

# Modbus Interface Description



## PR Actuator Rotary actuator for butterfly valves

Edition 2024-01 / V3.08

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## **Modbus register description**

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# Modbus general notes

## General information

Date	01.12.2023
Product Name	Butterfly Valve Actuator
Actuator Type	PR..A-BAC-..
Protocol	Modbus RTU over RS-485

## Modbus RTU

Transmission Formats	1-8-N-2, 1-8-N-1, 1-8-E-1, 1-8-O-1 (Default: 1-8-N-2)
Baud Rates	9'600, 19'200, 38'400, 76'800, 115'200 Bd (Default: 38'400 Bd)
Address	1...247 (Default: 1)
Number of Nodes	Max. 32 (without repeater)
Terminating Resistor	120 Ω

## Parametrisation

Tool	Belimo Assistant App
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## Register implementation

All data is arranged in a table and addressed by 1..n (Register No.) or 0..n-1 (Address). No distinction is made between data types (Discrete Inputs, Coils, Input Registers and Holding Registers). As a consequence, all data can be accessed with the two commands for Holding Register. The commands for Discrete Inputs and Input Registers can be used as an alternative.

## Supported commands

Standard commands:	Optional commands:
Read Holding Registers [3]	Read Discrete Inputs [2]
Write Single Register [6]	Read Input Registers [4]
	Write Multiple Registers [16]

## Command "Read Discrete Inputs"

The command reads one or more bits and can alternatively be used for Register No. 105 (Malfunction and Service Information).

Example:

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The start address to be used is 1664 -> **104** (Register Address) \* **16** (Bit) = **1664**

## Interpret values in the registers

All values in the register are unsigned integer data types.

Example:

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Read (Function 03, 1 Register)  
Value Register No. x  
= 0001 1010 1100 1000<sub>2</sub>  
= 6,856<sub>10</sub>

Actual value  
= value \* scaling factor \* unit  
= 6,856 \* 0.01 \* unit  
= **68.56 unit**

## 32-bit values in two registers

Values that exceed 65,535 are stored in two consecutive Registers and have to be interpreted as "little endian" / LSW (Least Significant Word) first.

Example:

Register No. x (Value LowWord)	Register No. x + 1 (Value HighWord)
= 14,551 <sub>10</sub>	= 19 <sub>10</sub>
= 0011 1000 1101 0111 <sub>2</sub>	= 0000 0000 0001 0011 <sub>2</sub>

<b>Value LowWord</b> = 14,551 = 0011 1000 1101 0111 <sub>2</sub>	<b>Value HighWord</b> = 19 = 0000 0000 0001 0011 <sub>2</sub>
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32-bit value  
 = 0000 0000 0001 0011 0011 1000 1101 0111<sub>2</sub>  
 = 1,259,735<sub>10</sub>  
 = **1,259.735 unit**

Math formula:

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32-bit value = (Value HighWord \* 65,536) + Value LowWord  
 32-bit value = (19 \* 65,536) + 14,551  
 = 1,259,735  
 = 1,259.735 unit

## Deactivated registers

If a register is not supported by a device or by a device setting, this is indicated by 65,535 (1111 1111 1111 1111<sub>2</sub>).

# Modbus register overview

## Operation

No.	Address	Register	Access
1	0	Setpoint [%]	R / W
2	1	Override Control	R / W
3	2	Command	R / W
4	3	Actuator Type	R
5	4	Relative Position [%]	R
6	5	Absolute Position [°] [mm]	R
7	6	-	-
8	7	-	-
9	8	Sensor Value 1 [mV] [Ω] [-] [°C] [°F]	R
10	9	Sensor Value 2 [mV] [Ω] [-] [°C] [°F]	R
11	10	-	-
12	11	-	-
13	12	Analog Setpoint [%]	R

## Service

No.	Address	Register	Access
100	99	Bus Termination	R
101	100	Series Number 1 <sup>st</sup> part	
102	101	Series Number 2 <sup>nd</sup> part	R
103	102	Series Number 4 <sup>th</sup> part	
104	103	Firmware Version	R
105	104	Malfunction and Service Information	R
106	105	-	-
107	106	Max [%]	R / W
108	107	Sensor Type 1	R / W
109	108	Bus Fail Position	R / W
110	109	Communication Watchdog	R / W
111	110	-	-
112	111	-	-
113	112	-	-
114	113	-	-
115	114	Sensor Type 2	R / W
116	115	-	-
117	116	-	-
118	117	-	-
119	118	Setpoint Source	R / W
190	189	Fail-Safe Bridging Time	R / W
191	190	Fail-Safe Position	R / W



All writeable registers >100 are persistent and are **not** supposed to be written on a regular basis.

