SOLUTIONS FOR BUILDING CONTROL

animeo KNX
RS485 Motor Controller WM

Operating Manual

Ref. 1860286

somfy.

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Different types of motors could be used and connected on the animeo KNX RS485 Motor Controller.

Before connecting motor and Motor Controller make sure that the end limits of the motors have been set correctly.

Before starting up it is necessary to follow the safety instructions in this manual. SOMFY cannot be held liable for defects and damages when these have been caused as a result of not following instructions (wrong installation, incorrect service etc.). Establishing, testing and commissioning of the equipment is permitted only by a qualified person (in accordance with VDE 0100). Plug in all connections without voltage. Take precautions against unintentional turning on.

The installation of the Somfy products may occur only at easily accessible places. If maintenance and repair become hindered by accessibility substantially (e.g. stuck or extensively stuck flooring, installation behind lamps or behind façades), any originating supplementary costs therein cannot be charged to the seller.

Subject to technical changes.

The KNX RS485 is a wall-mounted Motor Controller which enables the controlling of up to 18 motors. The motors can be controlled either individually or by groups.
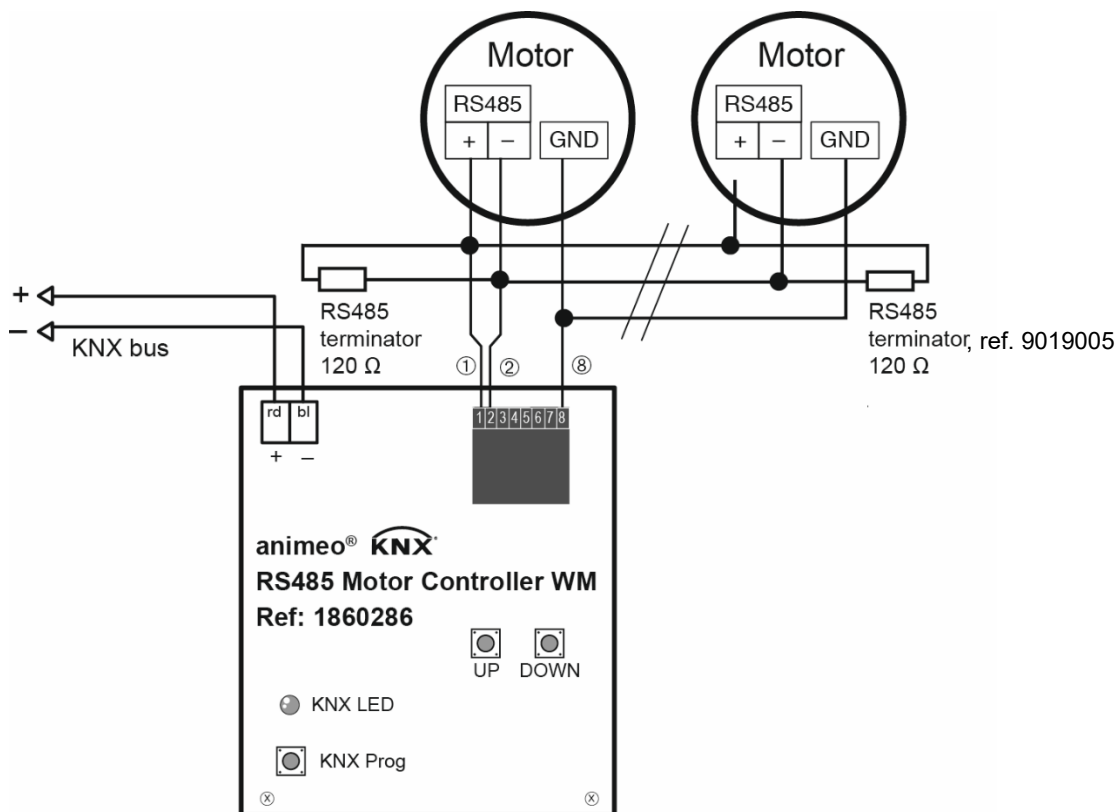
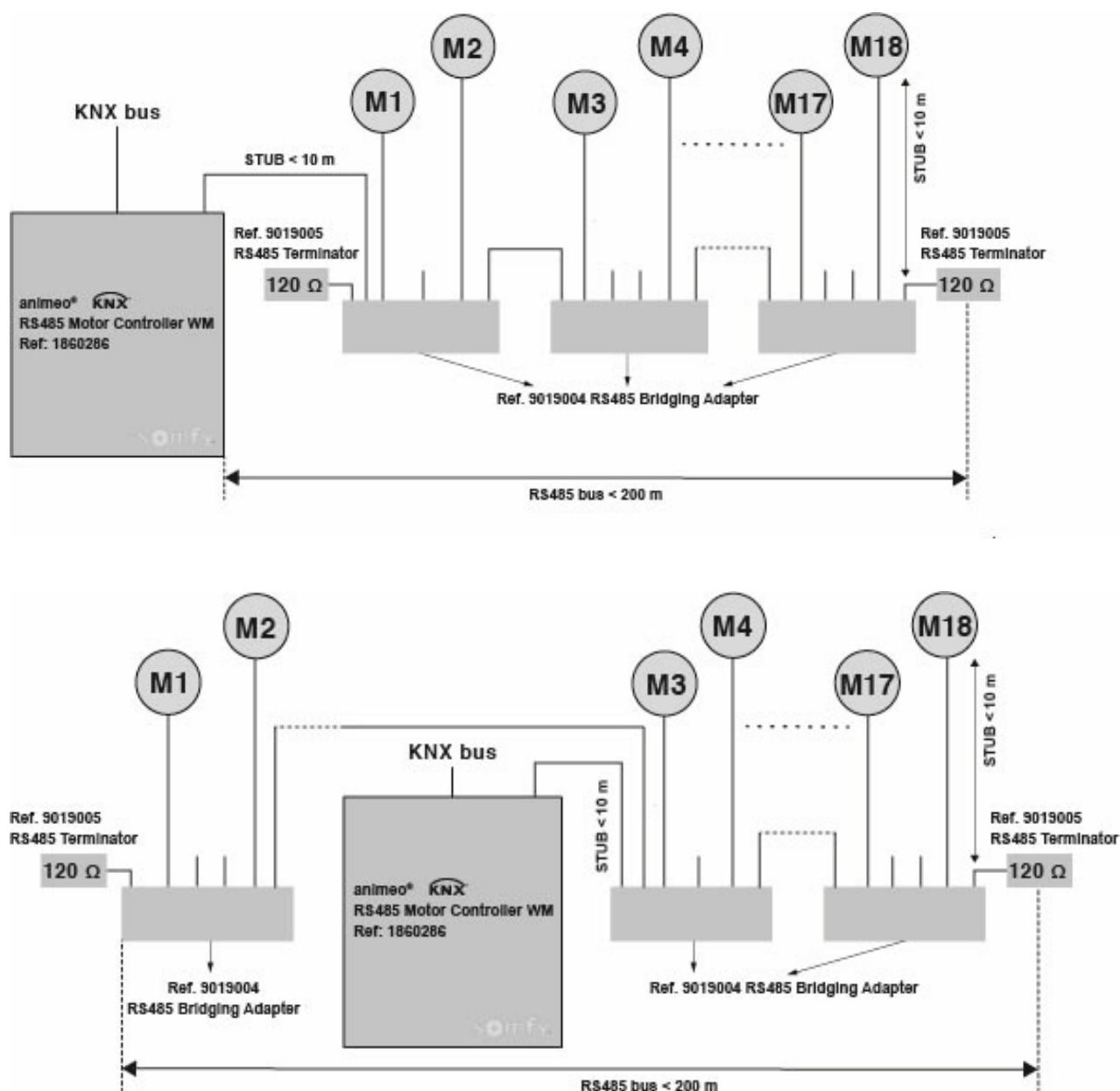RS485 motors can be connected to the RS485 Bridging Adapter, ref. 9019004. Different motor types can be used.

