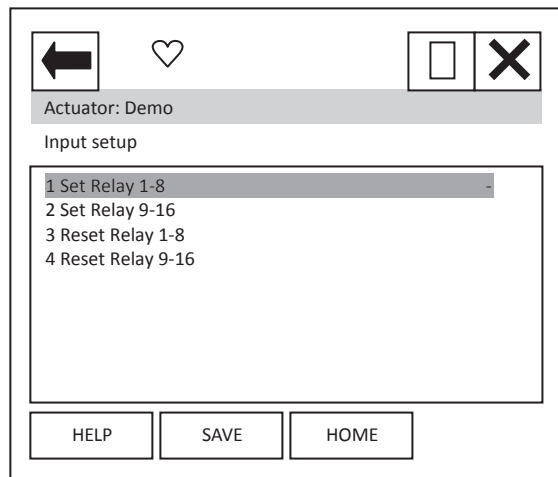
The final page, again has the option to Abort, but selecting OK will enable the user to enter a position value. The Actuator will run to the position selected.

To exit this mode, select Abort at any page.

**NOTE: On Aborting, the HART card will return to Analogue Input mode and the actuator may immediately move if the analogue input signal is different to the position that the actuator is at.**

Item 3 'Exit digital Pos. Mode' may be required to exit the digital positioning mode should the handheld tool be disconnected at any time, resulting in the HART card remaining in the digital positioning mode. Selecting this item will return the unit to Analogue Input mode.

Control: **Relay Control**



Each item can be selected, viewed, and modified where appropriate.

Items 1 to 4 enable the user to operate the 'extra' relays (if fitted) within the actuator. There are 2 sets of items to select for each relay, to activate the relay select the 'Set Relay' item that contains the relay to be set, then change the relays state to 'ON'. To reset the relay the same item will need to be set to 'OFF' and the associated 'Reset Relay' item must be set to 'ON'. To again operate the same relay the 'Reset Relay' item needs to be returned to 'OFF' before selecting 'ON' for the 'Set Relay' item.

**NOTE: The wiring diagram should be checked to confirm which relays are present within the actuator. The SI can have up to 12 relays fitted.**

*Appendix 1 – Capability Checklist*

Manufacturer, model and revision	Rotork Actuator, Rev. 1
Device type	Actuator
HART revision	7.1
Device Description available	Yes
Number and type of sensors	1 (internal ADC)
Number and type of actuators	1
Number and type of host side signals	1: 4 – 20 mA analogue
Number of Device Variables	5
Number of Dynamic Variables	4
Mappable Dynamic Variables?	No
Number of common-practice commands	8
Number of device-specific commands	5
Bits of additional device status	CVA 34, IQ 39, CMA 40
Alternative operating modes?	Yes
Burst mode?	No
Write-protection?	No

*Appendix 2 – Default Configuration*

Parameter	Default value
Lower Range Value	0
Upper Range Value	100
PV Units	%

*Appendix 3 – Device Identification*

<b>Manufacturer Name:</b>	Rotork Process Controls
<b>Manufacture ID Code:</b>	110 (6E Hex)
<b>HART Protocol Revision</b>	7.1
<b>Number of Device Variables</b>	5
<b>Physical Layers Supported</b>	FSK
<b>Physical Device Category</b>	Actuator, DC-isolated Bus Device
<b>Model Name(s):</b>	HART Option Board
<b>Device Type Code:</b>	221 (DD Hex)
<b>Device Revision:</b>	1
<b>Default Address</b>	0



## Appendix

---

### Appendix 4 – General HART Protocol Summary

#### Communication Signals

Traditional analogue 4–20 mA

Digital FSK, based on the Bell 202 telephone communication standard

Logical “0” frequency 2,200 Hz

Logical “1” frequency 1,200 Hz

Bit rate: 1,200 bits per second

#### Data Information

Data update rate:

- Request/response mode—2–3 updates per second

Data byte structure:

- 1 start bit, 8 data bits, 1 odd parity bit, 1 stop bit

Data integrity:

- Two-dimensional error checking (a combination of parity and checksum)
- Status information in every reply message

#### Simple Command Structure

Universal	Common to all devices
Common practice	Optional; used by many devices
Device specific	For unique product features

#### Communication Masters

- Two communication masters

#### Variables

- Up to 256 device variables per device
- IEEE 754 floating point format (32 bits) with engineering units

#### Wiring Topologies

- Point to point—simultaneous analogue and digital
- Point to point—digital only
- Multidrop network—digital only (up to 63 devices)

#### Cable Lengths

- Maximum twisted-pair length—10,000 ft (3,048 m)
- Maximum multiple twisted-pair length—5,000 ft (1,524 m)
- Cable length depends on the characteristics of individual products and cables.





# rotork®



[www.rotork.com](http://www.rotork.com)

A full listing of our worldwide sales and service network is available on our website.

Rotork plc  
Brassmill Lane, Bath, UK  
tel +44 (0)1225 733200  
email [mail@rotork.com](mailto:mail@rotork.com)

PUB092-003-00  
Issue 07/24

As part of a process of on-going product development, Rotork reserves the right to amend and change specifications without prior notice. Published data may be subject to change. For the very latest version release, visit our website at [www.rotork.com](http://www.rotork.com)

The name Rotork is a registered trademark. Rotork recognises all registered trademarks. Published and produced in the UK by Rotork. POLJB0724