# Modbus register description

No.	Address	Description Comment	Range, enumeration	Unit	Scaling	Access
1	0	<b>Setpoint</b> Setpoint for actuator between 0 and Max (Register No. 107)	0...10'000 Default: 0	%	0.01	R / W
2	1	<b>Override control</b> Overrides setpoint with defined values. Use of Fast open / Fast close: Fast open and Fast close cycles lead to increased mechanical load. Usage should be limited to certain time-critical events (e.g. frost protection).	0: None 1: Open 2: Close 3: Min 4: Mid 5: Max 6: Fast Open 7: Fast Close Default: None(0)	–	–	R / W
3	2	<b>Command</b> Initiation of actuator functions for service and test. After command is sent, register returns to None(0). With Reset(4), all malfunction and service information (Register No. 105) can be reset.	0: None 1: – 2: Test 3: Sync 4: Reset Default: None(0)	–	–	R / W
4	3	<b>Actuator type</b>	0: Actuator not connected 1: <b>Air / water</b> 2: VAV / EPIV 3: Fire 4: Energy Valve 5: 6way EPIV	–	–	R
5	4	<b>Relative position</b>	0...10'000	%	0.01	R
6	5	<b>Absolute position</b> The unit depends on the device: [°] for actuators with rotary movement [mm] for actuators with linear movement	0...max angle / stroke	° mm	1 1	R
7	6	–	–	–	–	–
8	7	–	–	–	–	–
9	8	<b>Sensor 1 value</b> Current value of sensor 1, depending on the setting of the sensor 1 type (Register No. 108) [mV] if sensor 1 type (Register No. 108) is Active(1) [Ω] if sensor 1 type (Register No. 108) is Passive_1K(2) or Passive_20K(3) [0 / 1] if sensor 1 type (Register No. 108) is Switch(4) [°C] if sensor 1 type (Register No. 108) is PT1000_C(5) or NI1000_C(6) or NTC10K2_C(7) [°F] if sensor 1 type (Register No. 108) is PT1000_F(8) or NI1000_F(9) or NTC10K2_F(10)	0...65'535	mV Ω – °C °F	1 1 0 / 1 0.1 0.1	R

No.	Address	Description Comment	Range, enumeration	Unit	Scaling	Access
10	9	<b>Sensor 2 value</b> Current value of sensor 2, depending on the setting of the sensor 2 type (Register No. 108) [mV] if sensor 2 type (Register No. 108) is Active(1) [Ω] if sensor 2 type (Register No. 108) is Passive_1K(2) or Passive_20K(3) [0 / 1] if sensor 2 type (Register No. 108) is Switch(4) [°C] if sensor 2 type (Register No. 108) is PT1000_C(5) or NI1000_C(6) or NTC10K2_C(7) [°F] if sensor 2 type (Register No. 108) is PT1000_F(8) or NI1000_F(9) or NTC10K2_F(10)	0...65'535	mV Ω – °C °F	1 1 0 / 1 0.1 0.1	R
11	10	–	–	–	–	–
12	11	–	–	–	–	–
13	12	<b>Analog setpoint</b> Shows the setpoint in % if actuator is controlled by analog signal.	0...10'000	%	0.01	R
100	99	<b>Bus termination</b> Indicates if bus termination (120 Ω) is enabled. Bus termination can be set with the configuration tools.	0: Inactive 1: Active Default: Inactive(0)	–	–	R
101	100	<b>Series number 1<sup>st</sup> part</b> Each device has an unambiguous series number, which is either impressed on or glued to the housing. The series number consists of 4 segments, although only parts 1, 2 and 4 are displayed on Modbus. Example: 00839-31324-064-008 1 <sup>st</sup> part: 00839 2 <sup>nd</sup> part: 31324 4 <sup>th</sup> part: 008	–	–	–	R
102	101	<b>Series number 2<sup>nd</sup> part</b>	–	–	–	R
103	102	<b>Series number 4<sup>th</sup> part</b>	–	–	–	R
104	103	<b>Firmware version</b> Firmware version of communication module Example: 302, Version 3.02	–	–	–	R
105	104	<b>Malfunction and service information</b> Value is bit-coded. More than one bit can be set to 1. Not all bits mentioned in the enumeration are used for this actuator range.  1: Mechanical travel increased: The actuator has been moved outside the adapted working range. 2: Actuator cannot move: Mechanical overload, e.g. blocked actuator, etc. 8: Internal activity: Actuator performs a test run, adaptation, etc. 9: Gear train disengaged: The manual override button is pressed. 10: Bus Watchdog triggered: Timeout for the Bus Watchdog expired.	Bitmask =  Bit0: – Bit1: Mechanical travel increased Bit2: Actuator cannot move Bit3: – Bit4: – Bit5: – Bit6: – Bit7: – Bit8: Internal activity Bit9: Gear train disengaged Bit10: Bus Watchdog triggered Bit11: – Bit12: – Bit13: – Bit14: – Bit15: –	–	–	R
106	105	–	–	–	–	–
107	106	<b>Max</b> Max has to be ≥ Min +30%	Min +3'000...10'000 Default: 10'000	%	0.01	R / W