Compatible with any Somfy SDN motors.

1 First operation

1. Blinds must be mounted and the upper and lower end limit **must be** adjusted (s. wiring diagram). The settings of the motor limits can be done via the use of the SDN configuration software.

2. Link all motors via the RS485 bus and connect them to the Motor Controller.

3. Turn on power supply of the motors.

4. Connect power supply to the Motor Controllers (KNX bus).

5. After a waiting time of ca. 30 seconds all motors can be operated by means of the push buttons on the Motor Controller.

6. Check end limits and running direction. Can be adjusted later via ETS, if necessary.

7. Create ETS project and download it.

8. After a waiting time of approx. 1 minute after downloading the Motor Controller is ready for operation.

2 Wiring diagram

Connection to		Cable	Twisted pair	Max. length
RS485 bus	Modular Jack 8P4C (RJ45)	Min.: 4 x 2 x 0.5 mm/24 AWG	Required twisted pair shielded, impedance 100 Ω (-10 Ω/+30 Ω), recommended CAT5-FTP, following Somfy RS485 guidelines (see "SDN Bus wiring guide" in Somfy Digital Network (RS485) section at www.somfy.com/pro-jects/downloads)	200 m
KNX Bus		2 x 0.8 mm/20 AWG	Required, following KNX topology guidelines	–

3 Communication objects

3.1 Object overview

A maximum of 450 communication objects are available, which however cannot be used at one time.
Maximum 480 group addresses can be linked.

3.1.1 List of Objects

No.	Object name	Model	DPT_ID	Description
1	**Motor 1 Position Request**	1 Bit	1.017	If a telegram with the value "1" or "0" is received on this communication object, the current status position is sent on the bus (object 2).
2	Motor 1 Feedback Position	1 Byte	5.001	On this communication object the current position (UP/DOWN direction) of the blind is sent to the bus based on the programmed running time. The type of feedback (on demand, status change, cyclic) is defined in the ETS parameters. With 18 motors connected, the feedback can take up to 5 seconds "0" = UP / "100" = DOWN
3	Motor 1 Feedback Slat	1 Byte	5.001	On this communication object the current angle (closed/turned slats direction) of the blind is sent to the bus based on the programmed tilting time. The type of feed-back (on demand, status change, cyclic) is defined in the ETS parameters. With 18 motors connected, the feedback can take up to 5 seconds "100" = slats max. closed / "0" = slats max. turned (standard) or "0" = slats max. closed / "100" = slats max. turned
4	Motor 1 Feedback Upper End	1 Bit	1.001	Over this communication object a telegram with the value "1" is sent if the upper end position is reached. When leaving the upper end position of the blind a telegram with the value "0" is sent. The upper and the lower end position result from the parameterized running times.
5	Motor 1 Feedback Lower End	1 Bit	1.001	Over this communication object a telegram with the value "1" is sent after the lower end position is reached. When leaving the lower end position of the blind a telegram with the value "0" is sent. The upper and the lower end position result from the parameterized running times.
6	Motor 1 Error Feedback	1 Bit	1.001	Over this communication object a telegram is sent if a motor error occurs. An error is when a move command was sent to the motor, but the motor does not move. The sent value of this communication object depends on what has been selected in the

No.	Object name	Model	DPT_ID	Description
				ETS parameters. • 1/0 (1 = error, 0 = no error) or • 0/1 (0 = error, 1 = no error)
7	Motor 1 Identification	4 Bytes	12.*	Write: 0 → Motor is winking 1-255 → Move to position Read: Read out the corresponding ID of the RS485 motor which is stored in the Motor Controller memory (see chapter 4.1.2 -2. Motor ID).
8	Motor 1 Cycles	4 Bytes	12.001	Read out the number of movement cycles of the motor.
9	Motor 1 Feedback Security	1 Bit	1.001	The object is "1" = "ON" when the last motor action was caused by a security order. It is sent to the bus when the value is changed.
10	Motor 1 Feedback Automatic	1 Bit	1.001	The object is "1" = "ON" when the last motor action was caused by an automatic order. It is sent to the bus when the value is changed.
11	Motor 1 Feedback Manual	1 Bit	1.001	The object is "1" = "ON" when the last motor action was caused by a manual order. It is sent to the bus when the value is changed.
12	**Motor 2 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
13	Motor 2 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
14	Motor 2 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
15	Motor 2 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
16	Motor 2 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
17	Motor 2 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
18	Motor 2 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
19	Motor 2 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
20	Motor 2 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
21	Motor 2 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
22	Motor 2 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
23	**Motor 3 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
24	Motor 3 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
25	Motor 3 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
26	Motor 3 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
27	Motor 3 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
28	Motor 3 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
29	Motor 3 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
30	Motor 3 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
31	Motor 3 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
32	Motor 3 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1

No.	Object name	Model	DPT_ID	Description
33	Motor 3 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
34	**Motor 4 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
35	Motor 4 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
36	Motor 4 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
37	Motor 4 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
38	Motor 4 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
39	Motor 4 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
40	Motor 4 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
41	Motor 4 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
42	Motor 4 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
43	Motor 4 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
44	Motor 4 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
45	**Motor 5 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
46	Motor 5 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
47	Motor 5 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
48	Motor 5 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
49	Motor 5 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
50	Motor 5 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
51	Motor 5 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
52	Motor 5 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
53	Motor 5 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
54	Motor 5 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
55	Motor 5 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
56	**Motor 6 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
57	Motor 6 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
58	Motor 6 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
59	Motor 6 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
60	Motor 6 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
61	Motor 6 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
62	Motor 6 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
63	Motor 6 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
64	Motor 6 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
65	Motor 6 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
66	Motor 6 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
67	**Motor 7 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
68	Motor 7 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
69	Motor 7 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1

No.	Object name	Model	DPT_ID	Description
70	Motor 7 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
71	Motor 7 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
72	Motor 7 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
73	Motor 7 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
74	Motor 7 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
75	Motor 7 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
76	Motor 7 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
77	Motor 7 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
78	**Motor 8 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
79	Motor 8 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
80	Motor 8 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
81	Motor 8 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
82	Motor 8 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
83	Motor 8 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
84	Motor 8 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
85	Motor 8 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
86	Motor 8 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
87	Motor 8 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
88	Motor 8 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
89	**Motor 9 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
90	Motor 9 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
91	Motor 9 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
92	Motor 9 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
93	Motor 9 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
94	Motor 9 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
95	Motor 9 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
96	Motor 9 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
97	Motor 9 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
98	Motor 9 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
99	Motor 9 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
100	**Motor 10 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
101	Motor 10 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
102	Motor 10 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
103	Motor 10 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
104	Motor 10 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
105	Motor 10 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
106	Motor 10 Identification	4 Bytes	12.*	See object description no. 7 for motor 1

