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DELTA_IA-MDS_CP2000_UM_EN_20200901

Delta Fan/Pump Vector Control Drive - CP2000 Series User Manual

Delta Fan/Pump Vector Control Drive CP2000 Series User Manual

www.deltaww.com

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PLEASE READ PRIOR TO INSTALLATION FOR SAFETY.

DANGER

☑ Disconnect AC input power before connecting any wiring to the AC motor drive.

☑ Even if the power has been turned off, a charge may still remain in the DC-link capacitors with hazardous voltages before the POWER LED is OFF. Do NOT touch the internal circuits and components.

☑ There are highly sensitive MOS components on the printed circuit boards. These components are especially sensitive to static electricity. Take anti-static measure before touching these components or the circuit boards.

☑ Never modify the internal components or wiring.

☑ Ground the AC motor drive by using the ground terminal. The grounding method must comply with the laws of the country where the AC motor drive is to be installed.

☑ Do NOT install the AC motor drive in a location with high temperature, direct sunlight or inflammable materials or gases.

CAUTION

☑ Never connect the AC motor drive output terminals U/T1, V/T2 and W/T3 directly to the AC mains circuit power supply.

☑ After finishing the wiring of the AC motor drive, check if U/T1, V/T2, and W/T3 are short-circuited to ground with a multimeter. Do NOT power the drive if short circuits occur. Eliminate the short circuits before the drive is powered.

☑ The rated voltage of power system to install motor drives is listed below. Ensure that the installation voltage is in the correct range when installing a motor drive.

1. For 230V models, the range is between 170–264V.
2. For 460V models, the range is between 323–528V.
3. For 575V models, the range is between 446–660V.
4. For 690V models, the range is between 446–759V.

☑ Refer to the table below for short circuit rating:

Model (Power)	Short circuit rating
230V / 460V	100 kA
575V (2–20HP)	5 kA
690V (25–50HP)	5 kA
690V (60–175HP)	10 kA
690V (215–335HP)	18 kA
690V (425–600HP)	30 kA
690V (745–850HP)	42 kA

☑ Only qualified persons are allowed to install, wire and maintain the AC motor drives.

☑ Even if the three-phase AC motor is stopped, a charge with hazardous voltages may still remain in the main circuit terminals of the AC motor drive.

☑ The performance of electrolytic capacitor will degrade if it is not charged for a long time. It is recommended to charge the drive which is stored in no charge condition every 2 years for 3–4 hours to restore the performance of electrolytic capacitor in the motor drive. Note: When power up the motor drive, use adjustable AC power source (ex. AC autotransformer) to charge the drive at 70%–80% of rated voltage for 30 minutes (do not run the motor drive). Then charge the drive at 100% of rated voltage for an hour (do not run the motor drive). By doing these, restore the performance of electrolytic capacitor before starting to run the motor drive. Do NOT run the motor drive at 100% rated voltage right away.

☑ Pay attention to the following precautions when transporting and installing this package (including wooden crate and wood stave)

1. If you need to deworm the wooden crate, do NOT use fumigation or you will damage the drive. Any damage to the drive caused by using fumigation voids the warranty.

2. Use other methods, such as heat treatment or any other non-fumigation treatment, to deworm the wood packaging material.
3. If you use heat treatment to deworm, leave the packaging materials in an environment of over 56°C for a minimum of thirty minutes.

☑ Connect the drive to a three-phase three-wire or three-phase four-wire Wye system to comply with UL standards.

☑ If the motor drive generates leakage current over AC 3.5 mA or over DC 10 mA on a grounding conductor, compliance with local grounding regulations or IEC61800-5-1 standard is the minimum requirement for grounding.

NOTE

The content of this manual may be revised without prior notice. Please consult our distributors or download the latest version at http://www.deltaww.com/iadownload_acmotordrive

Table of Contents

Issued Edition: 01
Firmware Version: V2.07
(Refer to Parameter 00-06 on the product to get the firmware version.)
Issued Date: 2020/09

Chapter 1 Introduction

1-1 Nameplate Information

1-2 Model Name

1-3 Serial Number

1-4 Apply After Service by Mobile Device

1-5 RFI Jumper

1-6 Dimensions

Receiving and Inspection

After receiving the AC motor drive, check for the following:

1. Inspect the unit after unpacking to ensure that it was not damaged during shipment. Make sure that the part number printed on the package matches the part number indicated on the nameplate.
2. Make sure that the mains voltage is within the range indicated on the nameplate. Install the AC motor drive according to the instructions in this manual.
3. Before applying power, make sure that all devices, including mains power, motor, control board and digital keypad, are connected correctly.
4. When wiring the AC motor drive, make sure that the wiring of input terminals “R/L1, S/L2, T/L3” and output terminals “U/T1, V/T2, W/T3” are correct to prevent damage to the drive.
5. When power is applied, use the digital keypad (KPC-CC01) to select the language and set parameters. When executing a trial run, begin with a low speed and then gradually increase the speed to the desired speed.

1-1 Nameplate Information:

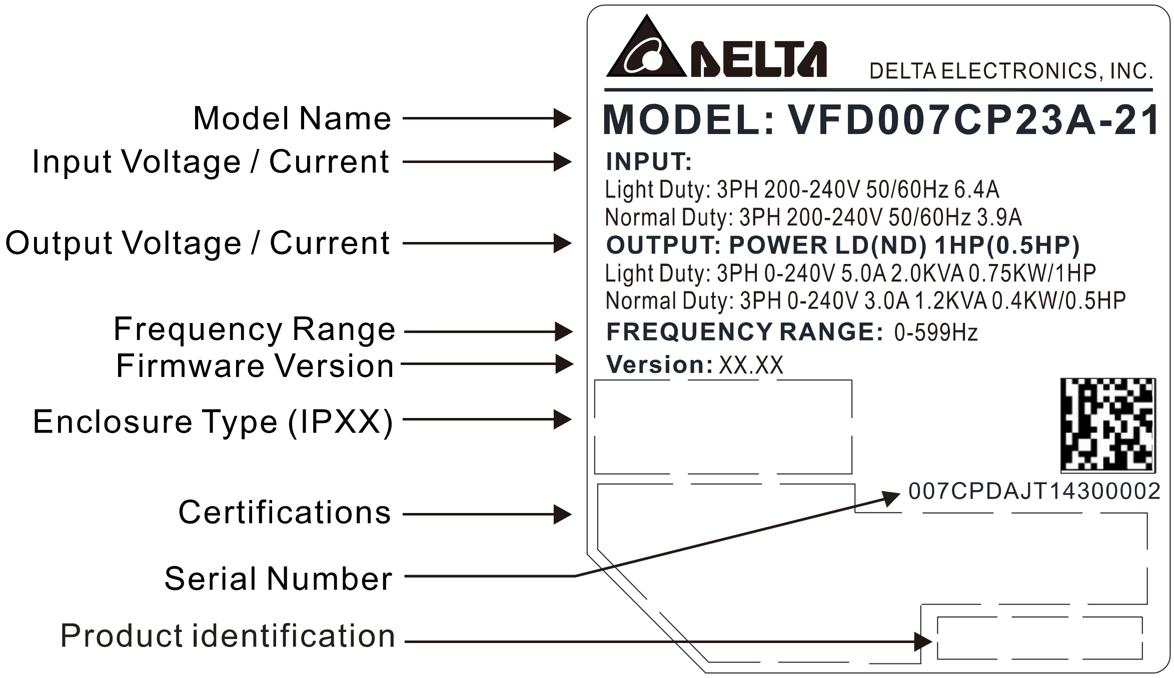
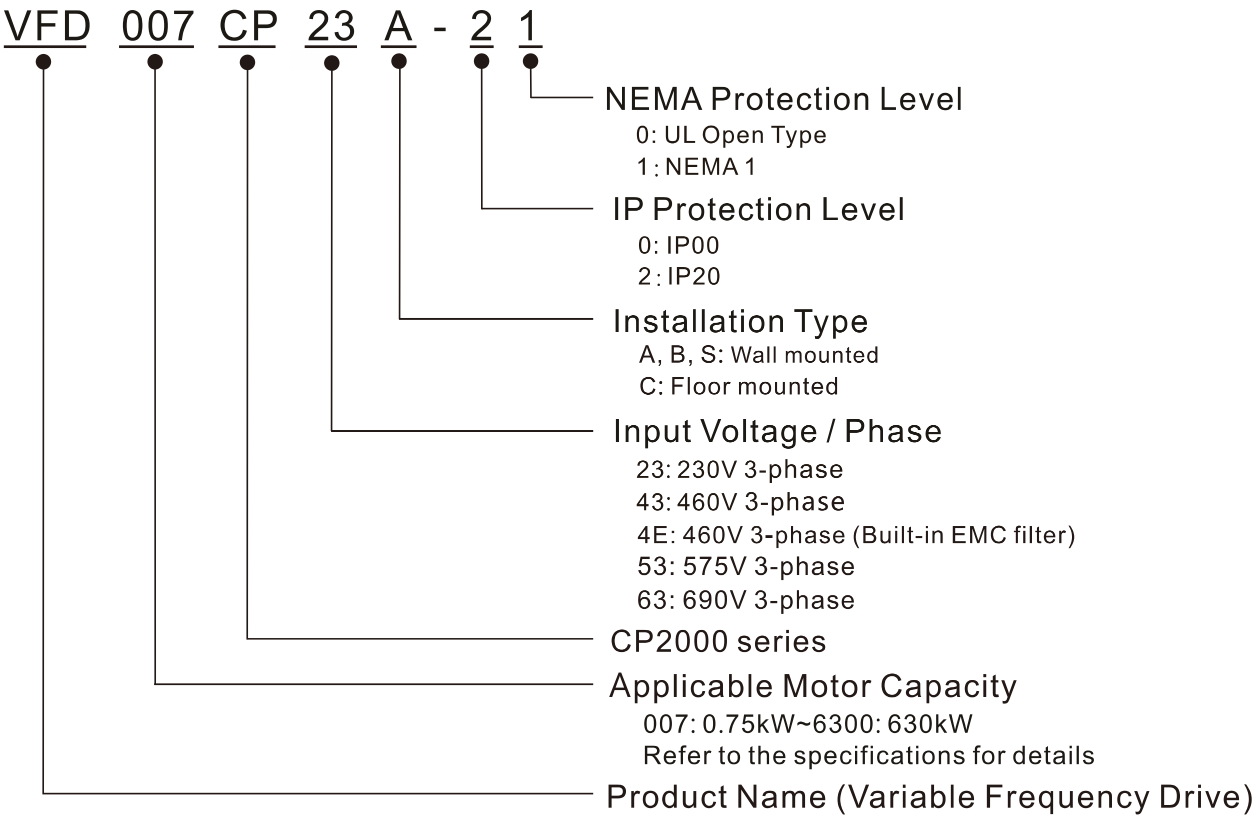


Figure 1-1

1-2 Model Name:



VFD 007 CP 23 A - 2 1

NEMA Protection Level
0: UL Open Type
1 : NEMA 1

IP Protection Level
0: IP00
2 : IP20

Installation Type
A, B, S: Wall mounted
C: Floor mounted

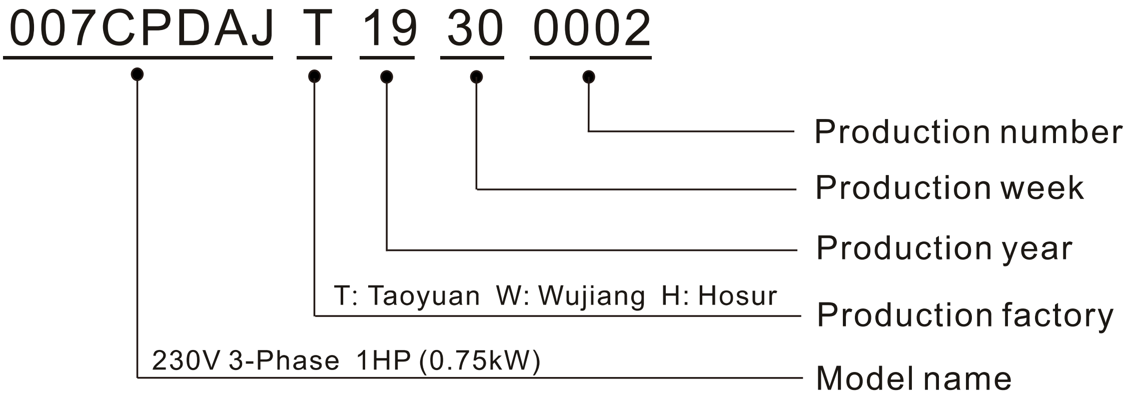
Input Voltage / Phase
23: 230V 3-phase
43: 460V 3-phase
4E: 460V 3-phase (Built-in EMC filter)
53: 575V 3-phase
63: 690V 3-phase

CP2000 series

Applicable Motor Capacity
007: 0.75kW~6300: 630kW
Refer to the specifications for details

Product Name (Variable Frequency Drive)

1-3 Serial Number:



007CPDAJ T 19 30 0002

Production number

Production week

Production year

T: Taoyuan W: Wujiang H: Hosur — Production factory

230V 3-Phase 1HP (0.75kW) — Model name

1-4 Apply After Service by Mobile Device

1-4-1 Location of Service Link Label

Frame A–H

Service link label (Service Label) is pasted on the area as the drawing below shows:

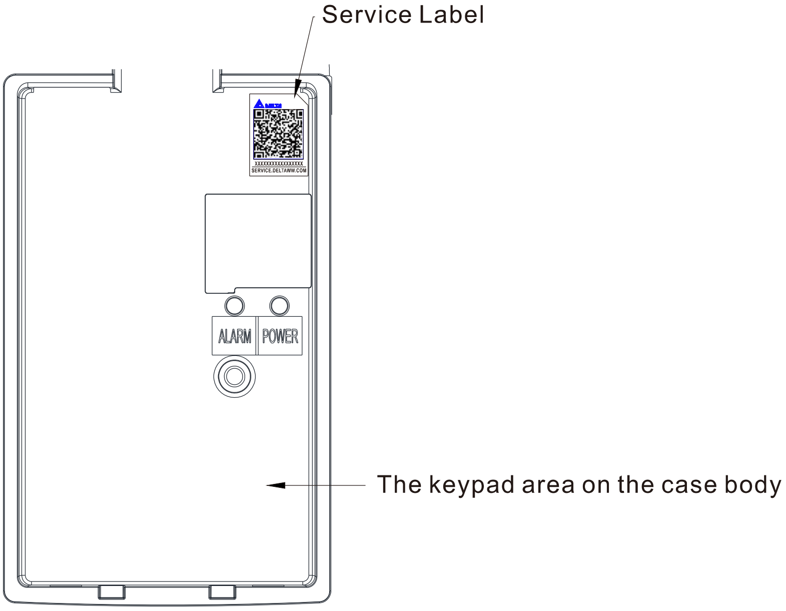


Figure 1-2

1-4-2 Service Link Label

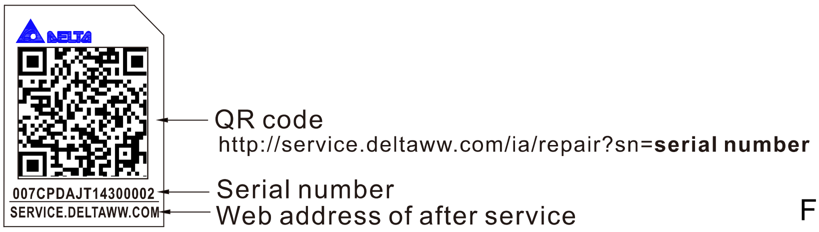

DELTA
QR code
http://service.deltaww.com/ia/repair?sn=**serial number**
007CPDAJT14300002
SERVICE.DELTAWW.COM
Serial number
Web address of after service

Figure 1-3

Scan QR Code to apply

1. Find the QR code sticker (as shown above).
2. Use a smartphone to run a QR Code reader APP.
3. Point your camera at the QR Code. Hold your camera steady until the QR code comes into focus.
4. Access the Delta After Service website.
5. Fill your information into the column marked with an orange star.
6. Enter the CAPTCHA and click “Submit” to complete the application.

Cannot find the QR Code?

1. Open a web browser on your computer or smart phone.
2. Enter https://service.deltaww.com/ia/repair in browser address bar and press the Enter key.
3. Fill your information into the columns marked with an orange star.
4. Enter the CAPTCHA and click “Submit” to complete the application.

1-5 RFI Jumper

(1) The driver contains Varistor / MOVs that are connected from phase-to-phase and from phase-to-ground to prevent the drive from unexpected stop or damage caused by mains surges or voltage spikes. Because the Varistors / MOVs from phase-to-ground are connected to ground with the RFI jumper, removing the RFI jumper disables the protection.

(2) In the models with a built-in EMC filter, the RFI jumper connects the filter capacitors to ground to form a return path for high frequency noise in order to isolate the noise from contaminating the mains power. Removing the RFI jumper strongly reduces the effect of the built-in EMC filter. Although a single drive complies with the international standards for leakage current, an installation with several drives with built-in EMC filter can trigger the RCD. Removing the RFI jumper helps, but the EMC performance of each drive would be no longer guaranteed.

Frame A–C

Screw Torque: 8–10 kg-cm / [6.9–8.7 lb -in.] / [0.8–1.0 Nm]

Loosen the screw and remove the MOV-PLATE. Fasten the screws back to the original position after MOV-PLATE is removed.

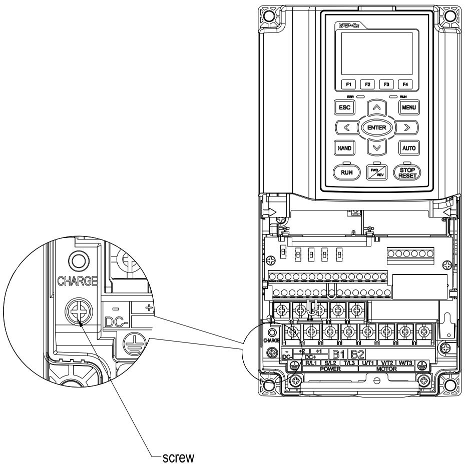


Figure 1-4

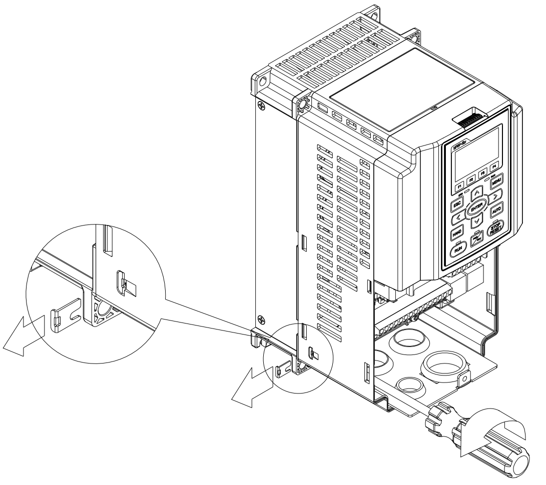


Figure 1-5

Frame D0–H

Remove the MOV-PLATE by hands, no screws need to be loosen

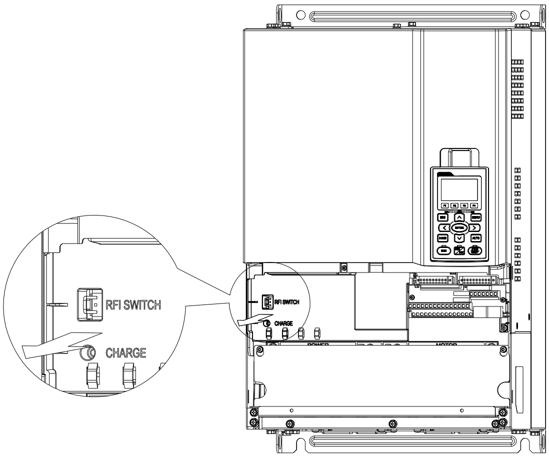


Figure 1-6

Isolating main power from ground:

When the power distribution system for the drive is a floating ground system (IT Systems) or an asymmetric ground system (Corner Grounded TN Systems), you must remove the RFI jumper. Removing the RFI Jumper disconnects the internal capacitors from ground to avoid damaging the internal circuits and to reduce the ground leakage current.

Important points regarding ground connection

☑ To ensure the safety of personnel, proper operation, and to reduce electromagnetic radiation, you must properly ground the motor and drive during installation.

☑ The diameter of the grounding cables must comply with the local safety regulations.

☑ You must connect the shielded cable to the motor drive's ground to meet safety regulations.

☑ Only use the shielded cables as the ground for equipment when the aforementioned points are met.

☑ When installing multiple drives, do not connect the grounds of the drives in series but connect each drive to ground. The following pictures show the correct and wrong ways to connect the grounds.