No.	Address	Description Comment	Range, enumeration	Unit	Scaling	Access
108	107	<b>Sensor 1 type</b>	0: None 1: Active 2: Passive_1K 3: Passive_20K 4: Switch 5: PT1000_C 6: NI1000_C 7: NTC10K2_C 8: PT1000_F 9: NI1000_F 10: NTC10K2_F Default: None(0)	–	–	R / W
109	108	<b>Bus fail position</b> Modbus communication is not monitored by default. In the event of a breakdown in communication, the actuator retains the current setpoint. The bus implementation tracks the Modbus communication. If neither the setpoint (Register No. 1) nor the override control (Register No. 2) is renewed before the timeout for Bus Watchdog (Register No. 110) expires, the actuator moves to the bus fail position. Triggered Bus Watchdog is indicated in the malfunction and service information (Register No. 105). In hybrid mode (SpSource (Register No. 119) = Analog), bus monitoring is not activated.	0: None / last setpoint 1: Fast close 2: Fast open 3: Mid position (parametrised) Default: None(0)	–	–	R / W
110	109	<b>Timeout for Bus Watchdog in s</b> Time until bus fail will be detected. If Bus Watchdog = 0 then deactivated. If bus fail position (Register No. 109) different from 0, the bus fail position becomes active after the timeout for Bus Watchdog has expired.	0...3'600 Default: 0 If bus fail position (Register No. 109) not None(0), then Default: 120	s	1	R / W
111	110	–	–	–	–	–
112	111	–	–	–	–	–
113	112	–	–	–	–	–
114	113	–	–	–	–	–
115	114	<b>Sensor 2 type</b>	0: None 1: Active 2: Passive_1K 3: Passive_20K 4: Switch 5: PT1000_C 6: NI1000_C 7: NTC10K2_C 8: PT1000_F 9: NI1000_F 10: NTC10K2_F Default: None(0)	–	–	R / W
116	115	–	–	–	–	–
117	116	–	–	–	–	–
118	117	–	–	–	–	–
119	118	<b>Setpoint source</b> Analog: Setpoint from analog signal 0...10 V on wire 3 Bus: Setpoint from Modbus (Register No. 1)	0: Analog 1: Bus Default: Bus(1)	–	–	R / W
190	189	<b>Fail-safe bridging time</b> In the event of a power failure, the actuator will remain stationary in accordance with the set bridging time. Only for electronic fail-safe actuators	0...10	s	1	R / W
191	190	<b>Fail-safe position</b> In the event of a power failure, the actuator will move into the selected fail-safe position, taking into account the bridging time that has been set. The rotary knob must be set to "tool" position.	0...10'000	%	0.01	R / W

Description Access: R = Read, W = Write



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