No.	Object name	Model	DPT_ID	Description
107	Motor 10 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
108	Motor 10 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
109	Motor 10 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
110	Motor 10 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
111	**Motor 11 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
112	Motor 11 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
113	Motor 11 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
114	Motor 11 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
115	Motor 11 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
116	Motor 11 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
117	Motor 11 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
118	Motor 11 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
119	Motor 11 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
120	Motor 11 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
121	Motor 11 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
122	**Motor 12 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
123	Motor 12 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
124	Motor 12 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
125	Motor 12 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
126	Motor 12 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
127	Motor 12 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
128	Motor 12 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
129	Motor 12 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
130	Motor 12 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
131	Motor 12 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
132	Motor 12 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
133	**Motor 13 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
134	Motor 13 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
135	Motor 13 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
136	Motor 13 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
137	Motor 13 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
138	Motor 13 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
139	Motor 13 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
140	Motor 13 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
141	Motor 13 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
142	Motor 13 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
143	Motor 13 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1

No.	Object name	Model	DPT_ID	Description
144	**Motor 14 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
145	Motor 14 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
146	Motor 14 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
147	Motor 14 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
148	Motor 14 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
149	Motor 14 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
150	Motor 14 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
151	Motor 14 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
152	Motor 14 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
153	Motor 14 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
154	Motor 14 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
155	**Motor 15 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
156	Motor 15 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
157	Motor 15 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
158	Motor 15 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
159	Motor 15 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
160	Motor 15 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
161	Motor 15 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
162	Motor 15 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
163	Motor 15 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
164	Motor 15 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
165	Motor 15 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
166	**Motor 16 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
167	Motor 16 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
168	Motor 16 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
169	Motor 16 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
170	Motor 16 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
171	Motor 16 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
172	Motor 16 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
173	Motor 16 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
174	Motor 16 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
175	Motor 16 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
176	Motor 16 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
177	**Motor 17 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
178	Motor 17 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
179	Motor 17 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
180	Motor 17 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1

No.	Object name	Model	DPT_ID	Description
181	Motor 17 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
182	Motor 17 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
183	Motor 17 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
184	Motor 17 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
185	Motor 17 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
186	Motor 17 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
187	Motor 17 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
188	**Motor 18 Position Request**	1 Bit	1.017	See object description no. 1 for motor 1
189	Motor 18 Feedback Position	1 Byte	5.001	See object description no. 2 for motor 1
190	Motor 18 Feedback Slat	1 Byte	5.001	See object description no. 3 for motor 1
191	Motor 18 Feedback Upper End	1 Bit	1.001	See object description no. 4 for motor 1
192	Motor 18 Feedback Lower End	1 Bit	1.001	See object description no. 5 for motor 1
193	Motor 18 Error Feedback	1 Bit	1.001	See object description no. 6 for motor 1
194	Motor 18 Identification	4 Bytes	12.*	See object description no. 7 for motor 1
195	Motor 18 Cycles	4 Bytes	12.001	See object description no. 8 for motor 1
196	Motor 18 Feedback Security	1 Bit	1.001	See object description no. 9 for motor 1
197	Motor 18 Feedback Automatic	1 Bit	1.001	See object description no. 10 for motor 1
198	Motor 18 Feedback Manual	1 Bit	1.001	See object description no. 11 for motor 1
199	**Command Group 1 Up/Down**	1 Bit	1.008	If a telegram with the value "0" is received on this communication object, the appropriate blind goes up. If a telegram with the value "1" is received, the appropriate blind goes down.
200	Command Group 1 Dedicated Stop	1 Bit	1.017	With vertical awnings, roller shutters, awnings and windows: When the end product is moving, the move is stopped with the receiving of a telegram on this communication object, no matter whether "0" or "1" is received. If this end product is not moving and a telegram is received on this communication object, no operation is carried out.
	Command Group 1 Step/Stop	1 Bit	1.017	With Venetian blinds: If the Venetian blind is moving, the move is stopped with the receiving of a telegram on one of these communication objects, no matter whether "0" or "1" is received. If the Venetian blind is stationary, a turn is carried out. In addition, the slats turn CLOSED with the receiving of a telegram with the value "1" and UP with the receiving of a telegram with the value "0". The duration of the turning step is defined in the parameter settings.
201	Command Group 1 Position manual	1 Byte	5.001	If this communication object receives a telegram, the appropriate blind will go into the position which is defined by the received value.

No.	Object name	Model	DPT_ID	Description
				"0" = UP "100" = DOWN
202	Command Group 1 Slat manual	1 Byte	5.001	If this communication object receives a telegram, the appropriate blind will go into the angle which is defined by the received value. "100" = slats max. closed / "0" = slats max. turned (standard) or "0" = slats max. closed / "100" = slats max. turned
203	Command Group 1 Position automatic	1 Byte	5.001	If this communication object receives a telegram, the appropriate blind will go into the position which is defined by the received value. "0" = UP "100" = DOWN
204	Command Group 1 Slat automatic	1 Byte	5.001	If this communication object receives a telegram, the appropriate blind will go into the angle which is defined by the received value. "100" = slats max. closed / "0" = slats max. turned (standard) or "0" = slats max. closed / "100" = slats max. turned
205	Command Group 1 Move to IP1	1 Bit	1.008	If a telegram with the value "1" is received on this communication object, the blind goes to the intermediate position 1 which was configured by local switch or parameterized in the ETS parameters. The last position which has been configured is active. Receiving a telegram with the value "0" on this communication object the appropriate blind goes to the upper end position.
206	Command Group 1 Move to IP2	1 Bit	1.008	If a telegram with the value "1" is received on one of these communication objects, the corresponding blind moves to the intermediate position 2 parameterized in the ETS parameters. Receiving a telegram with the value "0" on one of these communication objects, the corresponding blind moves to the upper end position.
207	Command Group 1 Security low prio	1 Bit	1.001	If a telegram with the value "1" is received on this communication object, the blind goes to the position which was parameterized in the ETS parameters. When the communication object receives a telegram with value "0" no action will be executed. Only with the selection "Restore previous position after security (Yes)" in the ETS parameters this action will be executed on the blind. If this communication object is active through a telegram with the value "1" and if then on the communication object 154 (security position, high priority) a telegram with value "1" is received, the blind will move to the position configured in the ETS parameters (security position, high priority).