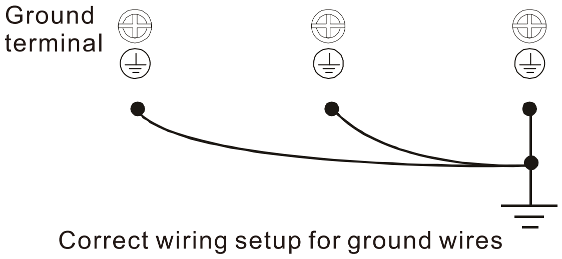


Figure 1-7

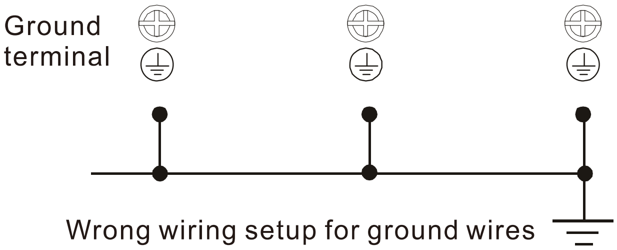


Figure 1-8

Pay particular attention to the following points:

☑ Do not remove the RFI jumper while the power is on.

☑ Removing the RFI jumper also cuts the capacitor conductivily of the surge absorber to ground and the built-in EMC filter capacitors. Compliance with the EMC specifications is no longer guaranteed.

☑ Do not remove the RFI jumper if the mains power is a symmetrical grounded power system in order to maintain the efficiency for EMC circuit.

☑ Remove the RFI jumper when conducting high voltage tests. When conducting a high voltage test to the entire facility, disconnect the mains power and the motor if the leakage current is too high.

Floating Ground System (IT Systems)

A floating ground system is also called an IT system, an ungrounded system, or a high impedance / resistance (greater than 30 Ω) grounded system.

☑ Remove the RFI jumper to disconnect the ground cable from the internal filter capacitor and surge absorber.

☑ In situations where EMC is required, check for excess electromagnetic radiation affecting nearby low-voltage circuits. In some situations, the adapter and cable naturally provide enough suppression. If in doubt, install an extra electrostatic shielded cable on the power supply side between the main circuit and the control terminals to increase shielding.

☑ Do not install an external RFI / EMC filter. The external EMC filter passes through a filter capacitor and connects power input to the ground. This is very dangerous and damages the motor drive.

Asymmetric Ground System (Corner Grounded TN Systems)

Caution: Do not remove the RFI jumper while power to the input terminal of the drive is ON.

In the following four situations, you must remove the RFI jumper. This is to prevent the system from grounding through the RFI and filter capacitors and damaging the drive.

<table>
<tr><th colspan="2">You must remove the RFI jumper for an asymmetric ground system</th></tr>
<tr><td>1. Grounding at a corner in a triangle configuration

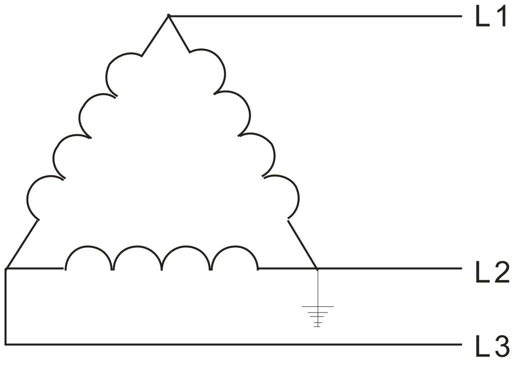



Figure 1-9</td><td>2. Grounding at a midpoint in a polygonal configuration

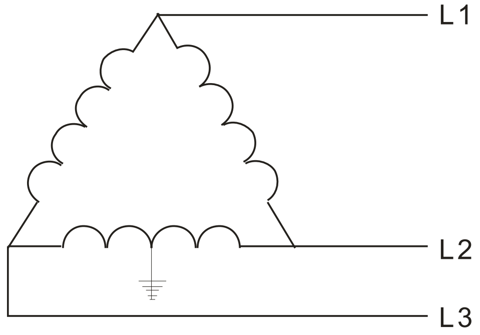



Figure 1-10</td></tr>
<tr><td>3. Grounding at one end in a single-phase configuration

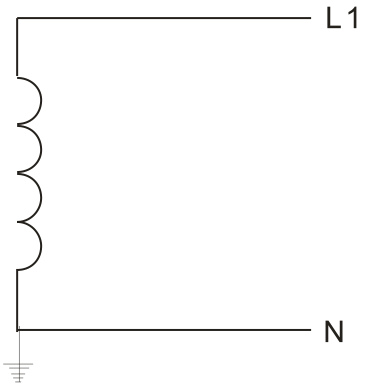



Figure 1-11</td><td>4. No stable neutral grounding in a three-phase autotransformer configuration

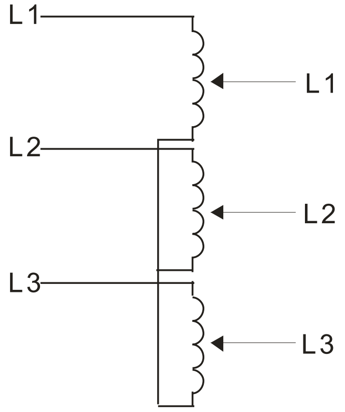
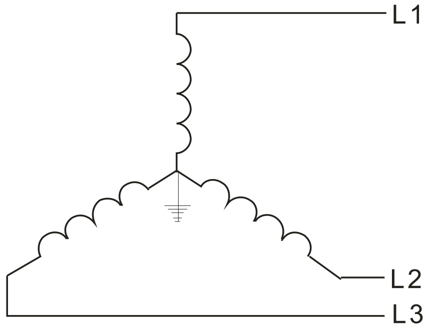



Figure 1-12</td></tr>
</table>

<table>
<tr><th colspan="2">You can use the RFI jumper for a symmetrical grounding power system</th></tr>
<tr><td>In a situation with a symmetrical grounding power system, you can use the RFI jumper to maintain the effect of the built-in EMC filter and surge absorber. For example, the diagram on the right is a symmetrical grounding power system.</td><td>
Figure 1-13</td></tr>
</table>

1-6 Dimensions

Frame A

VFD007CP23A-21; VFD015CP23A-21; VFD022CP23A-21; VFD037CP23A-21; VFD055CP23A-21; VFD007CP43A-21; VFD015CP43B-21; VFD022CP43B-21; VFD037CP43B-21; VFD040CP43A-21; VFD055CP43B-21; VFD075CP43B-21; VFD007CP4EA-21; VFD015CP4EB-21; VFD022CP4EB-21; VFD037CP4EB-21; VFD040CP4EA-21; VFD055CP4EB-21; VFD075CP4EB-21; VFD015CP53A-21; VFD022CP53A-21; VFD037CP53A-21

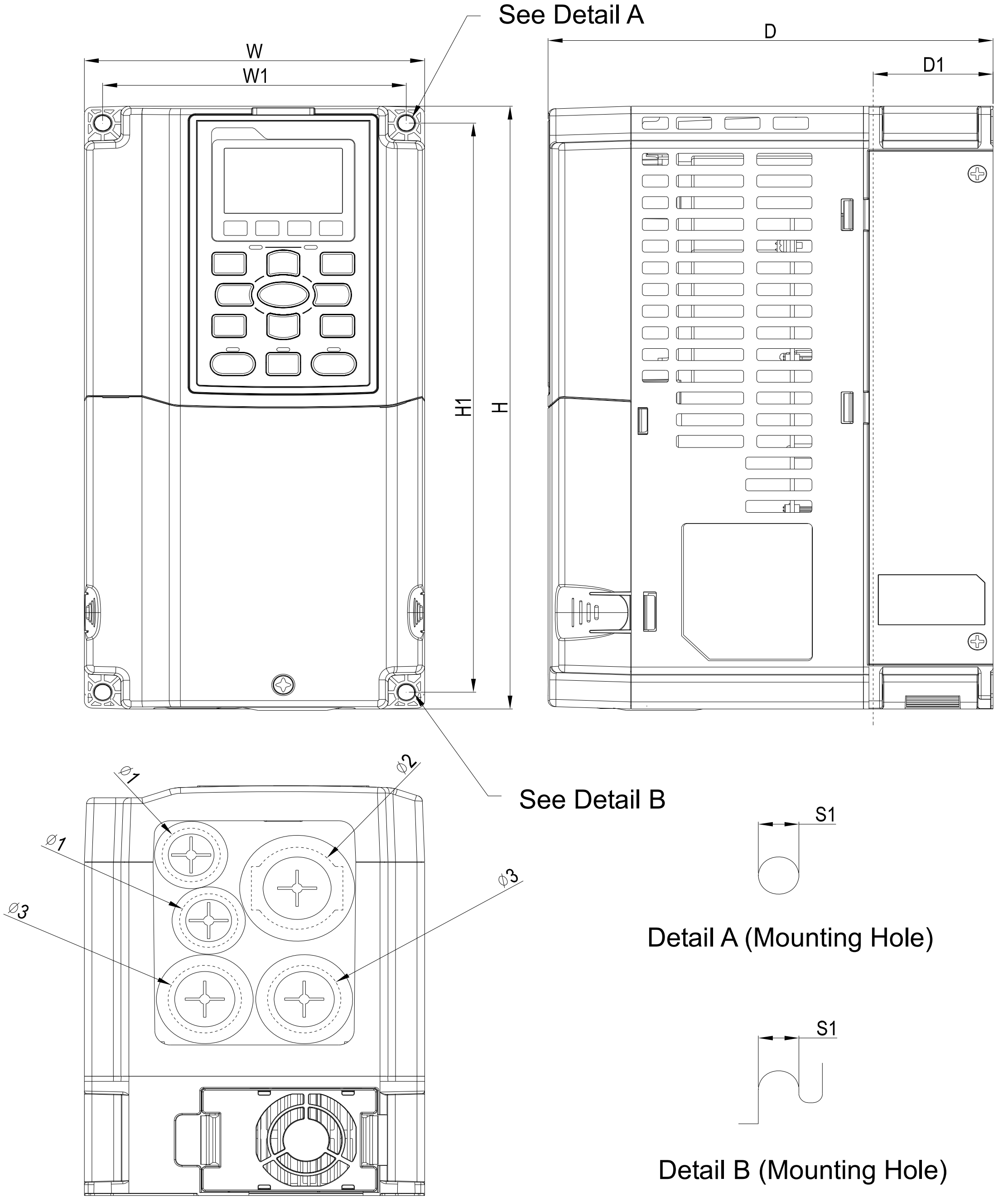


Figure 1-14

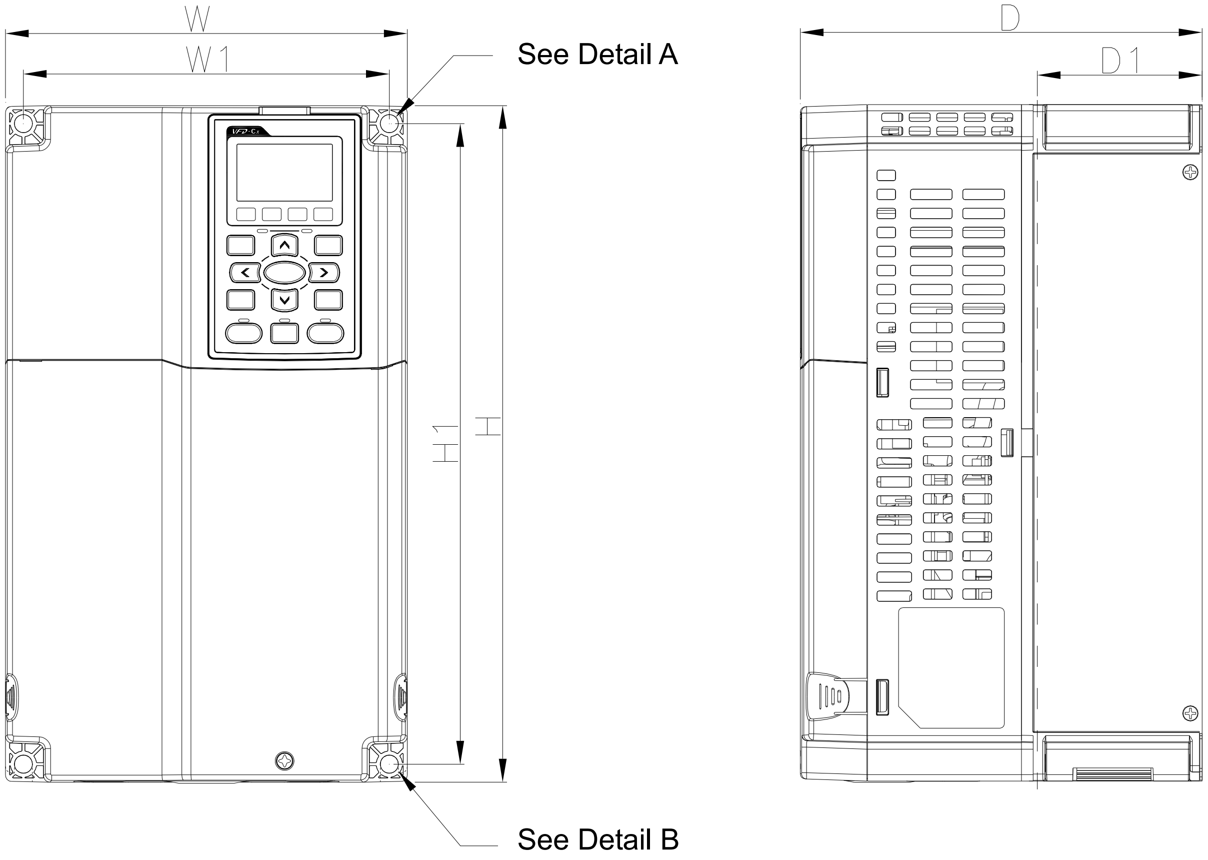
Unit: mm [inch]

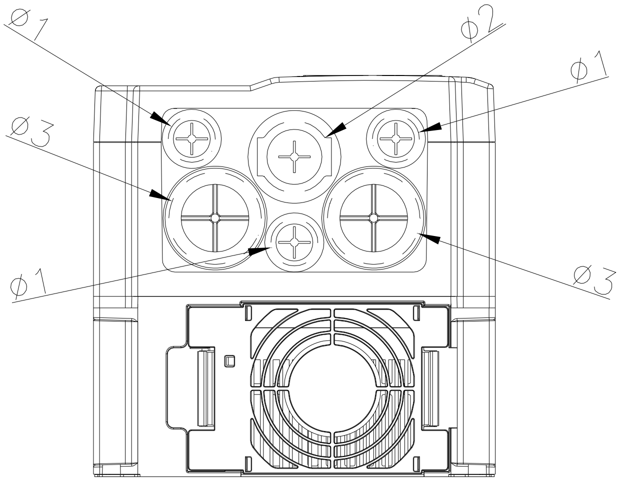
Frame	W	H	D	W1	H1	D1*	S1	Φ1	Φ2	Φ3
A	130.0 [5.12]	250.0 [9.84]	170.0 [6.69]	116.0 [4.57]	236.0 [9.29]	45.8 [1.80]	6.2 [0.24]	22.2 [0.87]	34.0 [1.34]	28.0 [1.10]

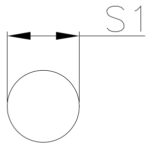
D1*: Flange mounting

Frame B

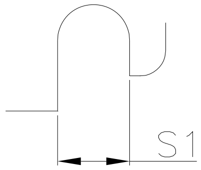
VFD075CP23A-21; VFD110CP23A-21; VFD150CP23A-21; VFD110CP43B-21; VFD150CP43B-21; VFD185CP43B-21; VFD110CP4EB-21; VFD150CP4EB-21; VFD185CP4EB-21; VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21; VFD150CP53A-21







Detail A (Mounting Hole)



Detail B (Mounting Hole)

Figure 1-15

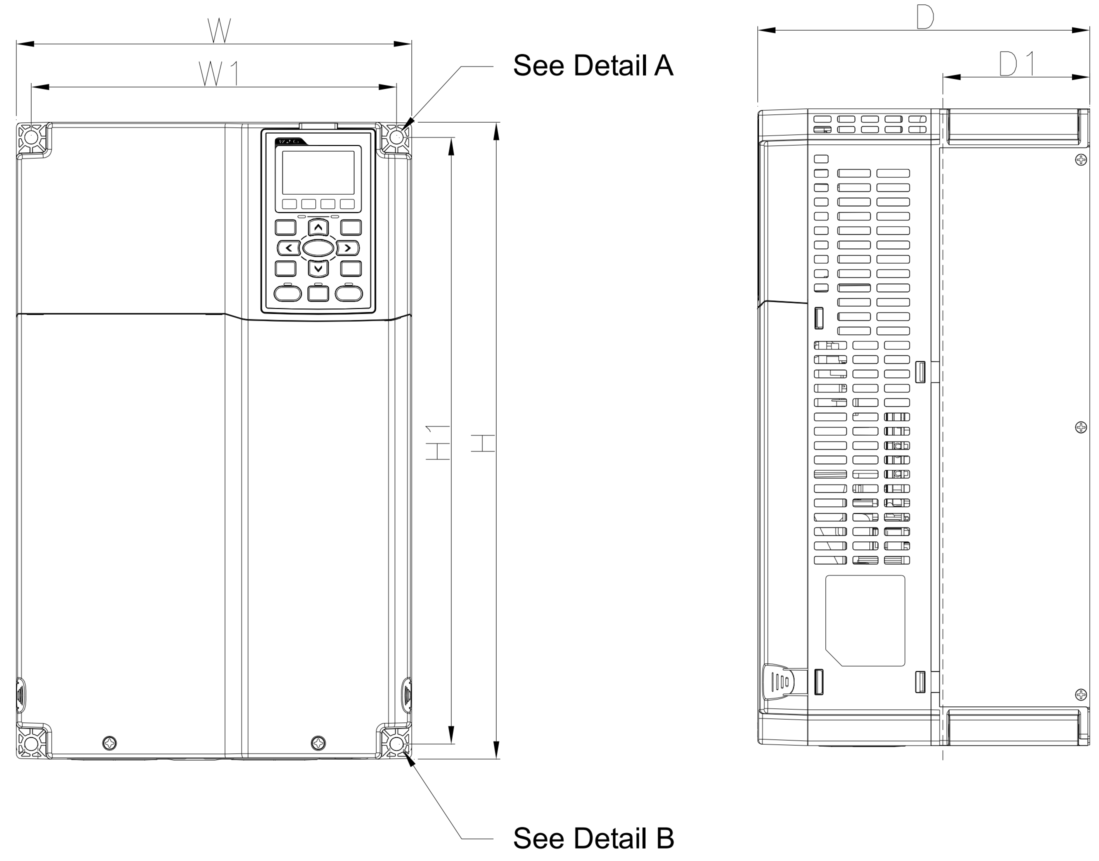
Unit: mm [inch]

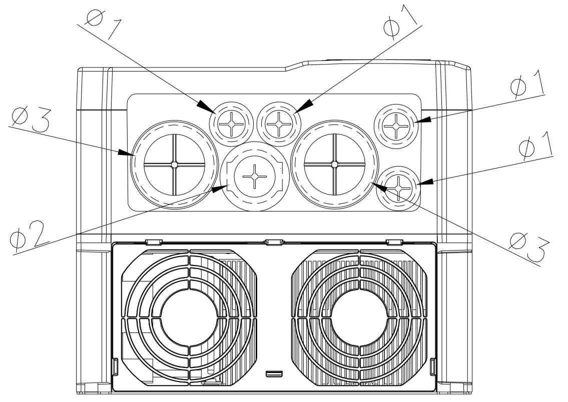
Frame	W	H	D	W1	H1	D1*	S1	Φ1	Φ2	Φ3
B	190.0 [7.48]	320.0 [12.60]	190.0 [7.48]	173.0 [6.81]	303.0 [11.93]	77.9 [3.07]	8.5 [0.33]	22.2 [0.87]	34.0 [1.34]	43.8 [1.72]

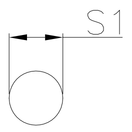
D1*: Flange mounting

Frame C

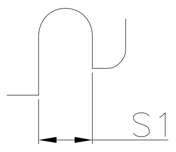
VFD185CP23A-21; VFD220CP23A-21; VFD300CP23A-21; VFD220CP43A-21; VFD300CP43B-21; VFD370CP43B-21; VFD220CP4EA-21; VFD300CP4EB-21; VFD370CP4EB-21; VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21







Detail A (Mounting Hole)



Detail B (Mounting Hole)

Figure 1-16

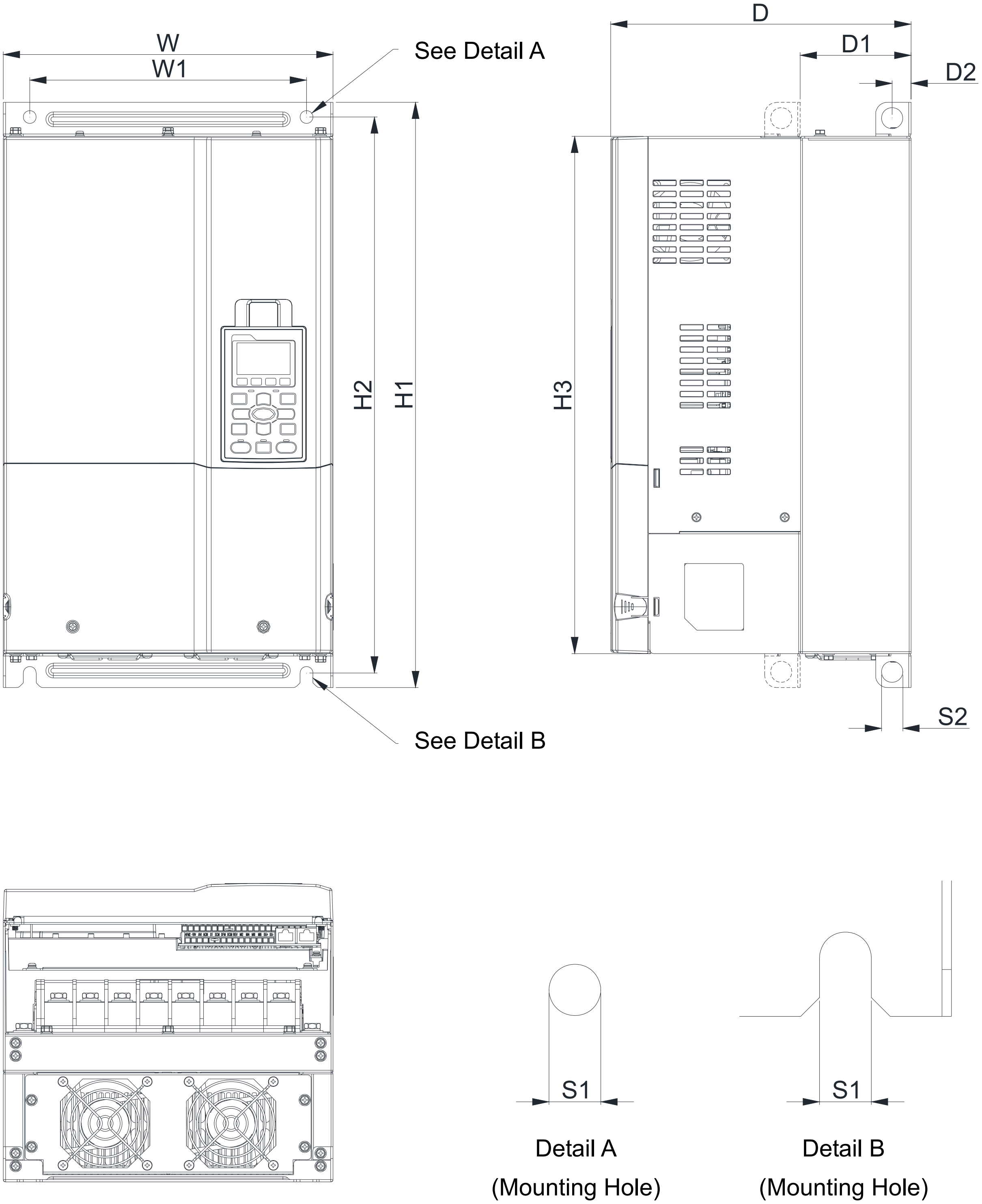
Unit: mm [inch]

Frame	W	H	D	W1	H1	D1*	S1	Φ1	Φ2	Φ3
C	250.0 [9.84]	400.0 [15.75]	210.0 [8.27]	231.0 [9.09]	381.0 [15.00]	92.9 [3.66]	8.5 [0.33]	22.2 [0.87]	34.0 [1.34]	50.0 [1.97]

D1*: Flange mounting

Frame D

D0-1: VFD450CP43S-00; VFD550CP43S-00



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-17

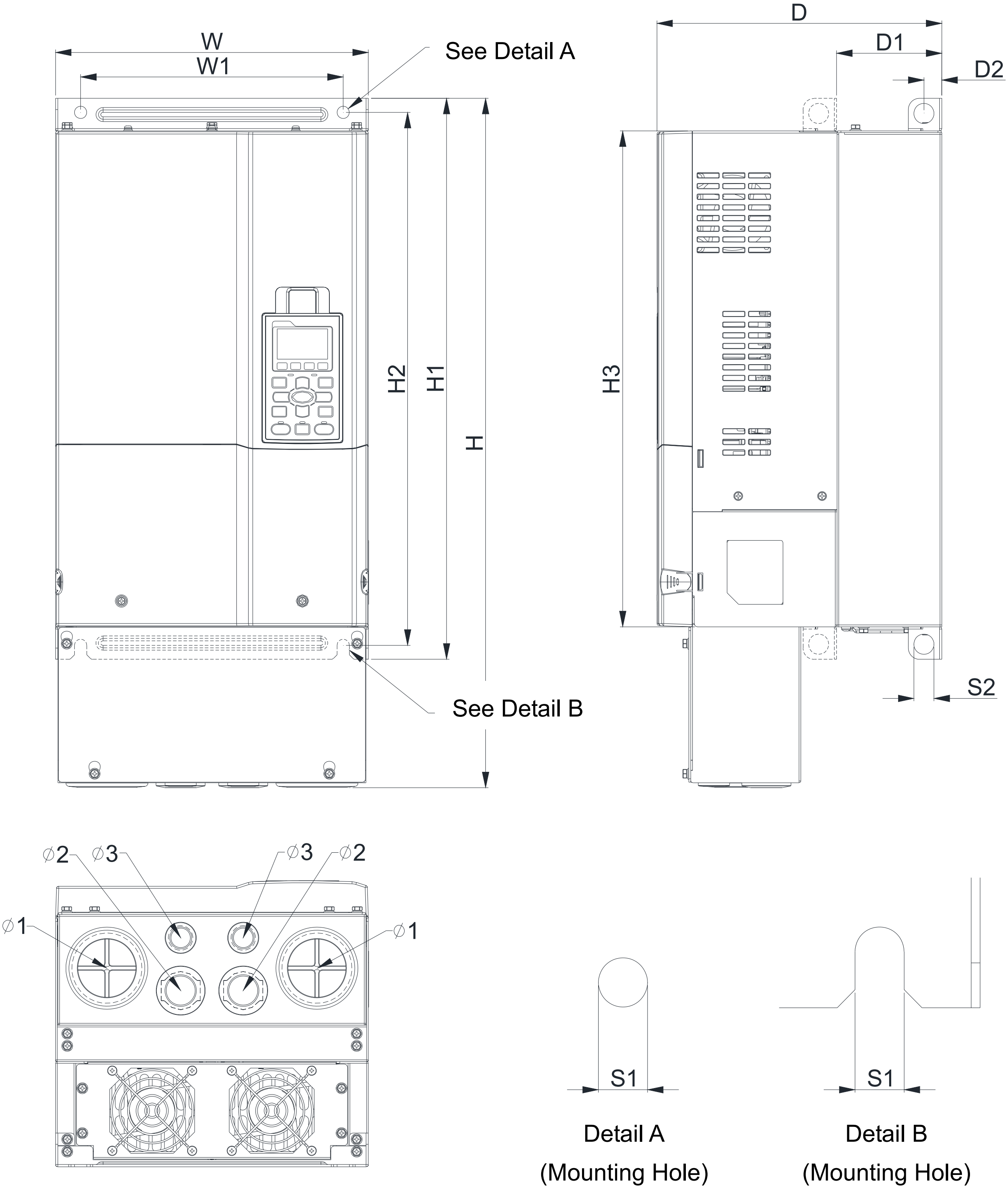
Unit: mm [inch]

Frame	W	H1	D	W1	H2	H3	D1*	D2	S1	S2
D0-1	280.0 [11.02]	500.0 [19.69]	255.0 [10.04]	235.0 [9.25]	475.0 [18.70]	442.0 [17.40]	94.2 [3.71]	16.0 [0.63]	11.0 [0.43]	18.0 [0.71]

D1*: Flange mounting

Frame D

D0-2: VFD450CP43S-21; VFD550CP43S-21



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-18

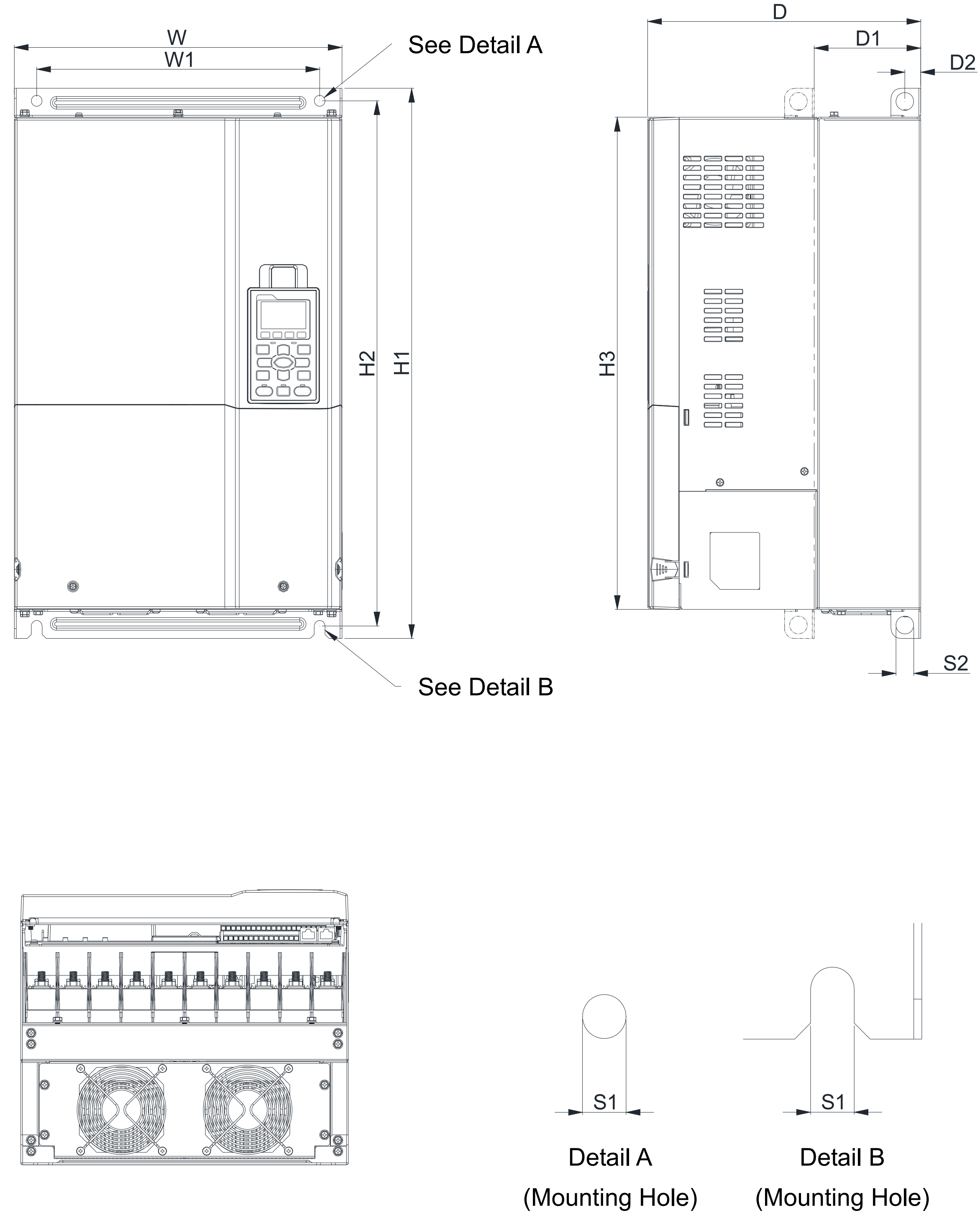
Unit: mm [inch]

Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1	S2	Φ1	Φ2	Φ3
D0-2	280.0 [11.02]	614.4 [24.19]	255.0 [10.04]	235.0 [9.25]	500.0 [19.69]	475.0 [18.70]	442.0 [17.40]	94.2 [3.71]	16.0 [0.63]	11.0 [0.43]	18.0 [0.71]	62.7 [2.47]	34.0 [1.34]	22.0 [0.87]

D1*: Flange mounting

Frame D

D1: VFD370CP23A-00; VFD450CP23A-00; VFD750CP43B-00; VFD900CP43A-00; VFD450CP63A-00; VFD550CP63A-00



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-19

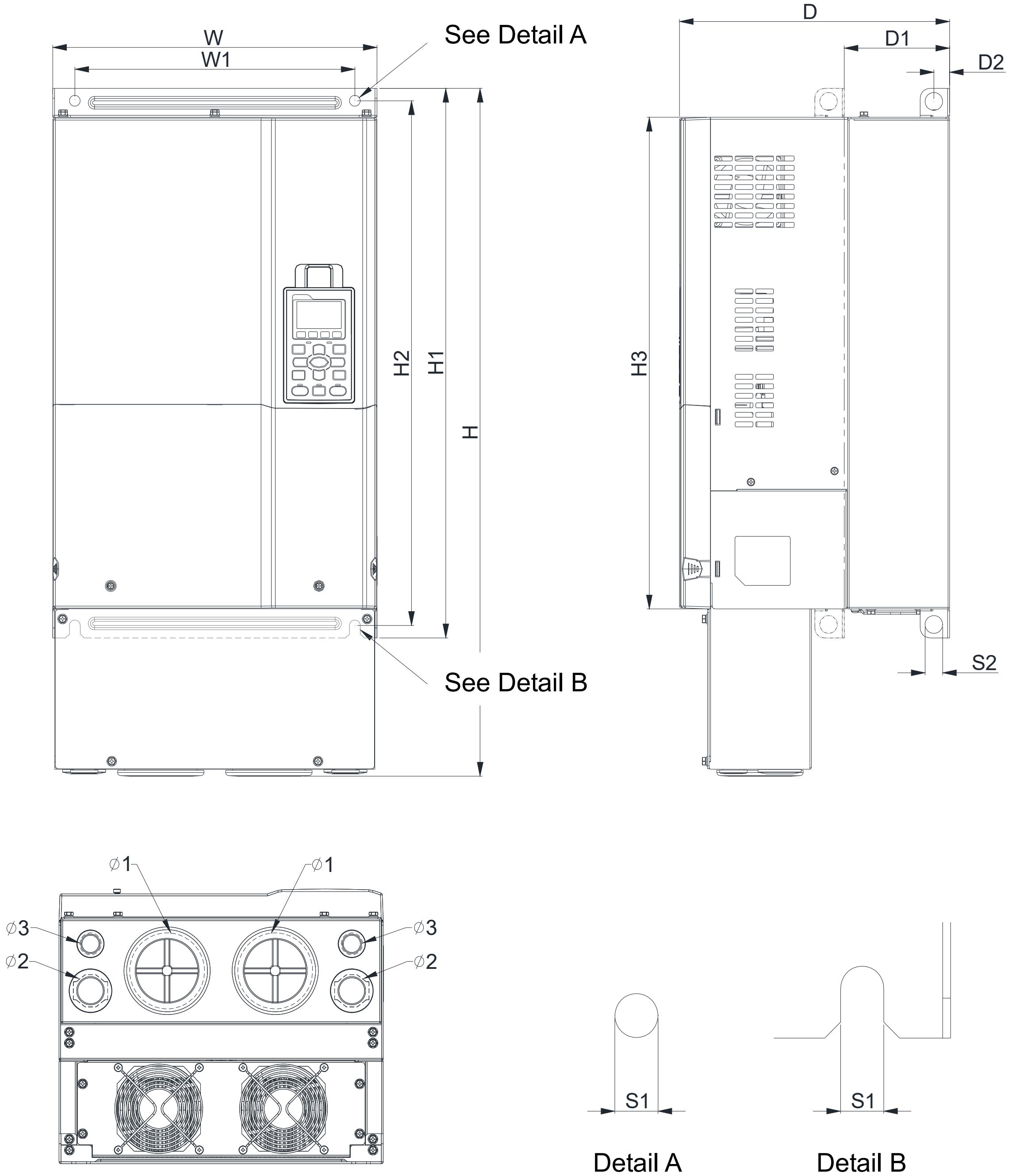
Unit: mm [inch]

Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1	S2	Φ1	Φ2	Φ3
D1	330.0 [12.99]	-	275.0 [10.83]	285.0 [11.22]	550.0 [21.65]	525.0 [20.67]	492.0 [19.37]	107.2 [4.22]	16.0 [0.63]	11.0 [0.43]	18.0 [0.71]	-	-	-

D1*: Flange mounting

Frame D

D2: VFD370CP23A-21; VFD450CP23A-21; VFD750CP43B-21; VFD900CP43A-21; VFD450CP63A-21; VFD550CP63A-21



Detail A (Mounting Hole)

Detail B (Mounting Hole)

Figure 1-20

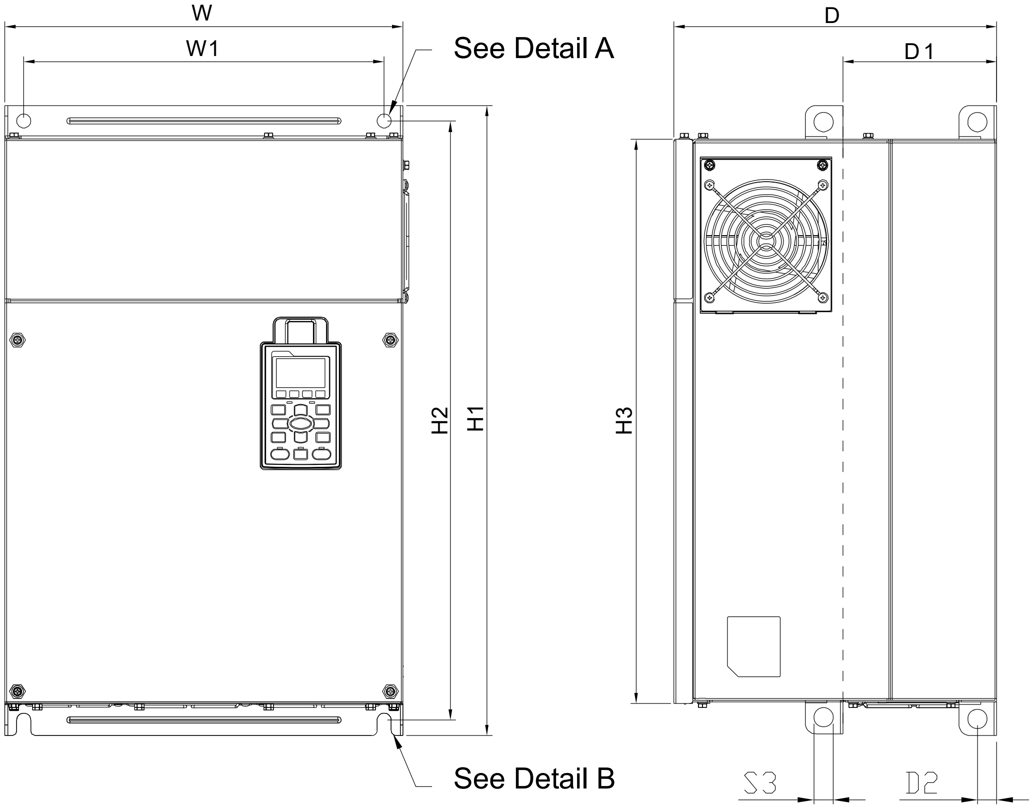
Unit: mm [inch]

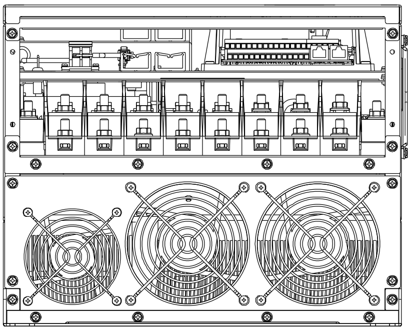
Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1	S2	Φ1	Φ2	Φ3
D2	330.0 [12.99]	688.3 [27.10]	275.0 [10.83]	285.0 [11.22]	550.0 [21.65]	525.0 [20.67]	492.0 [19.37]	107.2 [4.22]	16.0 [0.63]	11.0 [0.43]	18.0 [0.71]	76.2 [3.00]	34.0 [1.34]	22.0 [0.87]

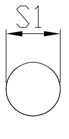
D1*: Flange mounting

Frame E

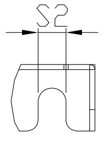
E1: VFD550CP23A-00; VFD750CP23A-00; VFD900CP23A-00; VFD1100CP43A-00; VFD1320CP43B-00;
VFD750CP63A-00; VFD900CP63A-00; VFD1100CP63A-00; VFD1320CP63A-00







Detail A
(Mounting Hole)



Detail B
(Mounting Hole)