No.	Object name	Model	DPT_ID	Description
208	Command Group 1 Security high prio	1 Bit	1.001	If a telegram with the value "1" is received on this communication object, the blind goes to the position which was parameterized in the ETS parameters. When the communication object receives a telegram with value "0" no action will be executed. Only with the selection " Restore previous position after security (Yes)" in the ETS parameters this will be executed in the blind. If the object 153 for security position, low priority is active ("1"), the blinds will go to the parameterized position for the low priority.
209	Command Group 1 Block functions	1 Bit	1.001	If a telegram with the value "1" is received on this communication object, the function which is selected in ETS parameters will be blocked for the blind. If a telegram with the value "0" is received on this communication object, the function for the blind will be enabled again.
210	Command Group 1 Prio automatic/manual	1 Bit	1.001	Over this communication object priority between automatic function and manual function can be switched. If a telegram with the value "1" is received on this communication object priority automatic function is active for the blind. If a telegram with the value "0" is received on this communication object priority manual functions are active for the blind.
211	Command Group 1 Reset priority	1 Bit	1.017	If a telegram with the value "1" or "0" is received on this communication object, the appropriate priority for the blind is reset. Priority automatic function or priority manual function is then again actively switched. The active priority depends on which communication object is active and/or which priority has been selected in the ETS parameters.
212	Command Group 1 Automatic commands	1 Bit	1.003	With this communication object automatic commands/functions can be controlled. It is only available if "Automatic command by object" inside the parameter "Automatic/ Manual functions" is selected. Automatic command will be enabled by default. By disabling the object, all automatic commands are blocked but recorded. By enabling the object again, the last automatic order will be executed, and all automatic commands are enabled.
213	**Command Group 2 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
214	Command Group 2 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command group 1
	Command Group 2 Step/Stop	1 Bit	1.017	
215	Command Group 2 Position manual	1 Byte	5.001	See object description no. 201 for command group 1

No.	Object name	Model	DPT_ID	Description
216	Command Group 2 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
217	Command Group 2 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
218	Command Group 2 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
219	Command Group 2 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
220	Command Group 2 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
221	Command Group 2 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
222	Command Group 2 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
223	Command Group 2 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
224	Command Group 2 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
225	Command Group 2 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
226	Command Group 2 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
227	**Command Group 3 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
228	Command Group 3 Dedicated Stop Command Group 3 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
229	Command Group 3 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
230	Command Group 3 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
231	Command Group 3 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
232	Command Group 3 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
233	Command Group 3 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
234	Command Group 3 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
235	Command Group 3 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
236	Command Group 3 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
237	Command Group 3 Block functions	1 Bit	1.001	See object description no. 209 for command group 1

No.	Object name	Model	DPT_ID	Description
238	Command Group 3 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
239	Command Group 3 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
240	Command Group 3 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
241	**Command Group 4 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
242	Command Group 4 Dedicated Stop Command Group 4 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
243	Command Group 4 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
244	Command Group 4 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
245	Command Group 4 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
246	Command Group 4 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
247	Command Group 4 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
248	Command Group 4 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
249	Command Group 4 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
250	Command Group 4 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
251	Command Group 4 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
252	Command Group 4 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
253	Command Group 4 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
254	Command Group 4 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
255	**Command Group 5 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
256	Command Group 5 Dedicated Stop Command Group 5 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
257	Command Group 5 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
258	Command Group 5 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1

No.	Object name	Model	DPT_ID	Description
259	Command Group 5 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
260	Command Group 5 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
261	Command Group 5 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
262	Command Group 5 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
263	Command Group 5 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
264	Command Group 5 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
265	Command Group 5 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
266	Command Group 5 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
267	Command Group 5 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
268	Command Group 5 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
269	**Command Group 6 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
270	Command Group 6 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command group 1
	Command Group 6 Step/Stop	1 Bit	1.017	
271	Command Group 6 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
272	Command Group 6 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
273	Command Group 6 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
274	Command Group 6 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
275	Command Group 6 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
276	Command Group 6 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
277	Command Group 6 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
278	Command Group 6 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
279	Command Group 6 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
280	Command Group 6 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1

No.	Object name	Model	DPT_ID	Description
281	Command Group 6 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
282	Command Group 6 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
283	**Command Group 7 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
284	Command Group 7 Dedicated Stop Command Group 7 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
285	Command Group 7 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
286	Command Group 7 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
287	Command Group 7 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
288	Command Group 7 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
289	Command Group 7 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
290	Command Group 7 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
291	Command Group 7 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
292	Command Group 7 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
293	Command Group 7 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
294	Command Group 7 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
295	Command Group 7 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
296	Command Group 7 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
297	**Command Group 8 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
298	Command Group 8 Dedicated Stop Command Group 8 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
299	Command Group 8 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
300	Command Group 8 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
301	Command Group 8 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1

No.	Object name	Model	DPT_ID	Description
302	Command Group 8 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
303	Command Group 8 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
304	Command Group 8 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
305	Command Group 8 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
306	Command Group 8 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
307	Command Group 8 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
308	Command Group 8 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
309	Command Group 8 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
310	Command Group 8 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
311	**Command Group 9 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
312	Command Group 9 Dedicated Stop Command Group 9 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
313	Command Group 9 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
314	Command Group 9 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
315	Command Group 9 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
316	Command Group 9 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
317	Command Group 9 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
318	Command Group 9 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
319	Command Group 9 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
320	Command Group 9 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
321	Command Group 9 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
322	Command Group 9 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
323	Command Group 9 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1

No.	Object name	Model	DPT_ID	Description
324	Command Group 9 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
325	**Command Group 10 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
326	Command Group 10 Dedicated Stop Command Group 10 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
327	Command Group 10 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
328	Command Group 10 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
329	Command Group 10 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
330	Command Group 10 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
331	Command Group 10 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
332	Command Group 10 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
333	Command Group 10 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
334	Command Group 10 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
335	Command Group 10 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
336	Command Group 10 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
337	Command Group 10 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
338	Command Group 10 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
339	**Command Group 11 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
340	Command Group 11 Dedicated Stop Command Group 11 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
341	Command Group 11 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
342	Command Group 11 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
343	Command Group 11 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
344	Command Group 11 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1

No.	Object name	Model	DPT_ID	Description
345	Command Group 11 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
346	Command Group 11 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
347	Command Group 11 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
348	Command Group 11 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
349	Command Group 11 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
350	Command Group 11 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
351	Command Group 11 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
352	Command Group 11 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
353	**Command Group 12 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
354	Command Group 12 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command group 1
	Command Group 12 Step/Stop	1 Bit	1.017	
355	Command Group 12 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
356	Command Group 12 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
357	Command Group 12 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
358	Command Group 12 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
359	Command Group 12 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
360	Command Group 12 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
361	Command Group 12 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
362	Command Group 12 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
363	Command Group 12 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
364	Command Group 12 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
365	Command Group 12 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
366	Command Group 12 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1

No.	Object name	Model	DPT_ID	Description
367	**Command Group 13 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
368	Command Group 13 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command group 1
	Command Group 13 Step/Stop	1 Bit	1.017	
369	Command Group 13 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
370	Command Group 13 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
371	Command Group 13 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
372	Command Group 13 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
373	Command Group 13 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
374	Command Group 13 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
375	Command Group 13 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
376	Command Group 13 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
377	Command Group 13 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
378	Command Group 13 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
379	Command Group 13 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
380	Command Group 13 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
381	**Command Group 14 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
382	Command Group 14 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command group 1
	Command Group 14 Step/Stop	1 Bit	1.017	
383	Command Group 14 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
384	Command Group 14 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
385	Command Group 14 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
386	Command Group 14 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
387	Command Group 14 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
388	Command Group 14 Move to IP2	1 Bit	1.008	See object description no. 206 for command

No.	Object name	Model	DPT_ID	Description
				group 1
389	Command Group 14 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
390	Command Group 14 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
391	Command Group 14 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
392	Command Group 14 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
393	Command Group 14 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
394	Command Group 14 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
395	**Command Group 15 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
396	Command Group 15 Dedicated Stop Command Group 15 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
397	Command Group 15 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
398	Command Group 15 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
399	Command Group 15 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
400	Command Group 15 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
401	Command Group 15 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
402	Command Group 15 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
403	Command Group 15 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
404	Command Group 15 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
405	Command Group 15 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
406	Command Group 15 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
407	Command Group 15 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
408	Command Group 15 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
409	**Command Group 16 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
410	Command Group 16 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command

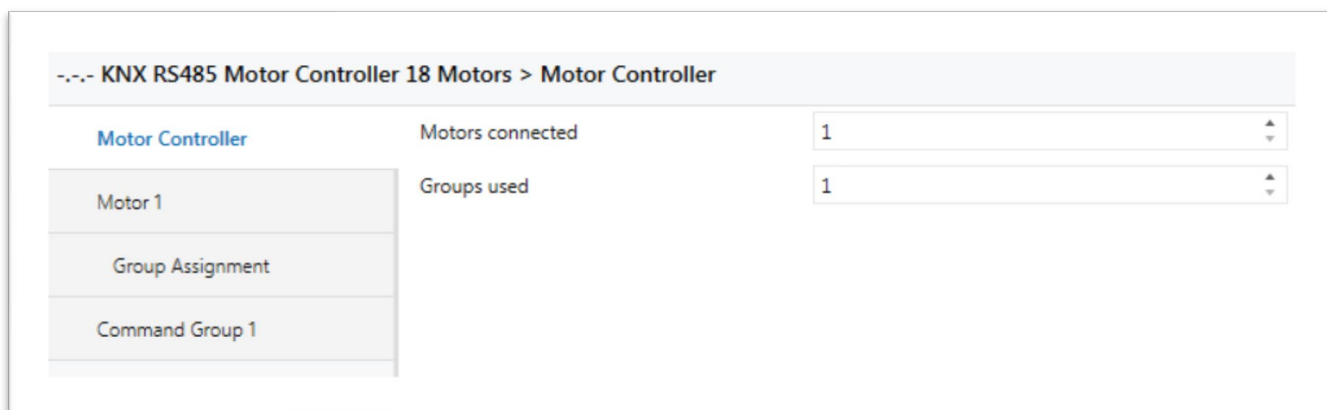| No.	Object name	Model	DPT_ID	Description
				group 1
	Command Group 16 Step/Stop	1 Bit	1.017	
411	Command Group 16 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
412	Command Group 16 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
413	Command Group 16 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
414	Command Group 16 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
415	Command Group 16 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
416	Command Group 16 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
417	Command Group 16 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
418	Command Group 16 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
419	Command Group 16 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
420	Command Group 16 Prio automatic/manual	1 Bit	1.001	See object description no. 210 for command group 1
421	Command Group 16 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
422	Command Group 15 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
423	**Command Group 17 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
424	Command Group 17 Dedicated Stop	1 Bit	1.017	See object description no. 200 for command group 1
	Command Group 17 Step/Stop	1 Bit	1.017	
425	Command Group 17 Position manual	1 Byte	5.001	See object description no. 201 for command group 1
426	Command Group 17 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
427	Command Group 17 Position automatic	1 Byte	5.001	See object description no. 203 for command group 1
428	Command Group 17 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
429	Command Group 17 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
430	Command Group 17 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
431	Command Group 17 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1

No.	Object name	Model	DPT_ID	Description
432	Command Group 17 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
433	Command Group 17 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
434	Command Group 17 Prio auto-matic/manual	1 Bit	1.001	See object description no. 210 for command group 1
435	Command Group 17 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
436	Command Group 17 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1
437	**Command Group 18 Up/Down**	1 Bit	1.008	See object description no. 199 for command group 1
438	Command Group 18 Dedicated Stop Command Group 18 Step/Stop	1 Bit 1 Bit	1.017 1.017	See object description no. 200 for command group 1
439	Command Group 18 Position man-ual	1 Byte	5.001	See object description no. 201 for command group 1
440	Command Group 18 Slat manual	1 Byte	5.001	See object description no. 202 for command group 1
441	Command Group 18 Position auto-matic	1 Byte	5.001	See object description no. 203 for command group 1
442	Command Group 18 Slat automatic	1 Byte	5.001	See object description no. 204 for command group 1
443	Command Group 18 Move to IP1	1 Bit	1.008	See object description no. 205 for command group 1
444	Command Group 18 Move to IP2	1 Bit	1.008	See object description no. 206 for command group 1
445	Command Group 18 Security low prio	1 Bit	1.001	See object description no. 207 for command group 1
446	Command Group 18 Security high prio	1 Bit	1.001	See object description no. 208 for command group 1
447	Command Group 18 Block functions	1 Bit	1.001	See object description no. 209 for command group 1
448	Command Group 18 Prio auto-matic/manual	1 Bit	1.001	See object description no. 210 for command group 1
449	Command Group 18 Reset priority	1 Bit	1.017	See object description no. 211 for command group 1
450	Command Group 18 Automatic commands	1 Bit	1.003	See object description no. 212 for command group 1

4 Parameter

The options to be selected of the single parameters are described in each case. The default settings are printed in italic. In the following illustrations of the different parameter cards the maximum number of parameter is shown. Besides this and depending on the parameter settings, objects which are not required are faded out.

4.1   Motor Controller settings

4.1.1   Menu index card "Motor Controller"

With this menu index card it can be stated how many motors are connected on the Motor Controller and how many command groups shall be used for the connected motors.
The number of connected motors in ETS must correspond to the number of connected motors on the Motor Controller.

1.   Motors connected

Options: • *1*
                • 1 – 18

2.   Groups used

Options: • *1*
                • 1 – 18

4.1.2 Menu index card "Motor 1"

The settings for the motors are exemplarily described on "Motor 1". Depending on the number of motors se-
lected in the menu "Motor Controller", the settings have to be done for all further motors (motor 1….18).

```
-.-.- KNX RS485 Motor Controller V2 > Motor 1

  Motor Controller          Descriptive text for motor application/     Text
                            location

    Motor 1                 Motor ID                                    Auto

      Group Assignment         -> a value between 000000 and FFFFFF stores or changes the Motor ID

    Command Group 1            -> FFFFFF deletes the stored Motor ID and initiates a discovery

                               -> other entries let the Motor ID untouched

                            Application with tilting function      ◉ No   ○ Yes

                            Adjust actual end limit                   No                        ▼

                            Direction of rotation                     As it is                 ▼

                            Intermediate Position 1 (IP 1)            0                      ⬍ %

                            Intermediate Position 2 (IP 2)            0                      ⬍ %

                               IP1 and IP2 disabled! To enable enter values > 0

                            Error feedback logic                   ◉ Error (1), Ok (0)   ○ Error (0), Ok (1)

                            Feedback upper/lower end limit         ◉ No   ○ Yes

                            Position feedback mode                    None                     ▼
```

1.   Description for motor application/location

The name of the blind location can be entered here, e.g. window number.

2.   Motor ID

The motor ID can be entered or deleted here. With "Auto" one of the found motor IDs is used.
If "FFFFFF" is entered, the parameter must be reset to "Auto" so that the motor ID is not deleted again after
the next download.