Figure 1-21

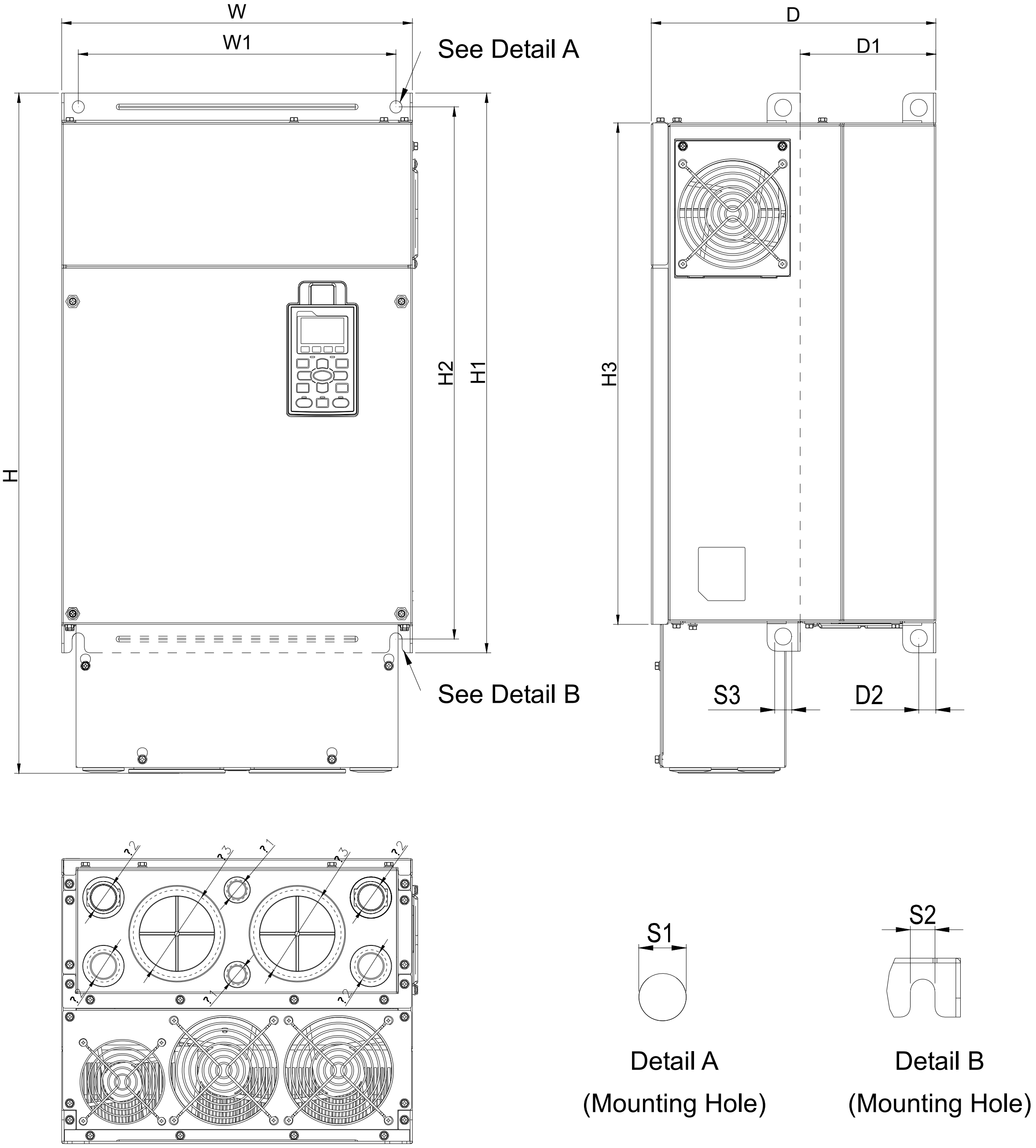
Unit: mm [inch]

Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1/S2	S3	Φ1	Φ2	Φ3
E1	370.0 [14.57]	-	300.0 [11.81]	335.0 [13.19]	589.0 [23.19]	560.0 [22.05]	528.0 [20.80]	143.0 [5.63]	18.0 [0.71]	13.0 [0.51]	18.0 [0.71]	-	-	-

D1*: Flange mounting

Frame E

E2: VFD550CP23A-21; VFD750CP23A-21; VFD900CP23A-21; VFD1100CP43A-21; VFD1320CP43B-21;
VFD750CP63A-21; VFD900CP63A-21; VFD1100CP63A-21; VFD1320CP63A-21



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-22

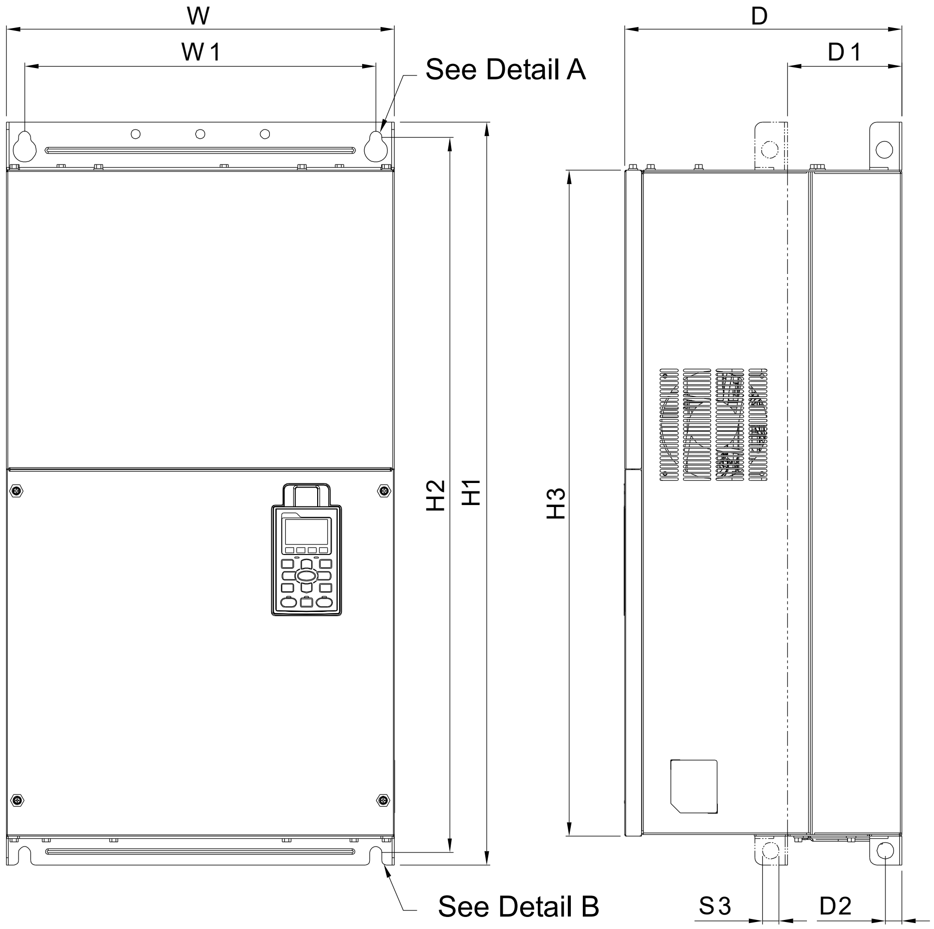
Unit: mm [inch]

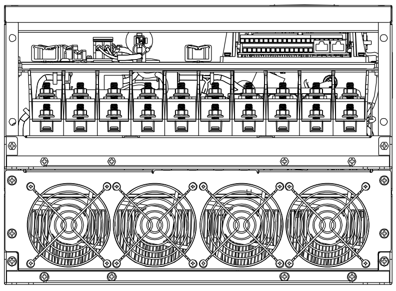
Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1, S2	S3	Φ1	Φ2	Φ3
E2	370.0 [14.57]	715.8 [28.18]	300.0 [11.81]	335.0 [13.19	589.0 [23.19]	560.0 [22.05]	528.0 [20.80]	143.0 [5.63]	18.0 [0.71]	13.0 [0.51]	18.0 [0.71]	22.0 [0.87]	34.0 [1.34]	92.0 [3.62]

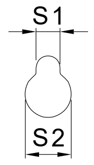
D1*: Flange mounting

Frame F

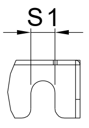
F1: VFD1600CP43A-00; VFD1850CP43B-00; VFD1600CP63A-00; VFD2000CP63A-00







Detail A (Mounting Hole)



Detail B (Mounting Hole)

Figure 1-23

Unit: mm [inch]

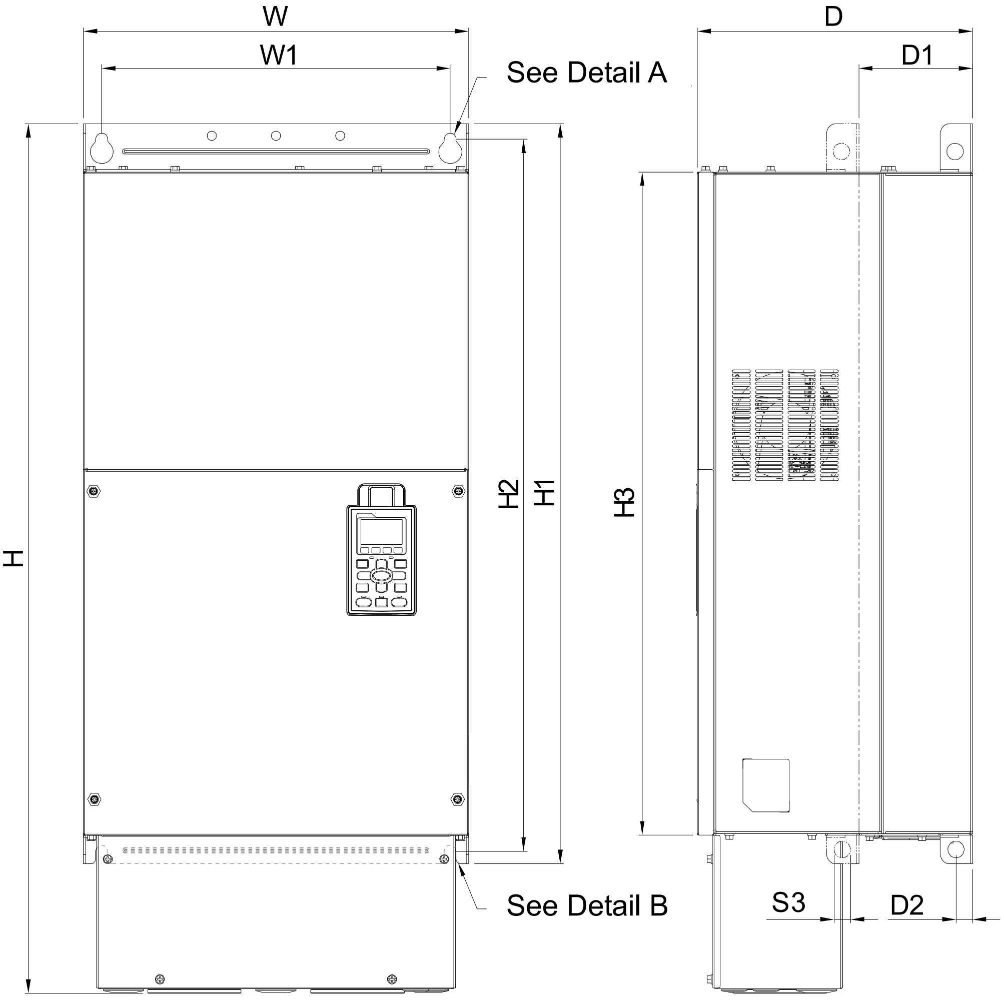
Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1	S2	S3
F1	420.0 [16.54]	-	300.0 [11.81]	380.0 [14.96]	800.0 [31.50]	770.0 [30.32]	717.0 [28.23]	124.0 [4.88]	18.0 [0.71]	13.0 [0.51]	25.0 [0.98]	18.0 [0.71]

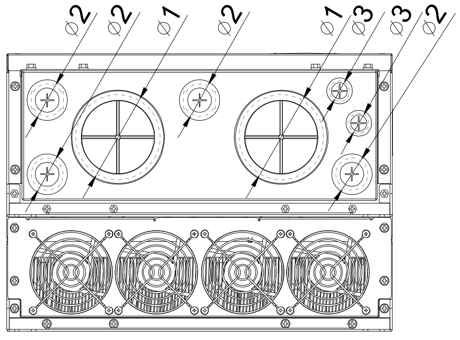
Frame	Φ1	Φ2	Φ3
F1	-	-	-

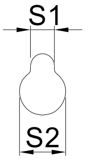
D1*: Flange mounting

Frame F

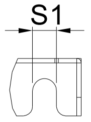
F2: VFD1600CP43A-21; VFD1850CP43B-21; VFD1600CP63A-21; VFD2000CP63A-21







Detail A (Mounting Hole)



Detail B (Mounting Hole)

Unit: mm [inch]

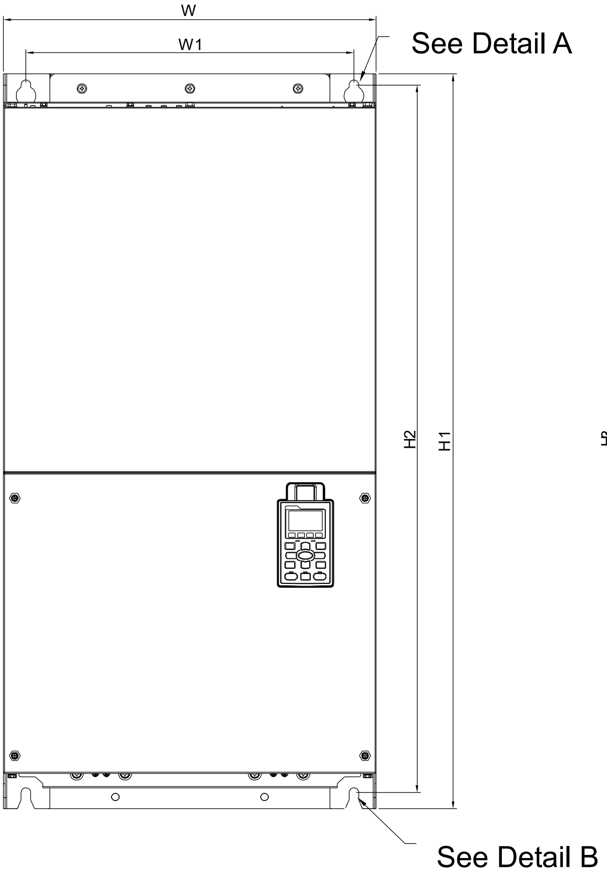
Frame	W	H	D	W1	H1	H2	H3	D1*	D2	S1	S2	S3
F2	420.0 [16.54]	940.0 [37.00]	300.0 [11.81]	380.0 [14.96]	800.0 [31.50]	770.0 [30.32]	717.0 [28.23]	124.0 [4.88]	18.0 [0.71]	13.0 [0.51]	25.0 [0.98]	18.0 [0.71]

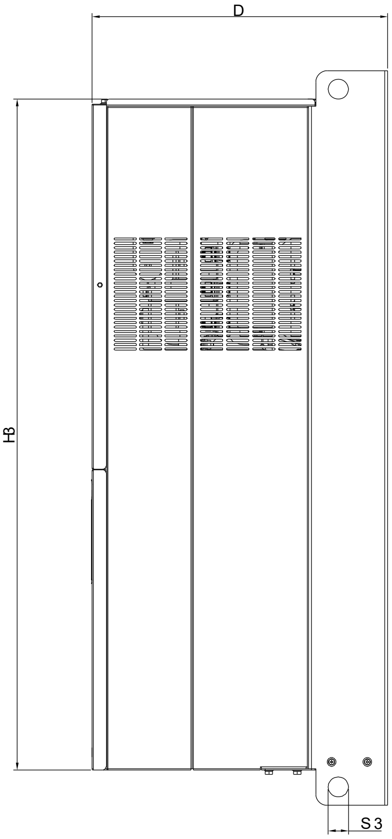
Frame	Φ1	Φ2	Φ3
F2	92.0 [3.62]	35.0 [1.38]	22.0 [0.87]

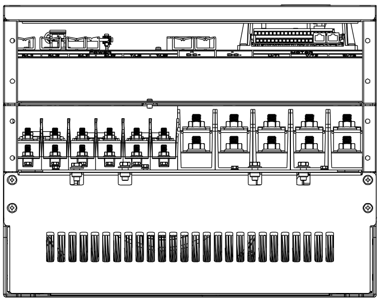
D1*: Flange mounting

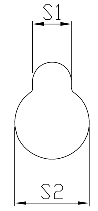
Frame G

G1: VFD2000CP43A-00; VFD2200CP43A-00; VFD2500CP43A-00; VFD2800CP43A-00;
VFD2500CP63A-00; VFD3150CP63A-00

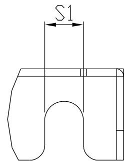








Detail A
(Mounting Hole)



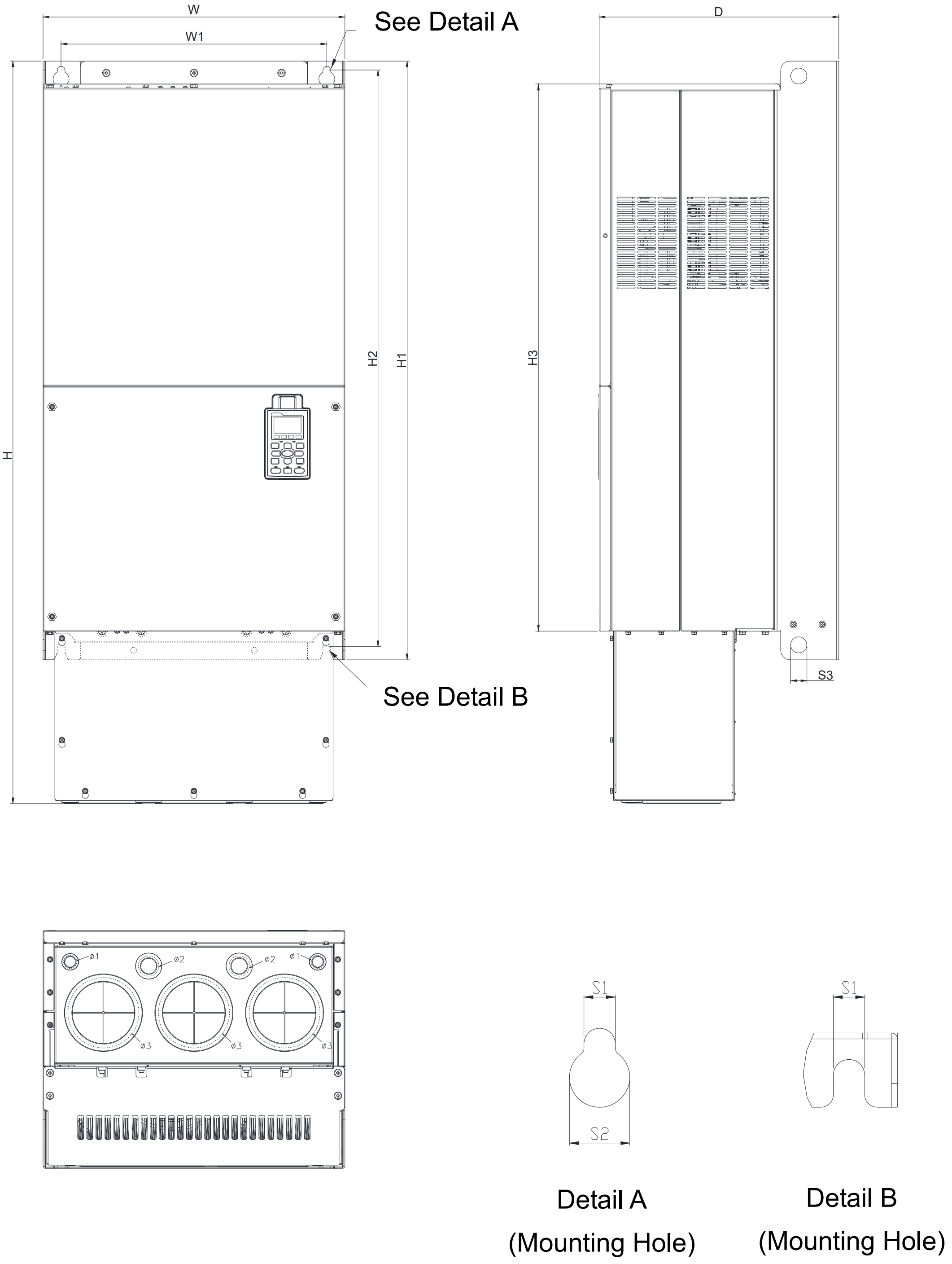
Detail B
(Mounting Hole)

Unit: mm [inch]

Frame	W	H	D	W1	H1	H2	H3	S1	S2	S3	Φ1	Φ2	Φ3
G1	500.0 [19.69]	-	397.0 [15.63]	440.0 [217.32]	1000.0 [39.37]	963.0 [37.91]	913.6 [35.97]	13.0 [0.51]	26.5 [1.04]	27.0 [1.06]	-	-	-

Frame G

G2: VFD2000CP43A-21; VFD2200CP43A-21; VFD2500CP43A-21; VFD2800CP43A-21;
VFD2500CP63A-21; VFD3150CP63A-21



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

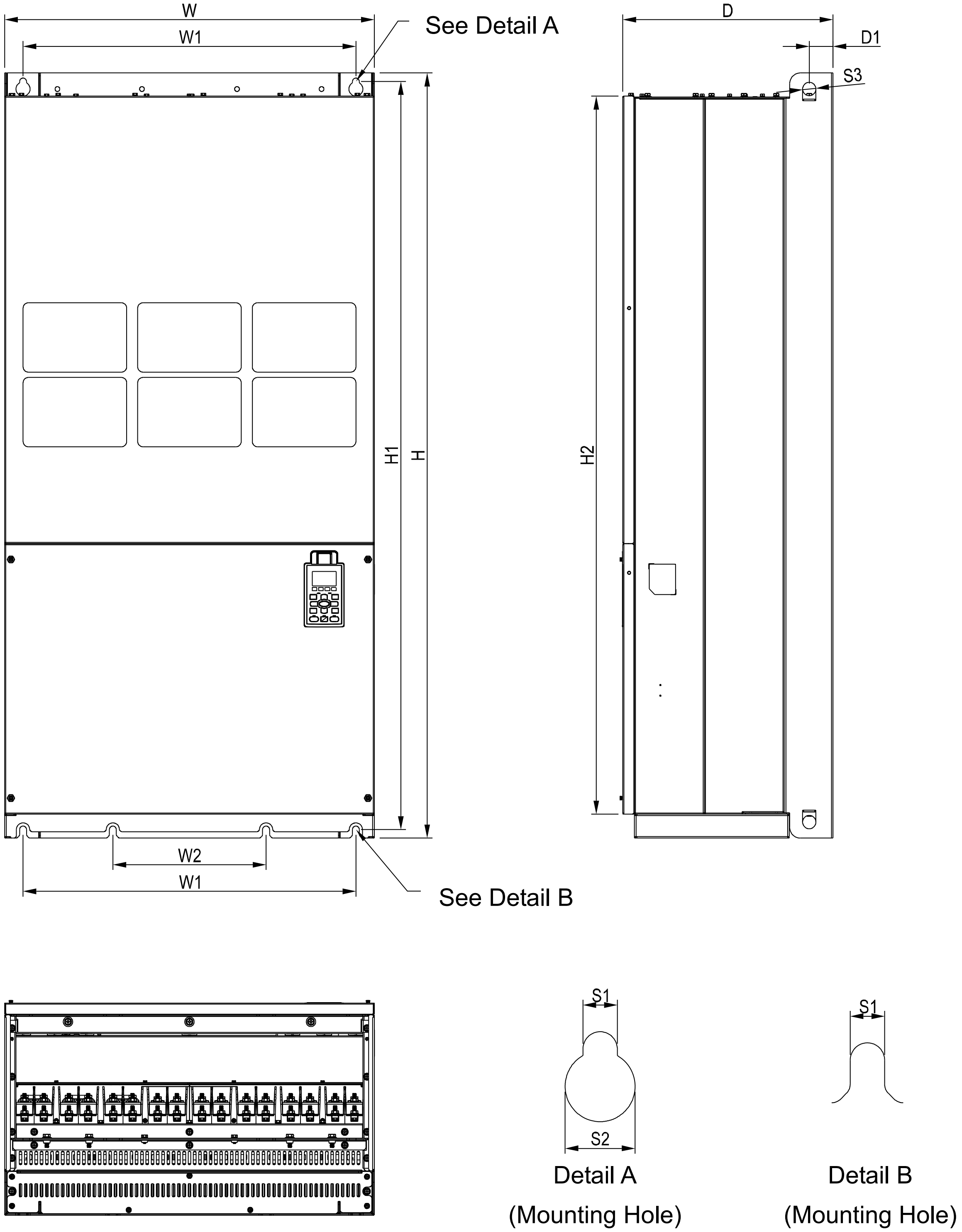
Figure 1-26

Unit: mm [inch]

Frame	W	H	D	W1	H1	H2	H3	S1	S2	S3	Φ1	Φ2	Φ3
G2	500.0 [19.69]	1240.2 [48.83]	397.0 [15.63]	440.0 [217.32]	1000.0 [39.37]	963.0 [37.91]	913.6 [35.97]	13.0 [0.51]	26.5 [1.04]	27.0 [1.06]	22.0 [0.87]	34.0 [1.34]	117.5 [4.63]

Frame H

H1: VFD3150CP43A-00; VFD3550CP43A-00; VFD4000CP43A-00; VFD5000CP43A-00;
VFD5600CP43A-00; VFD6300CP43A-00



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-27

Unit: mm [inch]

Frame	W	H	D	W1	W2	W3	W4	W5	W6	H1	H2	H3	H4
H1	700.0 [27.56]	1435.0 [56.5]	398.0 [15.67]	630.0 [24.8]	290.0 [11.42]	-	-	-	-	1403.0 [55.24]	1346.6 [53.02]	-	-
Frame	H5	D1	D2	D3	D4	D5	D6	S1	S2	S3	Φ1	Φ2	Φ3
H1	-	45.0 [1.77]	-	-	-	-	-	13.0 [0.51]	26.5 [1.04]	25.0 [0.98]	-	-	-

Frame H

H2: VFD3150CP43C-00; VFD3550CP43C-00; VFD4000CP43C-00; VFD5000CP43C-00

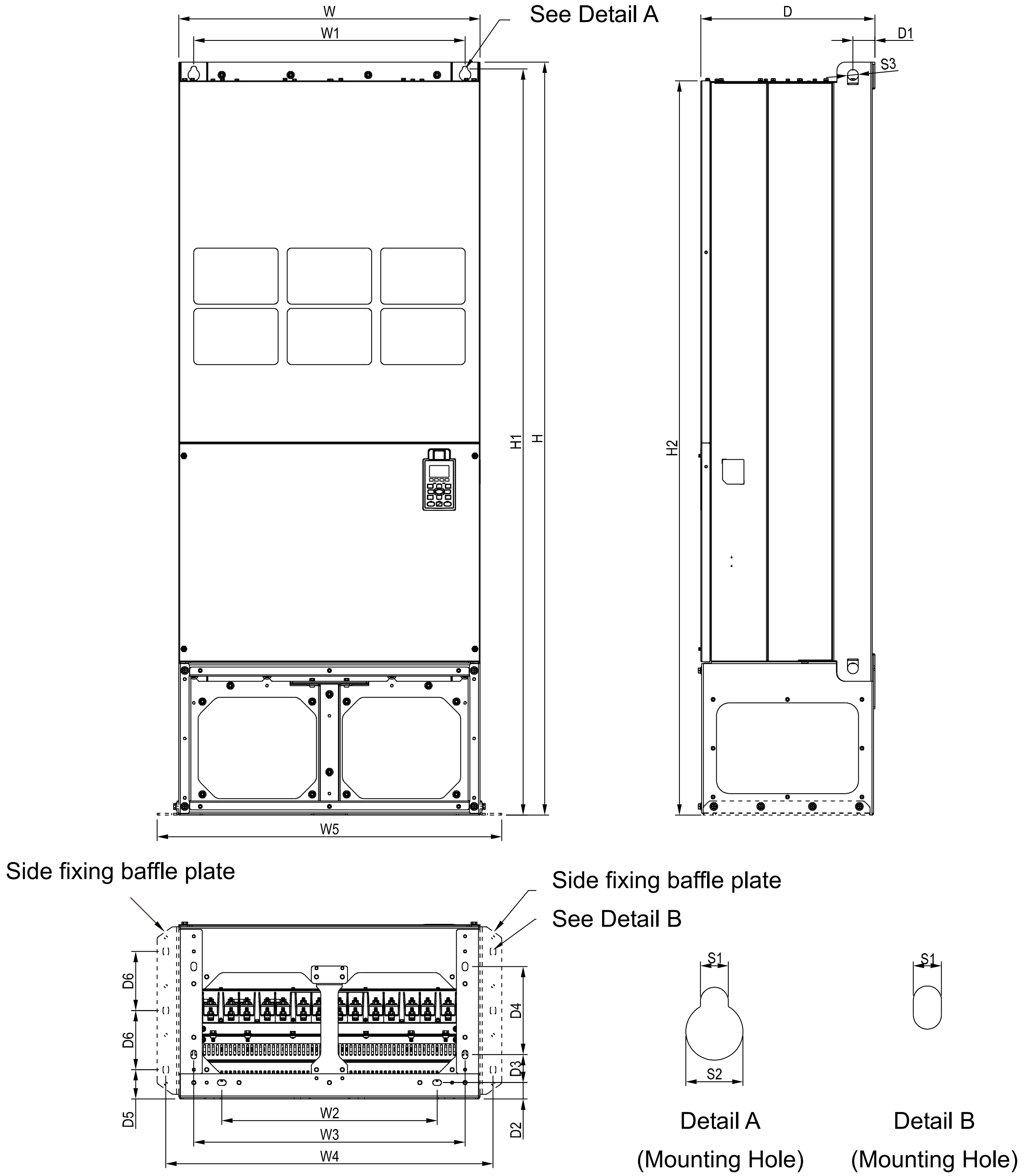


Figure 1-28

Unit: mm [inch]

Frame	W	H	D	W1	W2	W3	W4	W5	W6	H1	H2	H3	H4
H2	700.0 [27.56]	1745.0 [68.70]	404.0 [15.90]	630.0 [24.8]	500.0 [19.69]-	630.0 [24.80]	760.0 [29.92]	800.0 [31.5]	-	1729.0 [68.07]	1701.6 [66.99]	-	-
Frame	H5	D1	D2	D3	D4	D5	D6	S1	S2	S3	Φ1	Φ2	Φ3
H2	-	51.0 [2.00]	38.0 [1.50]	65.0 [2.56]	204.0 [8.03]	68.0 [2.68]	137.0 [5.40]	13.0 [0.51]	26.5 [1.04]	25.0 [0.98]	-	-	-

Frame H

H3: VFD3150CP43C-21; VFD3550CP43C-21; VFD4000CP43C-21; VFD5000CP43C-21; VFD5600CP43C-21; VFD6300CP43C-21

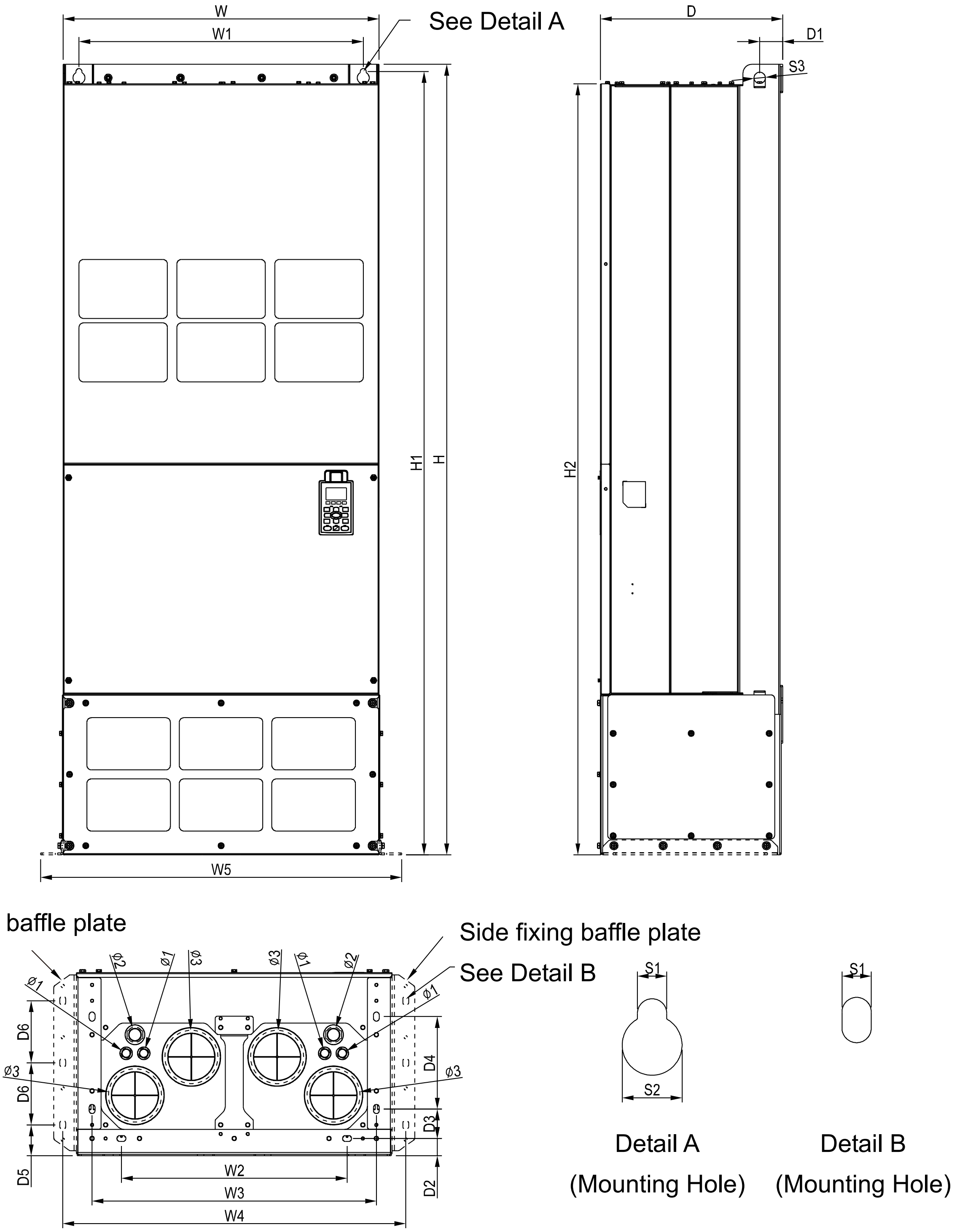


Figure 1-29

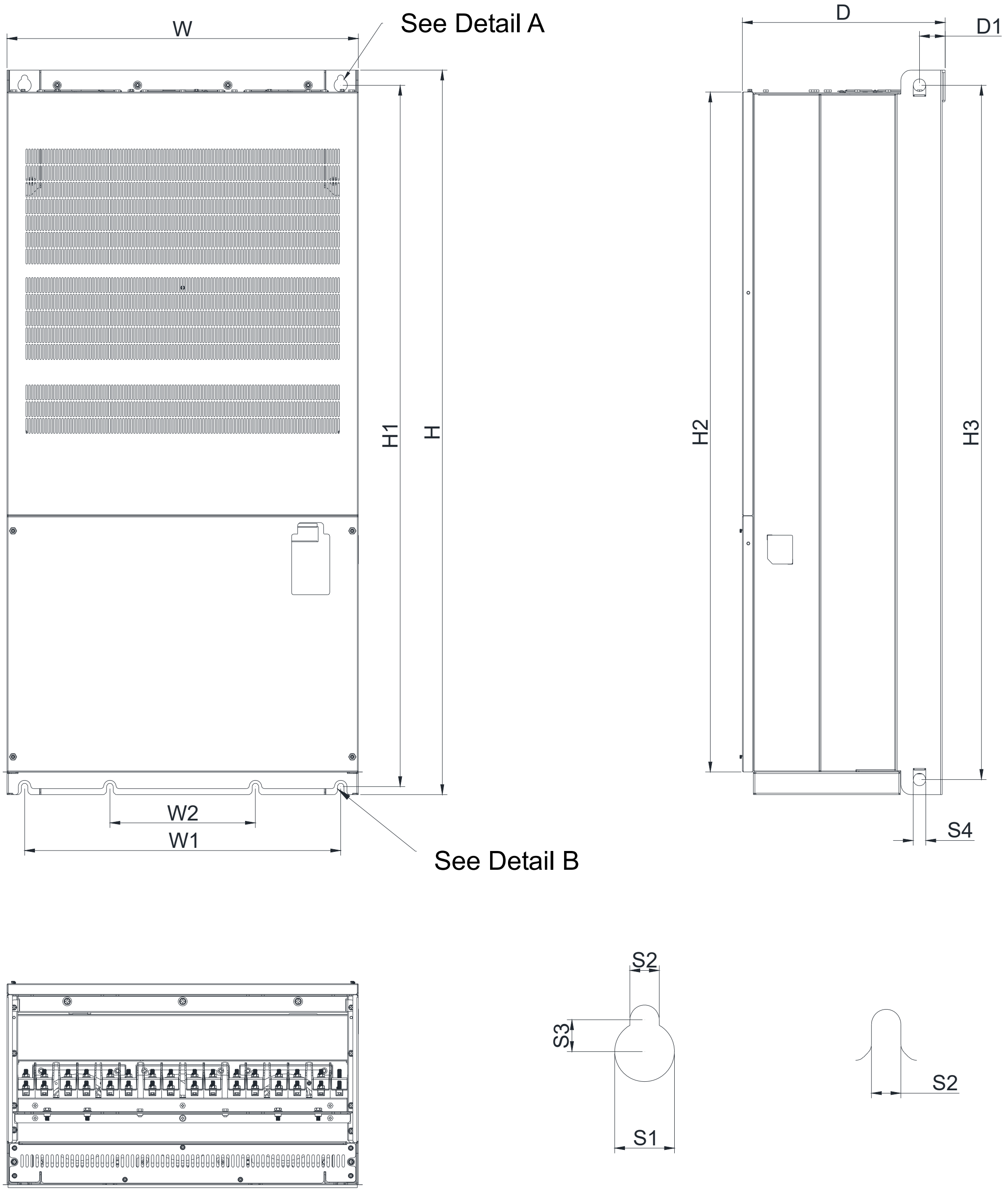
Unit：mm [inch]

Frame	W	H	D	W1	W2	W3	W4	W5	W6	H1	H2	H3	H4
H3	700.0 [27.56]	1745.0 [68.70]	404.0 [15.91]	630.0 [24.80]	500.0 [19.69]	630.0 [24.80]	760.0 [29.92]	800.0 [31.5]	-	1729.0 [68.07]	1701.6 [66.99]	-	-
Frame	H5	D1	D2	D3	D4	D5	D6	S1	S2	S3	Φ1	Φ2	Φ3
H3	-	51.0 [2.00]	38.0 [1.50]	65.0 [2.56]	204.0 [8.03]	68.0 [2.68]	137.0 [5.40]	13.0 [0.51]	26.5 [1.04]	25.0 [0.98]	22.0 [0.87]	34.0 [1.34]	117.5 [4.63]

690V

Frame H

H1: VFD4000CP63A-00; VFD4500CP63A-00; VFD5600CP63A-00; VFD6300CP63A-00



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-30

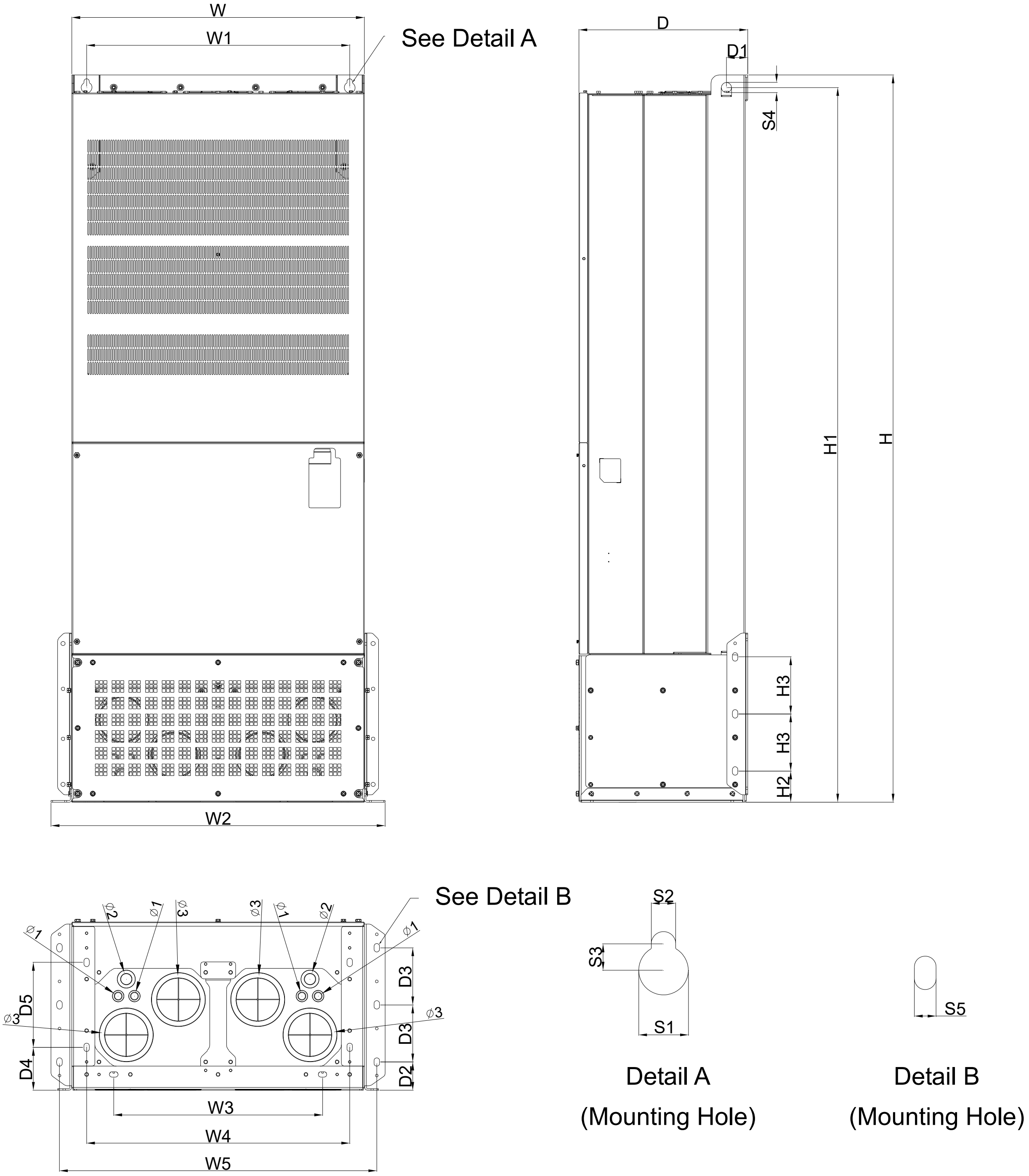
Unit: mm [inch]