In order to be able to communicate with individual motors via the SDN bus, it is necessary to address them
by means of their ID, e.g. motor wink.

The motor address is stored in the Motor Controller and is linked to the associated KNX objects. If a stored
motor is no longer physically connected/available, the address must be replaced. The "Motor-Identification"
objects are used to read and display exactly this stored address. If this address does not belong to any of the
physically connected motors, no motor will react.

3.   Application with tilting function

If the end product is Venetian blinds, the "Yes" parameter must be set here. "No" applies to all other types of
blinds.

4.   Adjust actual end limit

Options: • *No*
                • Upwards
                • Downwards

This parameter is to shift the taught-in end limit of the motor in the upper or lower direction. With the parameter "Upwards" or "Downwards" further menu parameters open.

⚠ Before starting to download the set ETS parameter into the KNX RS485 Motor Controller, the blind has to be in the end limit position which needs to be changed/modified.

⚠ **This parameter should be used only for little adjustments of the limits and never to set completely the motor limits. Motor limits have to be set with the use of the "SDN configuration software or with the RS485 Setting Tool.**

- **No**

The end limit will not be adjusted.

- **Upwards**

The end limit will be adjusted into the up direction by the set value as soon as the application is downloaded via the ETS software.

Adjust actual end limit	Upwards ▼
Shift end limit by	10 ⏶⏷ pulses

Set back to 'No' after first Download to avoid unwanted adjustments !

⚠ If "Adjust actual end limit" is set, you have to set the parameter back to "No" to avoid changing the end limits again!

- **Downwards**

The end limit will be adjusted into the down direction by the set value as soon as the application is downloaded via the ETS software.

Adjust actual end limit	Downwards ▼
Shift end limit by	10 ⏶⏷ pulses

Set back to 'No' after first Download to avoid unwanted adjustments !

⚠ If "Adjust actual end limit" is set, you have to set the parameter back to "No" to avoid changing the end limits again!

4.1 Shift end limit by

Options: 10 – 50 pulses

The end limits of the motors are readjusted by 10 – 50 increments upwards and downwards.

⚠️ Different revolutions are possible to adjust the actual end limits of the 3 motor types:

Sonesse50 RS485 or LT50 RS485 ≈ 130 pulses
Sonesse30 RS485   ≈ 320 pulses
Sonesse50 Ultra DC RS485   ≈ 1680 pulses

End limits can be shifted between 10 and 50 pulses over ETS. If the targeted end limit is still not reached, the parameter has to be downloaded once again into the Motor Controller.

5.   Direction of rotation

Options: • Standard
                    • Inverted
                    • *As it is*

Should the roller shutter not move into the desired direction, e.g. downwards after an UP command, you can change the movement direction by adjusting "inverted".

- **Standard**

This will set the motor running direction. So, if an UP command is sent, the motor will move with an anti-clockwise rotation.
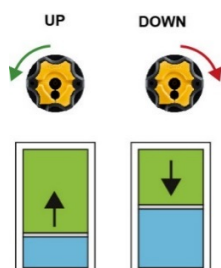
- **Inverted**

This will set the motor running direction. So, if an UP command is sent, the motor will move with a clockwise rotation.
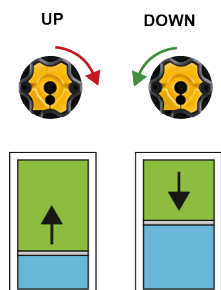
- **As it is**

No change of the motor running direction.

6.   Intermediate Position 1 (IP1) and 2 (IP2)

Options: • *0*
                • 1 – 99 %

With these parameters the intermediate positions 1 and 2 are defined. The set value in % refers to the pa-
rameterized running time of the blind. To disable IP1 and IP2 the value 0 has to be entered.
See table in chapter 4.2.2 "Automatic/Manual Function".

7.   Error feedback logic

Options: • *Error (1), Ok (0)*
                • Error (0), Ok (1)

With this parameter the indication can be defined if an error occurs on the motor:

   1/0   a telegram with the value "1" is sent if a motor error occurs (e.g. if the motor is blocked)
   0/1   a telegram with the value "0" is sent if a motor error occurs

8.   Feedback upper/lower end limit

To select if the position feedback of the upper/lower end limit is active over object 4 and 5.

Options: • *No*
                • Yes

9.   Feedback Position mode

Options: • *None*
                • On demand
                • On status change
                • Cyclic

• **None**
Feedback Position is not activated.

• **On demand**
The current position of the blinds must be requested via object 1. The position feedback will be provided to
object 2. If the end product is an application with tilting function (e.g. Venetian blind) the feedback of the slat
angle is reported to object 3.

• **Status change**
The current position of the blind is transmitted after every position change on the bus. The position is trans-
mitted on the bus when the destination position is reached.

• **Cyclic**
This parameter opens a further parameter ("Feedback cycle time") with which the time for cyclical sending is
set. With 18 motors connected, the feedback can take up to 5 seconds.

10. Feedback cycle time

This parameter defines the time intervals at which the current position of the blinds and the angle of the slats is reported by the controller and transmitted on the bus. The time required for the feedback of the motors increases with each additional motor connected. With 18 motors connected, the feedback can take up to 5 seconds.

Options:
- 1 second
- 5 seconds
- 10 seconds
- 20 seconds
- *30 seconds*
- 1 minute
- 5 minutes
- 10 minutes
- 20 minutes
- 30 minutes
- 60 minutes

4.2   Group Assignment

4.2.1   Menu index card "Group Assignment"

The settings for the group assignments are exemplarily described on "Motor 1". Depending on the number of motors selected in the menu "Motor Controller", the settings have to be done for all further motors (motor 1….18).

1.   Motor 1 belongs to

Choose an available command group:

Options: • *Command Group 1*
            • Command Group 2
            • Command Group 3
            • Command Group 4
            • Command Group 5
            • Command Group 6
            • Command Group 7
            • Command Group 8
            • Command Group 9
            • Command Group 10
            • Command Group 11
            • Command Group 12
            • Command Group 13
            • Command Group 14
            • Command Group 15
            • Command Group 16
            • Command Group 17
            • Command Group 18

Depending on the selected number of "groups used" in the menu card "Motor Controller" the command groups for each motor can be chosen accordingly.

⚠ Each motor supports only 16 command groups.

4.2.2 Menu index card "Command Group 1"

The settings for the command groups are exemplarily described on "Command Group 1". Depending on the number of command groups selected in the menu "Command Group", the settings have to be done for all further command groups (command group 1….18).

-.-.- KNX RS485 Motor Controller V3 > Command Group 1		
Motor Controller	Descriptive text for the Command Group	Text
Motor 1	Security position low priority	Ignore security ▼
Group Assignment	Security position high priority	Upper end limit ▼
	Cyclic monitor time	0 ⇕ minutes
Command Group 1	Restore previous position after security	◉ No ○ Yes
	Automatic/Manual function	None ▼
	Reaction at bus power return	Ignore security ▼
	Encoder pulses per tilting step	0 ⇕
	Block automatic position orders and IP 2	◉ No ○ Yes
	Block manual orders and IP1	◉ No ○ Yes
	Block manual tilt-step/stop orders	◉ No ○ Yes
	Position feedback for the group from	No motor ▼

1.   Description of the Command Group

The name of the command group location can be entered here. Several blinds can be grouped and named, e.g. floor, façade, room.

2.   Security position low priority

Options: • Upper end limit
                • Lower end limit
                • Intermediate position 1 (IP1)
                • Intermediate position 2 (IP2)
                • *Ignore security*
                • Stop

If a telegram with the value "1" is received on this communication object (object 153), the blind moves to the position parameterized in the ETS parameters.
If a telegram with the value "0" is received on this communication object, no operation is carried out.
If the function "Restore previous position after security" is set with "Yes", the blind moves again to the last position before activating this priority position. If a motor is used in different groups (see chapter 4.2.1), security commands from the Master Control must be linked to all the groups containing this motor. See the picture in chapter 7 Appendix

3.   Security position high priority

Options: • *Upper end limit*
                • Lower end limit
                • Ignore security
                • Stop

If a telegram with the value "1" is received on this communication object (object 154), the blind moves to the position parameterized in the ETS parameters.
If a telegram with the value "0" is received on this communication object, no operation is carried out.
If the function "Restore previous position after security" is set with "Yes", it is checked whether "Low priority" is active or inactive. When "Low priority" (value "1") is active, the blinds move to the parameterized "Security position low priority" (see previous point). If the "Low priority" (value "0") is also inactive, the blind moves again to the last position before activating the high and low priorities. If a motor is used in different groups (see chapter 4.2.1), security commands from the Master Control must be linked to all the groups containing the motor. See the graphic in chapter 7 Appendix

⚠ Emergency operation: It is possible to bypass the security priority mode using the local push buttons on the Motor Controller.

⚠ Do not cross command groups with different security functions when one motor is integrated in different command groups. Always use the same security function for all command groups!

4.   Cyclic monitor time in minutes (0 – 255)

The cyclic monitor time is active as soon as a higher value than "0" is entered and refers to both security objects, low and high priority.

⚠ With active cyclic monitoring time, attention must be paid to the fact that the time of the cyclic transmitter is lower approx. 1/4 than the parameterized cyclic monitoring time for the security objects, low and high priority. If the predefined value *"0"* remains set, the security objects react statically to the values "1" and "0".

5.   Restore previous position after security

If "Yes" is set, the blind moves back at the end of the safety function to the last position before the priority position has been activated.

6.   Automatic/Manual function

Options: • *None*
              • Priority for automatic functions
              • Priority for manual function
              • Automatic controlled by object

• **None**
The move commands are carried out in the incoming order sequence.

• **Priority automatic functions**
If an automatic command (1 bit or 1 byte) occurs prior to a manual command, all manual commands and intermediate position 1 (object 205) are disabled (1 bit and 1 byte). A reset of the priority automatic function occurs when "Priority reset" (object 211) receives "1" or "0" on the corresponding object. Shifting between priority manual function (value "0") and priority automatic function (value "1") is done via the corresponding object (object 210). After changing to the corresponding priority the function is again in the reset state. This means that for priority automatic functions the manual commands are blocked only with the next automatic command.

• **Priority manual functions**
If a manual command (1 bit or 1 byte) occurs prior to an automatic command (1 bit and 1 byte), all automatic commands are blocked. The object 206 (intermediate position 2) is also disabled. A reset of the priority manual function occurs when "Priority reset" (object 211) receives "1" or "0" on the corresponding object. Shifting between priority manual functions (value "0") and priority automatic functions (value "1") is done via the corresponding object (object 210). After changing to the corresponding priority, the function is again in the reset state. This means that for priority automatic functions the manual commands are blocked only with the next automatic command. Via the priority manual function the user has the option of switching off the automatic functions. User comfort can be defined, for example, with a timer: At 8 a.m. the priority manual function is activated via the corresponding object (210) and the user can move to the desired position using the manual functions until the function priority changes to priority automatic functions around 5 p.m. Via the corresponding object (210), switching to and from priority manual function and priority automatic function can be done at any time.

| Parameter settings	Commands that activate the function	Commands that are blocked after activating
Priority for automatic functions	**Automatic commands:** • Position automatic (1 Byte) • Slat automatic (1 Byte) • IP 2 (1 Bit)	**Manual commands:** • Up/Down (1 Bit) • IP 1 (1 Bit) • Step (1 Bit) is still possible • Position manual (1 Byte) • Slat manual (1 Byte)
Priority for manual functions	**Manual commands:** • Up/Down (1 Bit) • IP 1 (1 Bit) • Step (1 Bit) • Position manual (1 Byte) • Slat manual (1 Byte)	**Automatic commands:** • Position automatic (1 Byte) • Slat automatic (1 Byte) • IP 2 (1 Bit)

- **Automatic controlled by object**

The move commands are carried out defaultly in the incoming order sequence.
Automatic and manual orders have the same priority.
If the object "Automatic commands" is enabled = "1", all manual and automatic orders are taken into account (1 bit or 1 byte).
If the object "Automatic commands" is disabled = "0", only the manual commands are working (1 bit or 1 byte).
By enabling the object "Automatic commands" = "1" again, the last automatic order will be recalled and further commands will be executed.
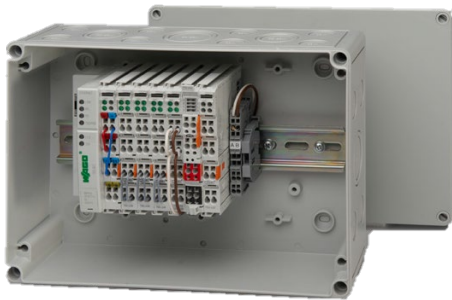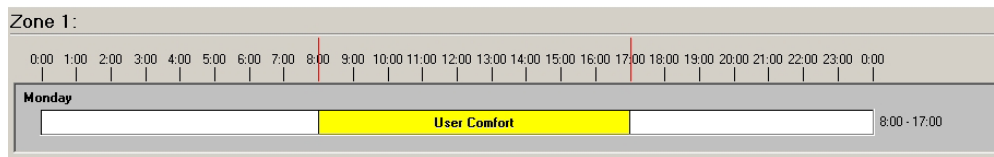
To set the timer, ideally the façade controllers
animeo KNX Master Control W2 (ref. 1860187) or
animeo KNX Master Control W8 (ref. 1860193)
can be used.

7.   Reaction at bus power return

This parameter defines the position after a bus power return.

Options: • Upper end limit
            • Lower end limit
            • Intermediate position 1 (IP1)
            • Intermediate position 2 (IP2)
            • *Ignore security*
            • Stop

8.   Encoder pulses per tilting step

The encoder pulses define the duration of the turning step of the slats (0...255). Parameter "0" defines that a blind stops and that it will not turn anymore for a step command.

9.   Step/Stop Object Dependency

This command can be used to synchronize the tilting of the blind slats.

Options: • STEP if all motors stopped
            • STEP if any motor stopped
            • STEP regardless motor status

10. Block automatic tilting orders

Automatic tilting commands for Venetian blinds can be disabled with the object (150) and with this parameter.