Frame	W	W1	W2	H	H1	H2	H3	D	D1	S1	S2	S3	S4
H1	700.0 [27.56]	630.0 [24.80]	290.0 [11.42]	1435.0 [56.50]	1389.0 [54.68]	1346.6 [53.02]	1375.0 [54.13]	398.0 [15.67]	45.0 [1.77]	26.5 [1.04]	13.0 [0.51]	14.0 [0.55]	25.0 [0.98]

690V

Frame H

H2: VFD4000CP63A-21; VFD4500CP63A-21; VFD5600CP63A-21; VFD6300CP63A-21



Detail A
(Mounting Hole)

Detail B
(Mounting Hole)

Figure 1-31

Unit: mm [inch]

Frame	W	W1	W2	W3	W4	W5	H	H1	H2	H3	D	D1	D2
H2	700.0 [27.56]	630.0 [24.80]	800.0 [31.50]	500.0 [19.69]	630.0 [24.80]	760.0 [29.92]	1745.0 [68.70]	1715.0 [67.52]	74.5 [2.93]	137.0 [5.39]	404.0 [15.91]	51.0 [2.01]	68.0 [2.68]
Frame	D3	D4	D5	S1	S2	S3	S4	S5	Φ1	Φ2	Φ3		
H2	137.0 [5.39]	103.0 [4.06]	204.0 [8.03]	26.5 [1.04]	13.0 [0.51]	14.0 [0.55]	25.0 [0.98]	13.0 [0.51]	22.0 [0.87]	34.0 [1.34]	117.50 [4.63]		

Digital Keypad

KPC-CC01

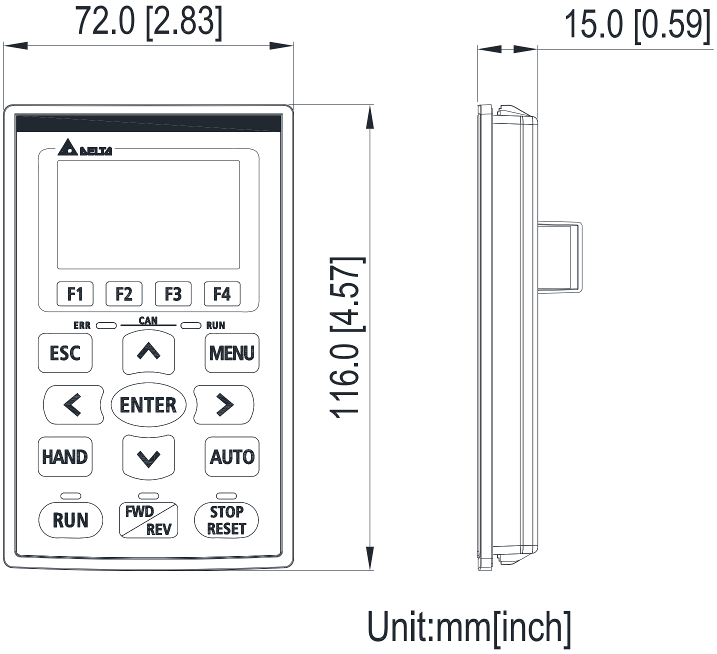


Figure 1-32

Chapter 2 Installation

2-1 Mounting Clearance

☑ Prevent fiber particles, scraps of paper, shredded wood, sawdust, metal particles, etc. from adhering to the heat sink.

☑ Install the AC motor drive in a metal cabinet. When installing one drive below another one, use a metal separator between the AC motor drives to prevent mutual heating and to prevent the risk of fire accident.

☑ Install the AC motor drive in Pollution Degree 2 environments only:
Normally only nonconductive pollution occurs and temporary conductivity caused by condensation is expected.

The appearances shown in the following figures are for reference only. The actual motor drives may look different.

Airflow direction: ⇠ (Blue arrow) Inflow ← (Red arrow) Outflow ↔ (Black) Distance

Single drive installation (Frame A–H)

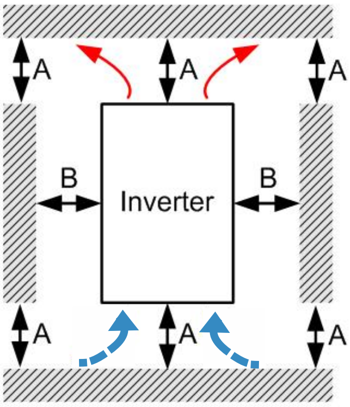


Figure 2-1

Side-by-side horizontal installation (Frame A–C)

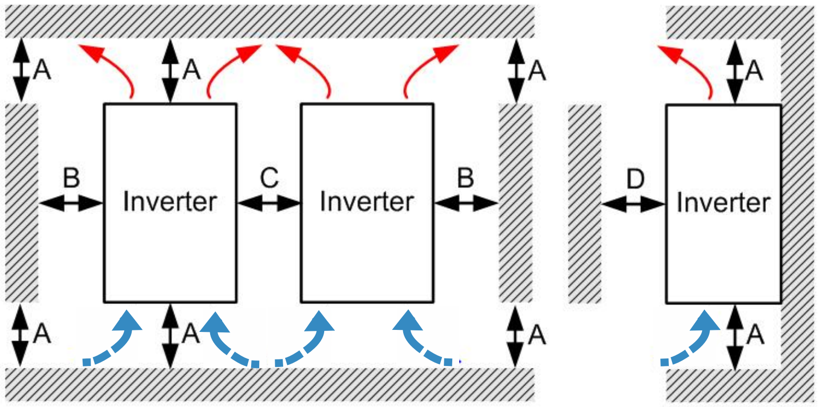


Figure 2-2

Multiple drives, single side-by-side horizontal installation (Frame G, H)

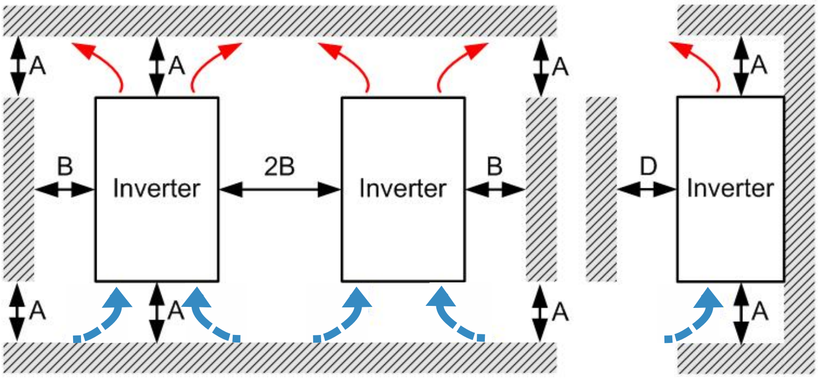


Figure 2-3

Multiple drives, side-by-side installation (Frame D0, D, E, F)

Install metal separator between the drives.

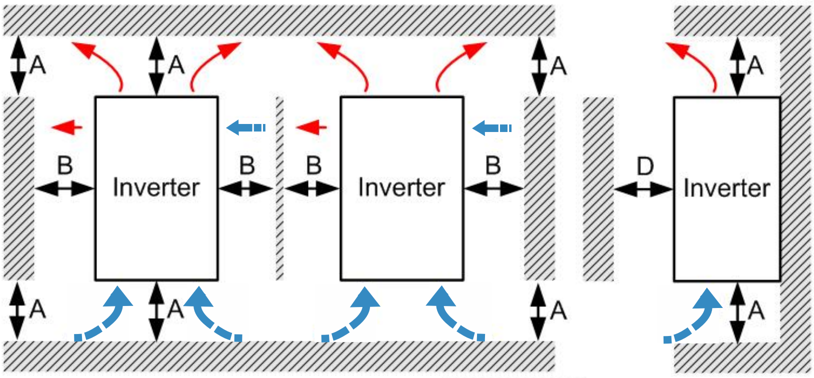


Figure 2-4

Multiple drives side-by-side vertical installation

Ta: Frame A–G Ta*: Frame H

When installing one AC motor drive below another one (top-bottom installation), use a metal separator between the drives to prevent mutual heating. The temperature measured at the fan's inflow side must be lower than the temperature measured at the operation side. If the fan's inflow temperature is higher, use a thicker or larger size of metal separator. Operation temperature is the temperature measured at 50 mm away from the fan's inflow side (as shown in the figure below).

(Frame A–C)

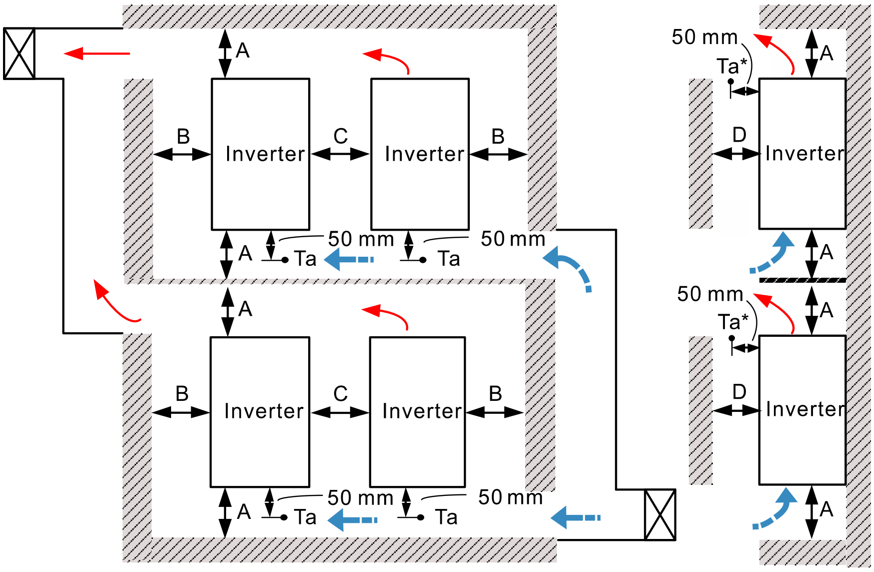


Figure 2-5

(Frame D0–G)

Install metal separator between the drives.

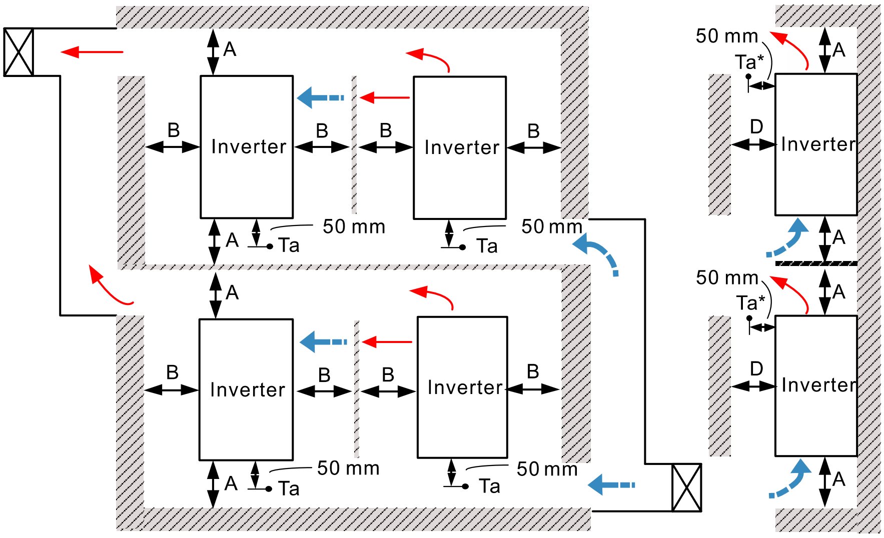


Figure 2-6

Minimum mounting clearance

Frame	A [mm]	B [mm]	C [mm]	D [mm]
A–C	60	30	10	0
D0–F	100	50	-	0
G	200	100	-	0
H	350	0	0	200 (Ta = Ta* = 50°C)
H	350	0	0	100 (Ta = Ta* = 40°C)

Table 2-1

NOTE

The minimum mounting clearances A–D stated in the table above apply to AC motor drives installation. Failing to follow the minimum mounting clearances may cause the fan to malfunction and heat dissipation problems.

Frame A	VFD007CP23A-21; VFD007CP43A/4EA-21; VFD015CP23A-21; VFD015CP43B/4EB-21; VFD022CP23A-21; VFD022CP43B/4EB-21; VFD037CP23A-21; VFD037CP43B/4EB-21; VFD040CP43A/4EA-21; VFD055CP23A-21; VFD055CP43B/4EB-21; VFD075CP43B/4EB-21; VFD015CP53A-21; VFD022CP53A-21; VFD037CP53A-21
Frame B	VFD075CP23A-21; VFD110CP23A-21; VFD110CP43B/4EB -21; VFD150CP23A-21; VFD150CP43B/4EB-21; VFD185CP43B/4EB-21; VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21; VFD150CP53A-21
Frame C	VFD185CP23A-21; VFD220CP23A-21; VFD220CP43A/4EA -21; VFD300CP23A-21; VFD300CP43B/4EB-21; VFD370CP43B/4EB-21; VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21
Frame D0	VFD450CP43S-00; VFD550CP43S-00; VFD450CP43S-21; VFD550CP43S-21
Frame D	VFD370CP23A-00/23A-21; VFD450CP23A-00/23A-21; VFD750CP43B-00/43B-21; VFD900CP43A-00/43A-21; VFD450CP63A-00/63A-21; VFD550CP63A-00/63A-21
Frame E	VFD550CP23A-00/23A-21; VFD750CP23A-00/23A-21; VFD900CP23A-00/23A-21; VFD1100CP43A-00/43A-21; VFD1320CP43B-00/43B-21; VFD750CP63A-00/63A-21; VFD900CP63A-00/63A-21; VFD1100CP63A-00/63A-21; VFD1320CP63A-00/63A-21
Frame F	VFD1600CP43A-00/43A-21; VFD1850CP43B-00/43B-21; VFD1600CP63A-00/63A-21; VFD2000CP63A-00/63A-21
Frame G	VFD2000CP43A-00/43A-21; VFD2200CP43A-00/43A-21; VFD2500CP43A-00/43A-21; VFD2800CP43A-00/43A-21; VFD2500CP63A-00/63A-21; VFD3150CP63A-00/63A-21
Frame H	VFD3150CP43A-00/43C-00/43C-21; VFD3550CP43A-00/43C-00/43C-21; VFD4000CP43A-00/43C-00/43C-21; VFD5000CP43A-00/43C-00/43C-21; VFD5600CP43A-00/43C-21; VFD6300CP43A-00/43C-21; VFD4000CP63A-00/63A-21; VFD4500CP63A-00/63A-21; VFD5600CP63A-00/63A-21; VFD6300CP63A-00/63A-21

Table 2-2

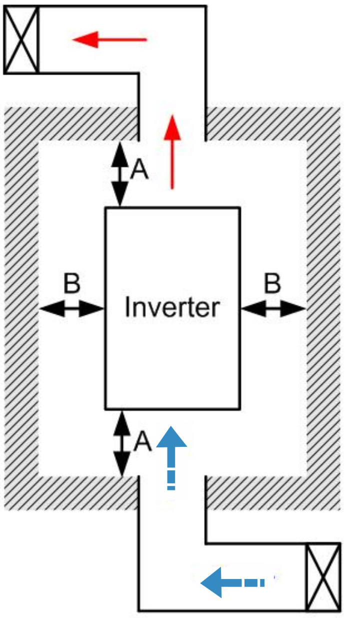


Figure 2-7

NOTE

※ The mounting clearance stated in the figure is for installing the drive in an open area. To install the drive in a confined space (such as cabinet or electric box), follow the following rules: (1) Keep the minimum mounting clearances. (2) Install a ventilation equipment or an air conditioner to keep surrounding temperature lower than operation temperature. (3) Refer to parameter setting and set up Pr.00-16, Pr.00-17, and Pr.06-55.

※ The table below shows the heat dissipation and the required air volume when installing a single drive in a confined space. When installing multiple drives, the required air volume shall be multiplied by the number of the drives.

※ Refer to the table below (Airflow Rate for Cooling) for ventilation equipment design and selection.

※ Refer to the table below (Power Dissipation for AC Motor Drive) for air conditioner design and selection.

※ Different control mode affects the derating. See Pr.06-55 for more information.

※ Ambient temperature derating curve shows the derating status in different temperature in relation to different protection level.

※ Refer to Section 9-7 for ambient temperature derating curve and derating curves under different control modes.

※ If UL Type 1 models need side-by-side installation, remove the top cover for Frame A–C. Do NOT install the conduit box for Frame D and above.