11. Block automatic position orders and IP2

Automatic running commands (byte/bit) can be blocked per object (155) using this parameter. If a telegram with the value "1" is received on the corresponding object during the movement of a blind, this movement is carried out up to the end. Only then further move commands (byte) and IP 2 are blocked. If a telegram with the value "0" is received on the corresponding object, the move commands (byte) are released again.

12. Block manual orders and IP1

Manual running commands (bit/byte) can be blocked per object (155) using this parameter. If a telegram with the value "1" is received on the corresponding object during a movement of the blinds, this movement is carried out up to the end. Only then further manual running commands and IP 1 are blocked. If a telegram with the value "0" is received on the corresponding object, the manual running command and IP1 are released again.

13. Block manual tilt-step/stop orders

Stop or tilting commands (bit) can be blocked per object (155) using this parameter. If a telegram with the value "0" is received on the corresponding object, the stop or turn commands (bit) are released again.

14. Position feedback for the group from …

Select which SDN motor should represent the command group.
The chosen motor with its position feedback will be the pilot motor of the whole command group.
All other motor feedbacks have lower priority.

5 Technical data

Supply voltage from KNX bus	KNX Voltage 21…30 V DC, SELV
Rated current consumption KNX	As per KNX guidelines, 12.5 mA
Terminals	RJ45
Terminal KNX	KNX bus terminal (black/red)
Operating temperature	-5° C to 50° C
Relative humidity	max. 85 %
Material of housing	PC-ABS
Housing dimensions	90 x 180 x 45 mm
Weight	175 g
Degree of protection	IP 20
Protection class	III
Conformity	www.somfy.com/ce

6 General information

Master Reset

1. Disconnect the KNX bus from the motor control unit.
2. Press the up/down button on the device, then connect the KNX bus.
3. Wait until the "KNX Prog" LED lights up.

  → The ETS project in the motor controller unit is deleted.
  → The motor IDs stored in the motor control unit are deleted, except for the motor ID of motor 1.

Discovery mode between Motor Controller and motors

⚠ During the scanning process, some motors might not be found automatically. In this case the scan has to be repeated several times. If the motors are still not found, the motor IDs have to be entered manually.

Setting new end limits via Configuration Tool or Setting Tool after downloading the ETS project

After adjusting the end limits over the Configuration or Setting Tool, it is necessary to download the ETS project again to save the current running times in the Motor Controller.

Missing error feedback while no reaction of one or more motors

If the motors do not react to any move command after commissioning, it may be that the end limits are not adjusted. It also means that the error feedback object will not be activated. You won't be informed that the end limits are not set.

  → Check if the end limits are set by pushing the local Up and Down button on the Motor Controller.

Deleting motor IDs over ETS

It is possible to delete single motor ID's by setting "FFFFF" instead of a motor ID and initiates the search of a new motor ID. It is also possible to delete all motor ID's by setting "rescan" in the motor ID of motor 1. A new search of motor IDs will be started afterwards.
If "FFFFFF" or "rescan" is set, you have to set back the parameter to "Auto" to avoid that the Motor ID is deleted again after the next download.

Avoid to assign one motor in different command groups

Synchronized movement of motors is inevitable. Be aware that security and interlocking functions only work on command group level.

Security function:
If a motor is used in different command groups, security commands from the Master Control must be linked to all command groups containing this motor (see the example in chapter 7 Appendix).
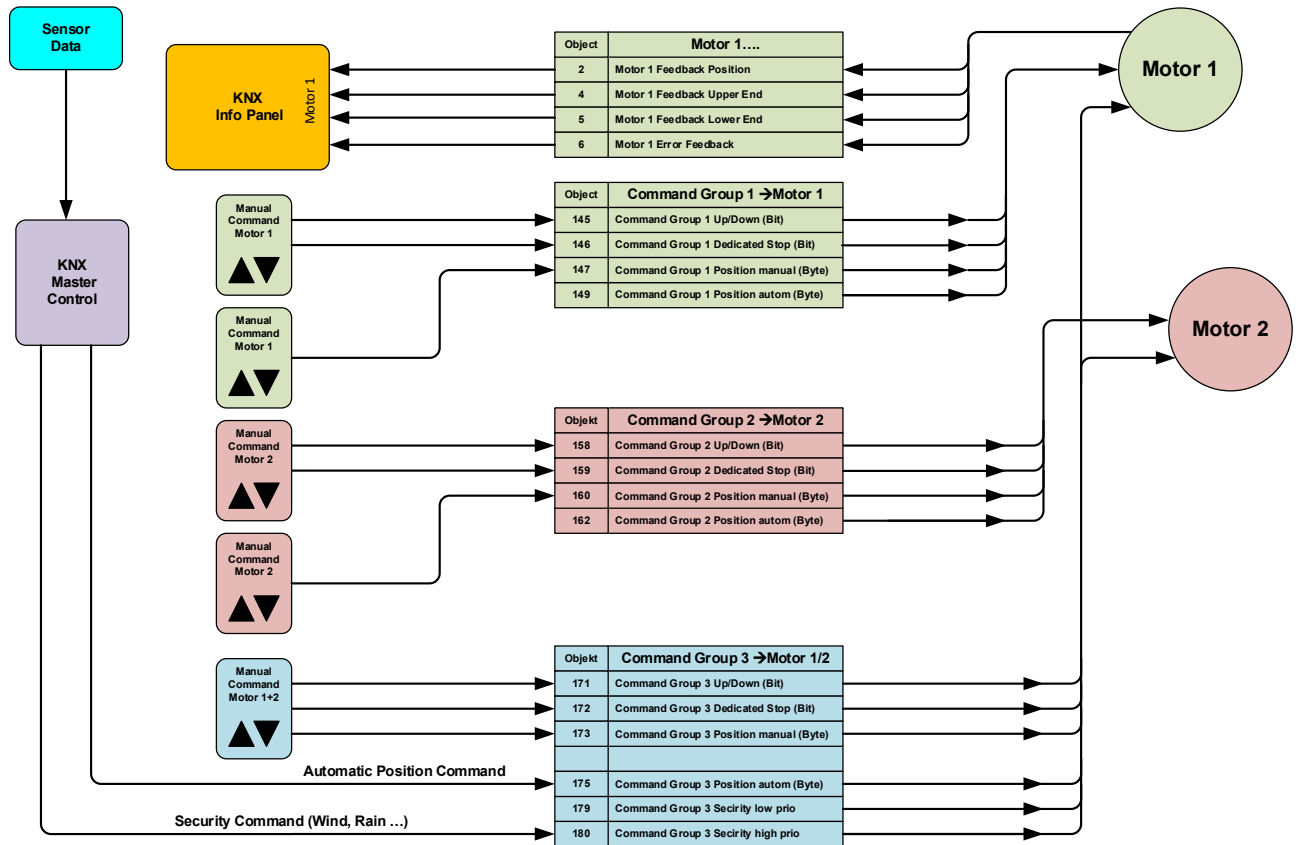
Unload application and address via ETS

Saved motor IDs won't be deleted.
Write "rescan" in the motor ID parameter of motor 1 to delete all saved motor IDs of the Motor Controller. The search of motor IDs starts afterwards.

7 Appendix

Examples of use

Somfy Activites SA
50 Avenue du Nouveau Monde
74300 Cluses
France
www.somfy.com/projects

A BRAND OF **SOMFY** GROUP

somfy.