2-2 Airflow and Power Dissipation

Model No.	Airflow Rate for Cooling						Power Dissipation for AC Motor Drive		
	Flow Rate (Unit: cfm)			Flow Rate (Unit: m^3/hr)			Power Dissipation (Unit: watt)		
	External	Internal	Total	External	Internal	Total	Loss External (Heat Sink)	Internal	Total
VFD007CP23A-21	-	-	-	-	-	-	40	31	71
VFD015CP23A-21	-	-	-	-	-	-	61	39	100
VFD022CP23A-21	14	-	14	24	-	24	81	45	126
VFD037CP23A-21	14	-	14	24	-	24	127	57	184
VFD055CP23A-21	10	-	10	17	-	17	158	93	251
VFD075CP23A-21	40	14	54	68	24	92	291	101	392
VFD110CP23A-21	66	14	80	112	24	136	403	162	565
VFD150CP23A-21	58	14	73	99	24	124	570	157	727
VFD185CP23A-21	166	12	178	282	20	302	622	218	840
VFD220CP23A-21	166	12	178	282	20	302	777	197	974
VFD300CP23A-21	146	12	158	248	20	268	878	222	1100
VFD370CP23A-00/ VFD370CP23A-21	179	30	209	304	51	355	1271	311	1582
VFD450CP23A-00/ VFD450CP23A-21	179	30	209	304	51	355	1550	335	1885
VFD550CP23A-00/ VFD550CP23A-21	228	73	301	387	124	511	1762	489	2251
VFD750CP23A-00/ VFD750CP23A-21	228	73	301	387	124	511	2020	574	2594
VFD900CP23A-00/ VFD900CP23A-21	246	73	319	418	124	542	2442	584	3026
VFD007CP43A/ VFD007CP4EA-21	-	-	-	-	-	-	35	32	67
VFD015CP43B/ VFD015CP4EB-21	-	-	-	-	-	-	48	39	87
VFD022CP43B/ VFD022CP4EB-21	-	-	-	-	-	-	64	52	116
VFD037CP43B/ VFD037CP4EB-21	14	-	14	24	-	24	103	77	180
VFD040CP43A/ VFD040CP4EA-21	10	-	10	17	-	17	124	81	205
VFD055CP43B/ VFD055CP4EB-21	10	-	10	17	-	17	142	116	258
VFD075CP43B/ VFD075CP4EB-21	10	-	10	17	-	17	205	129	334
VFD110CP43B/ VFD110CP4EB-21	40	14	54	68	24	92	291	175	466
VFD150CP43B/ VFD150CP4EB-21	66	14	80	112	24	136	376	190	566
VFD185CP43B/ VFD185CP4EB-21	58	14	73	99	24	124	396	210	606
VFD220CP43A/ VFD220CP4EA-21	99	21	120	168	36	204	455	358	813
VFD300CP43B/ VFD300CP4EB-21	99	21	120	168	36	204	586	410	996
VFD370CP43B/ VFD370CP4EB-21	126	21	147	214	36	250	778	422	1200
VFD450CP43S-00/ VFD450CP43S-21	179	30	209	304	51	355	1056	459	1515
VFD550CP43S-00/ VFD550CP43S-21	179	30	209	304	51	355	1163	669	1832
VFD750CP43B-00/ VFD750CP43B-21	179	30	209	304	51	355	1407	712	2119
VFD900CP43A-00/ VFD900CP43A-21	186	30	216	316	51	367	1787	955	2742
VFD1100CP43A-00/ VFD1100CP43A-21	257	73	330	437	124	561	2112	1084	3196
VFD1320CP43B-00/ VFD1320CP43B-21	223	73	296	379	124	503	2597	1220	3817

Model No.	Airflow Rate for Cooling						Power Dissipation for AC Motor Drive		
	Flow Rate (Unit: cfm)			Flow Rate (Unit: m^3/hr)			Power Dissipation (Unit: watt)		
	External	Internal	Total	External	Internal	Total	Loss External (Heat Sink)	Internal	Total
VFD1600CP43A-00/ VFD1600CP43A-21	224	112	336	381	190	571	3269	1235	4504
VFD1850CP43B-00/ VFD1850CP43B-21	289	112	401	491	190	681	3814	1570	5384
VFD2000CP43A-00/ VFD2000CP43A-21			454			771			5741
VFD2200CP43A-00/ VFD2200CP43A-21			454			771			6358
VFD2500CP43A-00/ VFD2500CP43A-21			454			771			6662
VFD2800CP43A-00/ VFD2800CP43A-21			454			771			7325
VFD3150CP43A-00/ VFD3150CP43C-00/ VFD3150CP43C-21			769			1307			8513
VFD3550CP43A-00/ VFD3550CP43C-00/ VFD3550CP43C-21			769			1307			9440
VFD4000CP43A-00/ VFD4000CP43C-00/ VFD4000CP43C-21			769			1307			10642
VFD5000CP43A-00/ VFD5000CP43C-00/ VFD5000CP43C-21			769			1307			13364
VFD5600CP43A-00/ VFD5600CP43C-21			952.9			1618.9			14350
VFD6300CP43A-00/ VFD6300CP43C-21			952.9			1618.9			16150
VFD015CP53A-21	-	-	-	-	-	-	39.5	13.0	53
VFD022CP53A-21	-	-	-	-	-	-	55.0	22.0	77
VFD037CP53A-21	0.006	-	0.006	13.6	-	13.6	86.8	42.7	130
VFD055CP53A-21	0.019	0.007	0.026	40.0	14.5	54.5	124.6	67.9	193
VFD075CP53A-21	0.019	0.007	0.026	40.0	14.5	54.5	143.5	119.0	263
VFD110CP53A-21	0.019	0.007	0.026	40.0	14.5	54.5	222.2	162.8	385
VFD150CP53A-21	0.019	0.007	0.026	40.0	14.5	54.5	308.5	216.5	525
VFD185CP63A-21	90.0	21.3	111.4	153.0	36.2	189.2	317.5	145.0	462.5
VFD220CP63A-21	90.0	21.3	111.4	153.0	36.2	189.2	408.2	141.8	550.0
VFD300CP63A-21	90.0	21.3	111.4	153.0	36.2	189.2	492.7	257.3	750.0
VFD370CP63A-21	89.0	21.3	110.3	151.2	36.2	187.5	641.6	283.4	925.0
VFD450CP63A-00/21	175.9	36.4	212.3	298.8	61.8	360.6	718.2	406.8	1125.0
VFD550CP63A-00/21	175.9	36.4	212.3	298.8	61.8	360.6	890.1	484.9	1375.0
VFD750CP63A-00/21	264.6	90.6	355.2	449.6	153.9	603.5	1356.0	519.0	1875.0
VFD900CP63A-00/21	264.6	90.6	355.2	449.6	153.9	603.5	1652.8	597.2	2250.0
VFD1100CP63A-00/21	264.6	90.6	355.2	449.6	153.9	603.5	1960.3	789.7	2750.0
VFD1320CP63A-00/21	264.6	90.6	355.2	449.6	153.9	603.5	2230.8	1069.2	3300.0
VFD1600CP63A-00/21	248.1	135.3	383.4	421.6	229.9	651.4	2627.3	1372.7	4000.0
VFD2000CP63A-00/21	248.1	135.3	383.4	421.6	229.9	651.4	3415.0	1585.0	5000.0
VFD2500CP63A-00/21			409.7			696.0	4751.7	1498.3	6250.0
VFD3150CP63A-00/21			409.7			696.0	5695.4	2179.6	7875.0
VFD4000CP63A-00/21			563.0			956.4	6796.2	3203.8	10000.0
VFD4500CP63A-00/21			952.9			1618.9	7313.6	3936.4	11250.0
VFD5600CP63A-00/21			952.9			1618.9	9553.4	4446.6	14000.0
VFD6300CP63A-00/21			952.9			1618.9	11042.4	4707.6	15750.0

Model No.	Airflow Rate for Cooling						Power Dissipation for AC Motor Drive		
	Flow Rate (Unit: cfm)			Flow Rate (Unit: m^3/hr)			Power Dissipation (Unit: watt)		
	External	Internal	Total	External	Internal	Total	Loss External (Heat Sink)	Internal	Total
※ The required airflow shown in the table is for installing single drive in a confined space. ※ When installing multiple drives, the required air volume should be the required air volume for single drive × the number of the drives.							※ The heat dissipation shown in the table is for installing single drive in a confined space. ※ When installing multiple drives, volume of heat dissipation should be the heat dissipated for single drive × the number of the drives. ※ Heat dissipation for each model is calculated by rated voltage, current and default carrier.		

Table 2-3

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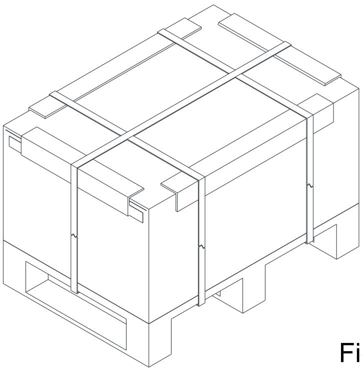
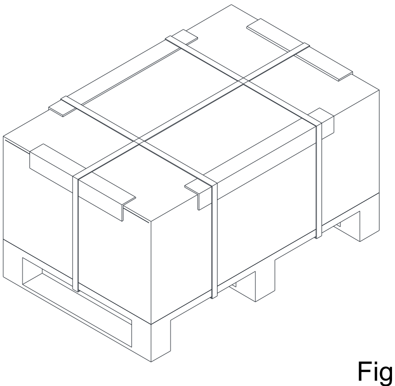
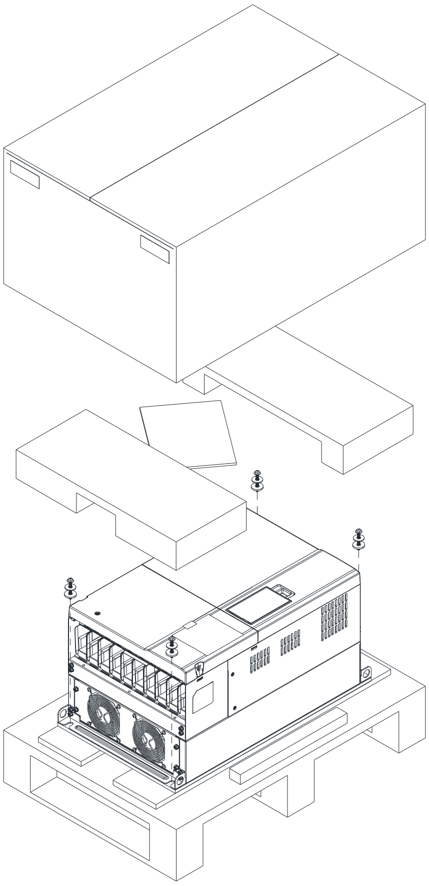
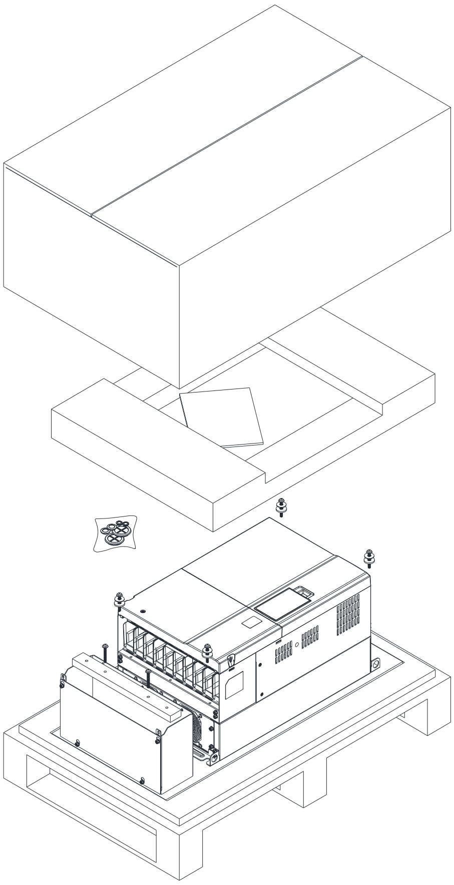
Chapter 3 Unpacking

The AC motor drive should be kept in the shipping carton or crate before installation. In order to retain the warranty coverage, the AC motor drive should be stored properly when it is not to be used for an extended period of time.

3-1 Unpacking

Follow these steps to unpack the AC motor drive:

Frame D (carton version)	
Unpacking 1 (VFDXXXCPXX-00)	Unpacking 2 (VFDXXXCPXXX-21)
Cut the three pieces of packaging strap off.  Figure 3-1	Cut the three pieces of packaging strap off.  Figure 3-4
Remove the top cover, take out the EPEs and the manual, and then loosen the four screws.  Figure 3-2	Remove the top cover, take out the EPEs, rubber and the manual, and then loosen the six screws.  Figure 3-5

<table>
<tr>
<td>Lift the drive by hooking the lifting hole. It is now ready for installation.

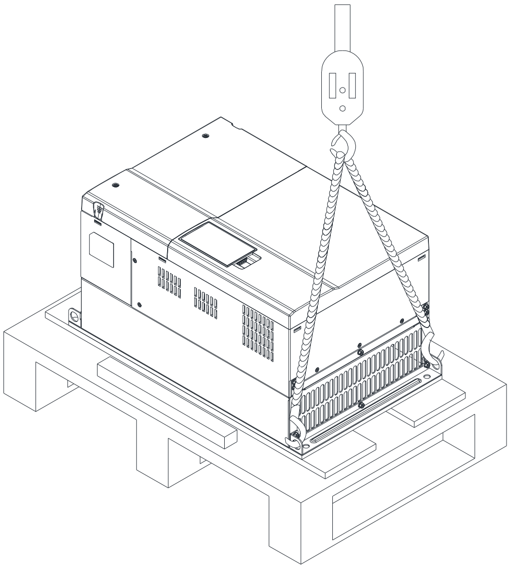



Figure 3-3</td>
<td>Lift the drive by hooking the lifting hole. It is now ready for installation.

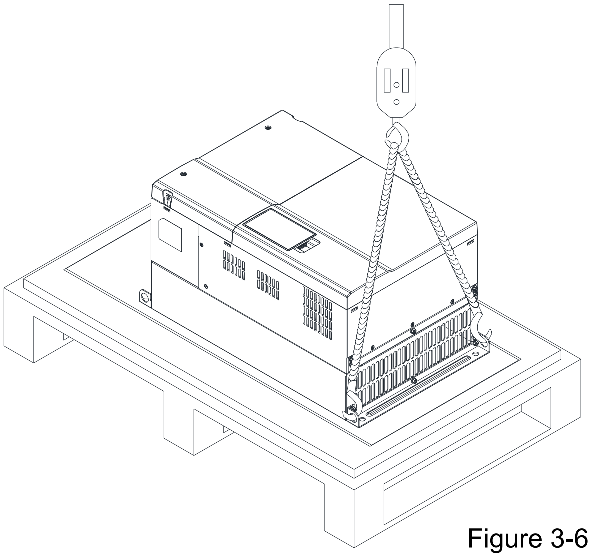
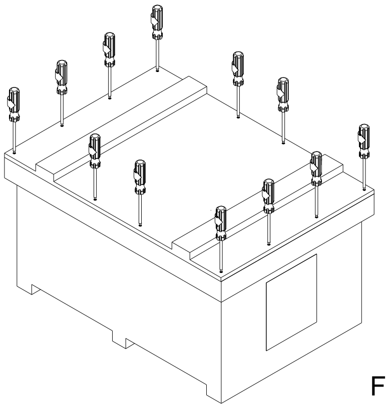
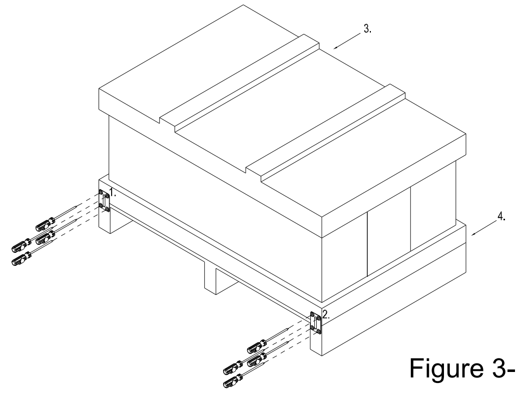
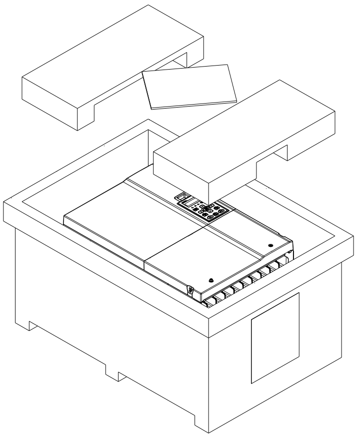
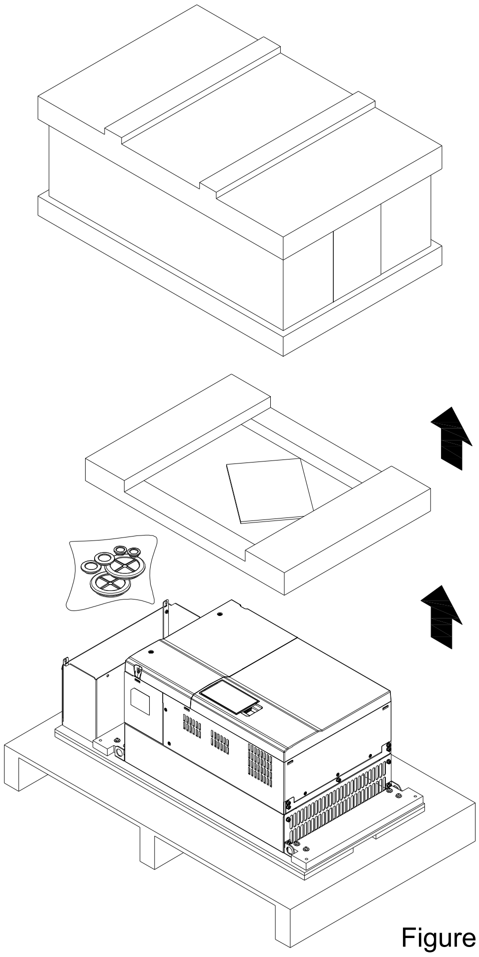
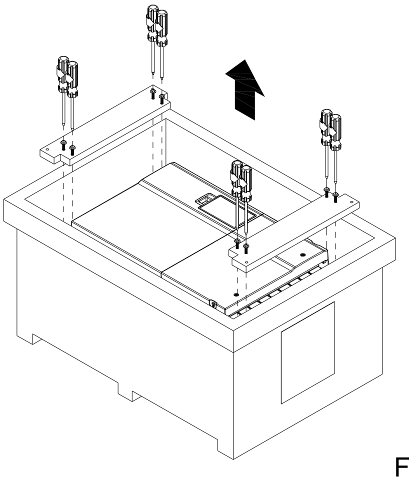



Figure 3-6</td>
</tr>
</table>

Frame D (crate version)	
Unpacking 1 (VFDXXXCPXXX-00) Loosen the 12 screws to open the top cover of the crate.  Figure 3-7	Unpacking 2 (VFDXXXCPXXX-21) Loosen the 16 screws at the four corners of the crate, and then remove the iron plates.  Figure 3-11
Take out the EPEs and the manual.  Figure 3-8	Remove the top cover, take out the EPEs, rubber and the manual.  Figure 3-12
Loosen the eight screws fasten the drive on the pallet, and then remove the wood plate.  Figure 3-9	

Lift the drive by hooking the lifting hole. It is now ready for installation.

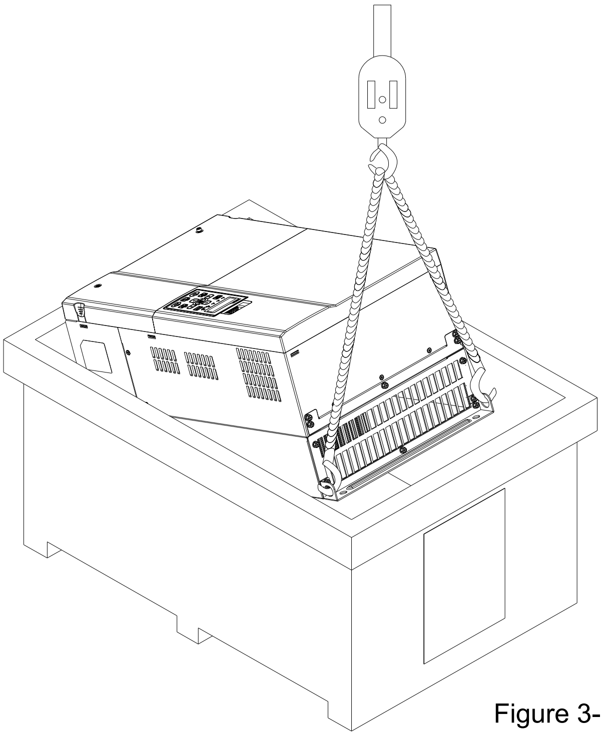


Figure 3-10

Loosen the ten screws fasten the drive on the pallet, and then remove the wood plate.

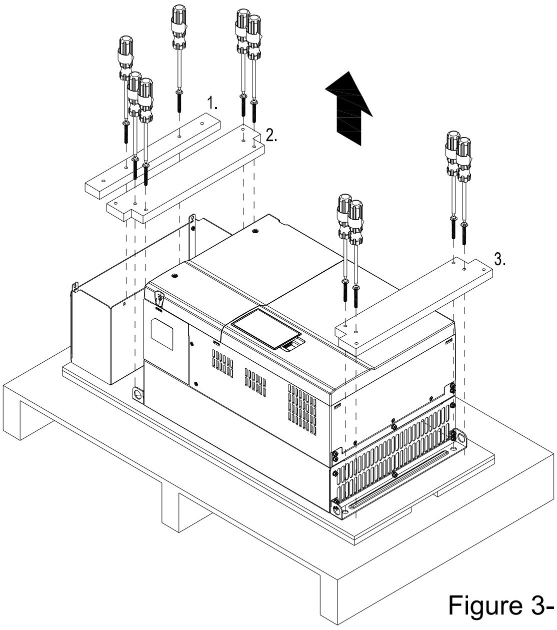


Figure 3-13

Lift the drive by hooking the lifting hole. It is now ready for installation.

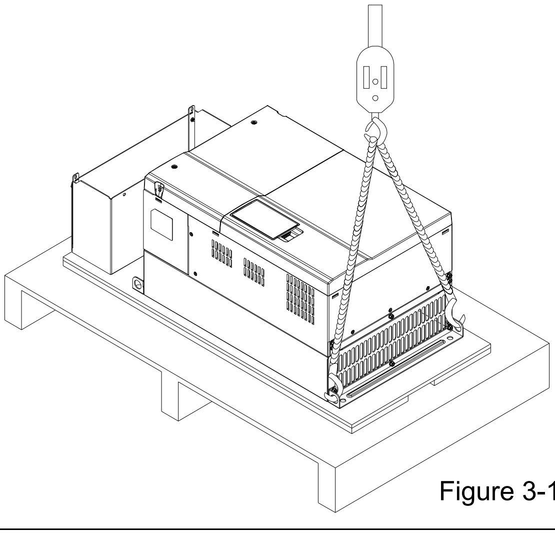
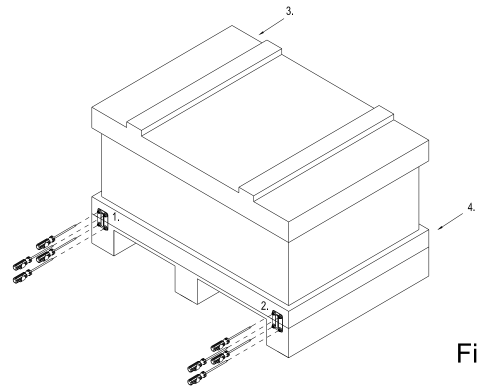
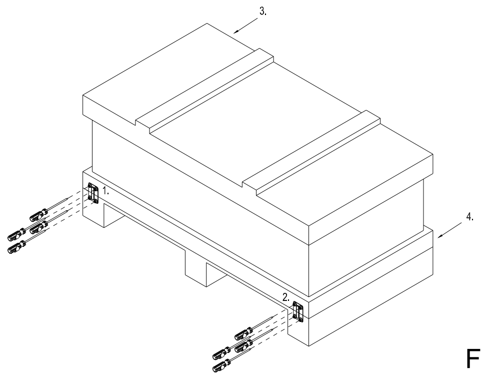
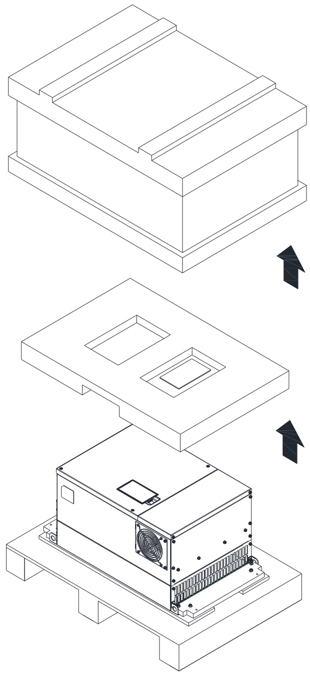
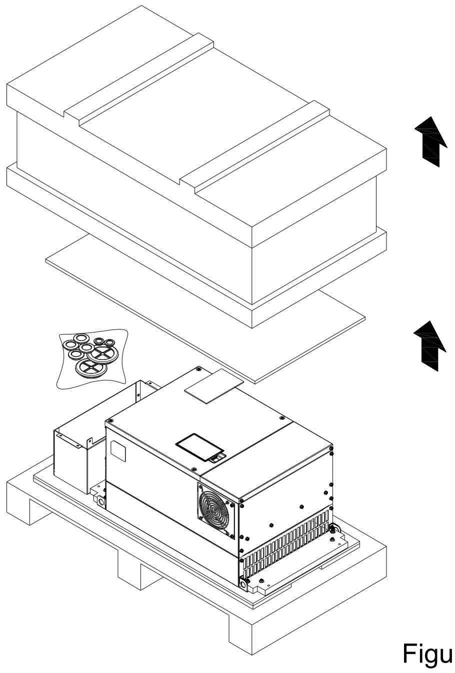
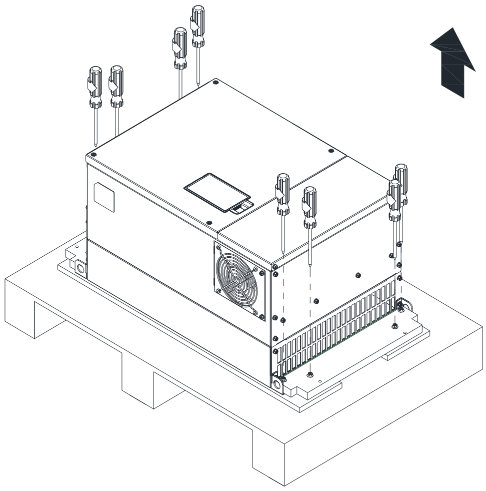
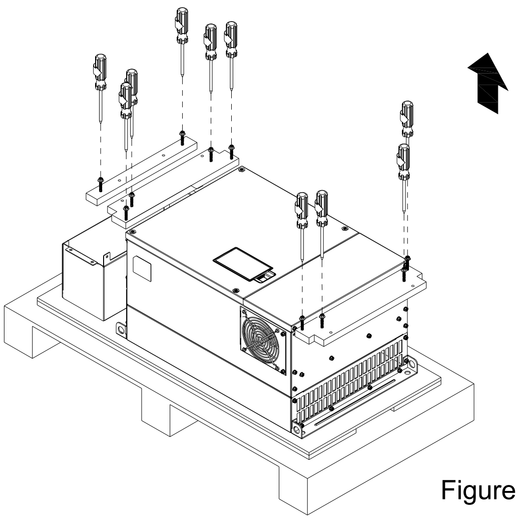
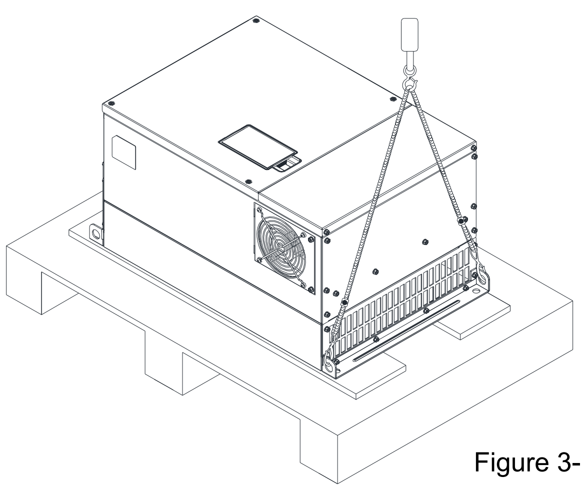
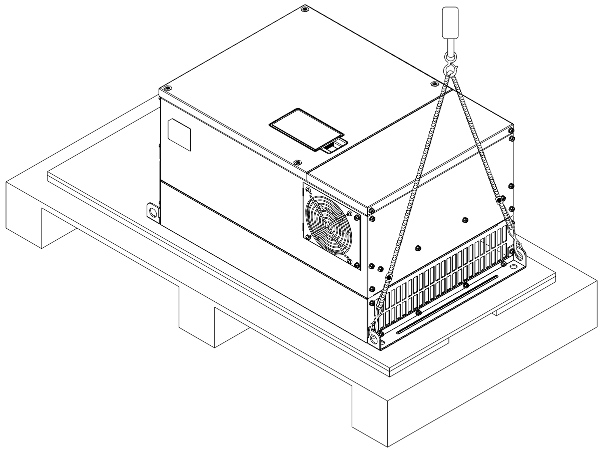
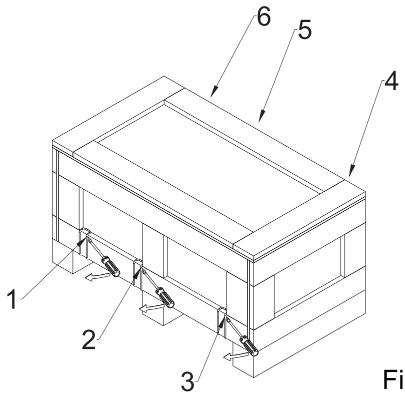
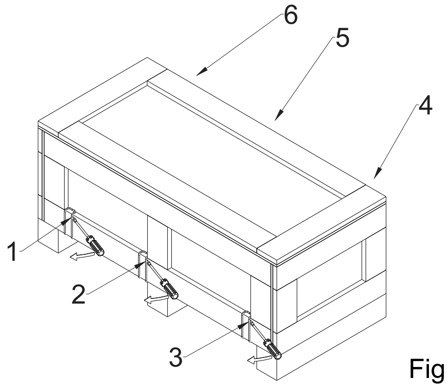
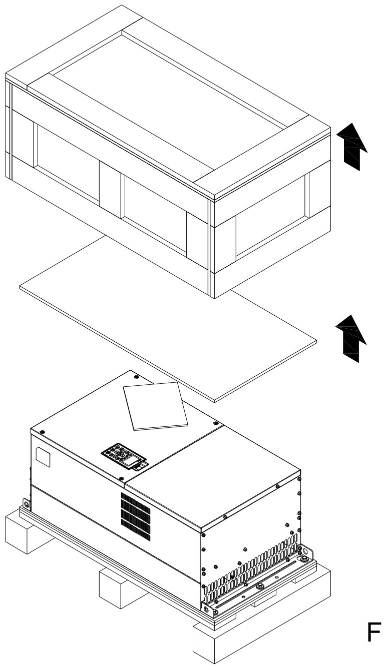
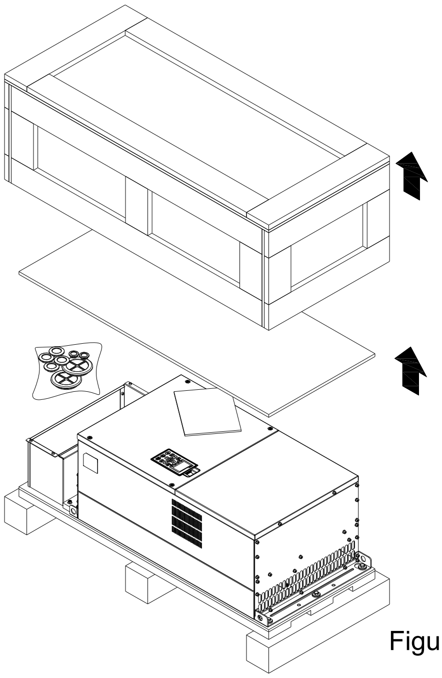
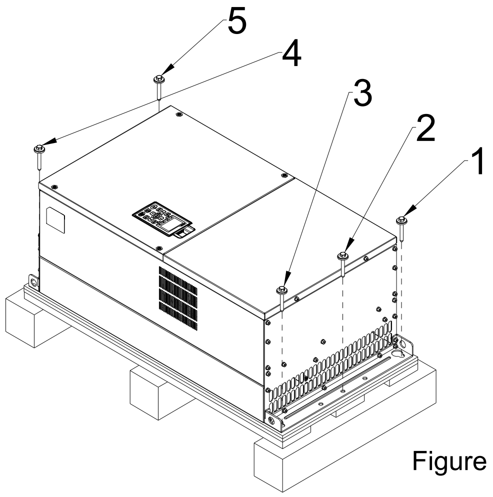
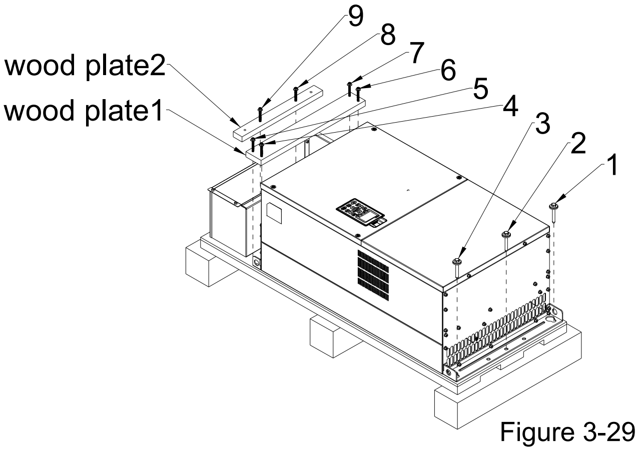
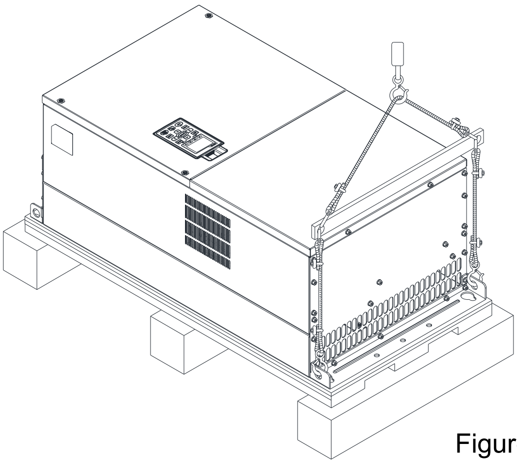
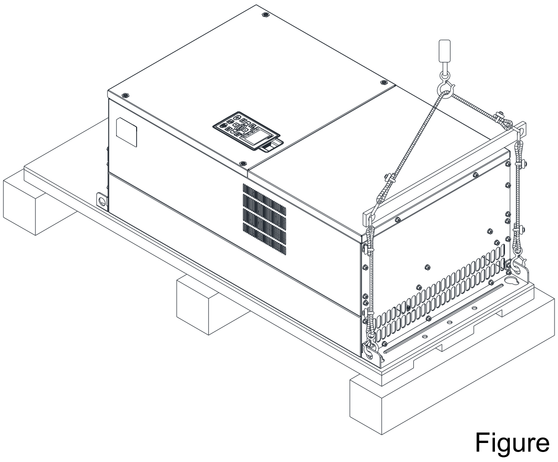


Figure 3-14

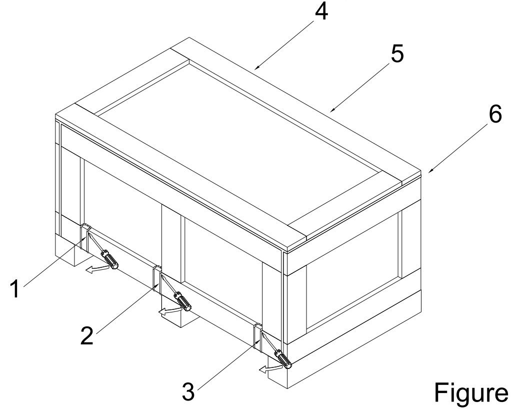
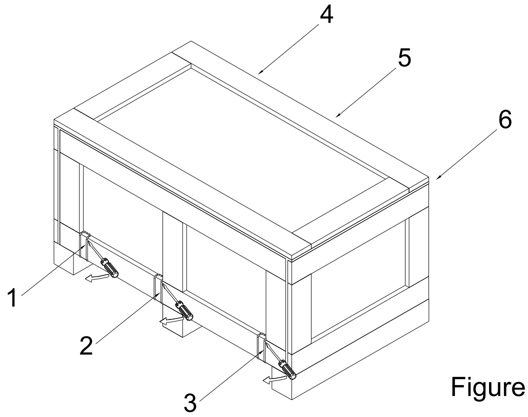
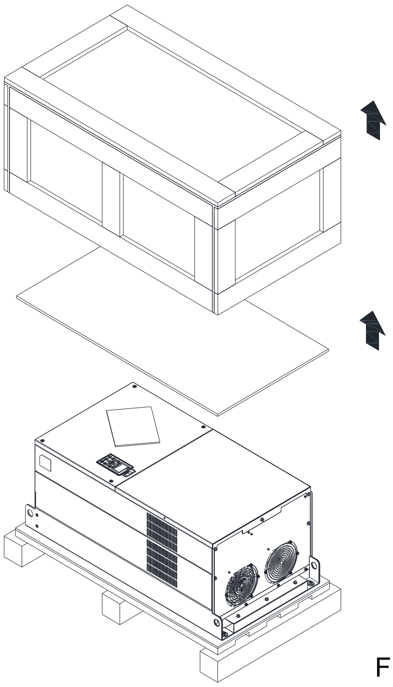
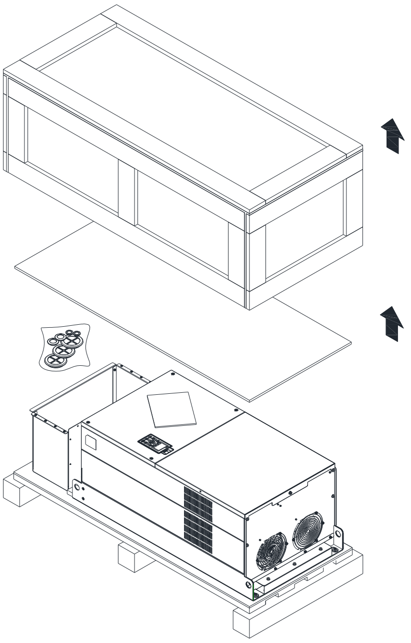
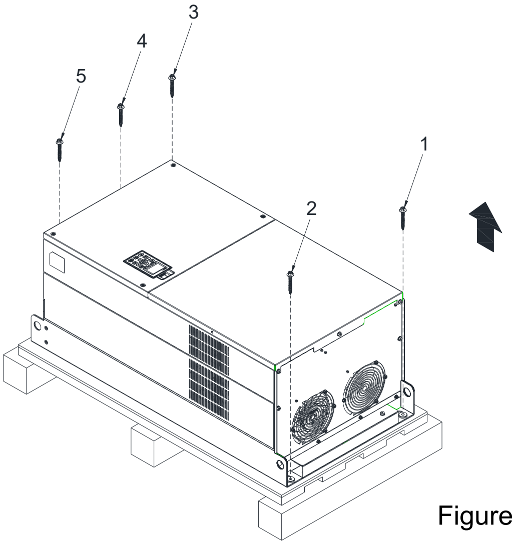
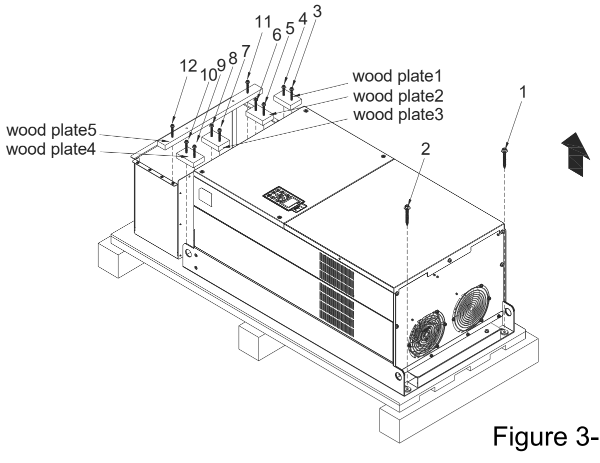
Frame E	
Unpacking 1 (VFDXXXCPXXX-00) Loosen the 16 screws at the four corners of the crate, and then remove the iron plates.  Figure 3-15	Unpacking 2 (VFDXXXCPXXX-21) Loosen the 16 screws at the four corners of the crate, and then remove the iron plates.  Figure 3-19
Remove the top cover, take out the EPEs and the manual.  Figure 3-16	Remove the top cover, take out the EPEs, rubber and the manual.  Figure 3-20
Loosen the eight screws fasten the drive on the pallet, and then remove the wood plate.  Figure 3-17	Loosen the ten screws fasten the drive on the pallet, and then remove the wood plates and the conduit box.  Figure 3-21

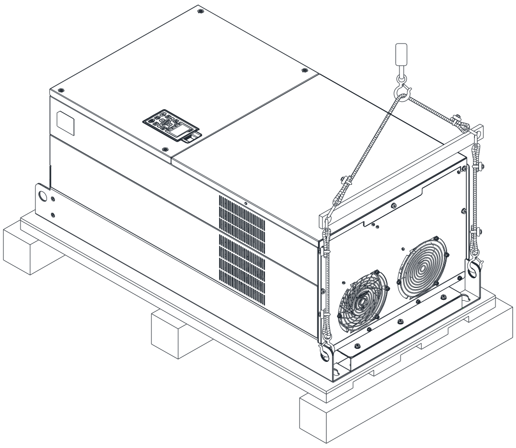
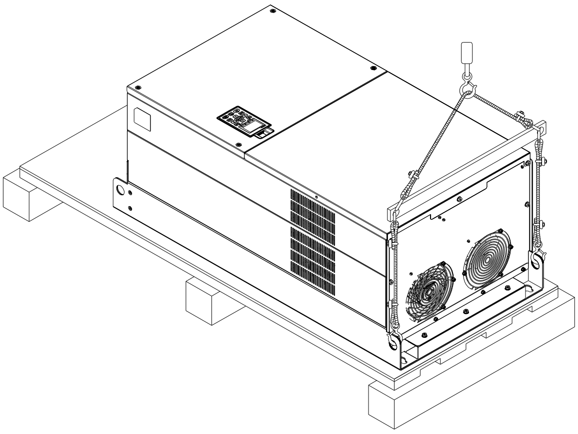
Lift the drive by hooking the lifting hole. It is now ready for installation.  Figure 3-18	Lift the drive by hooking the lifting hole. It is now ready for installation.  Figure 3-22

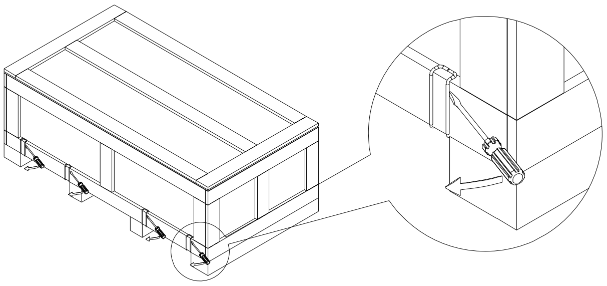
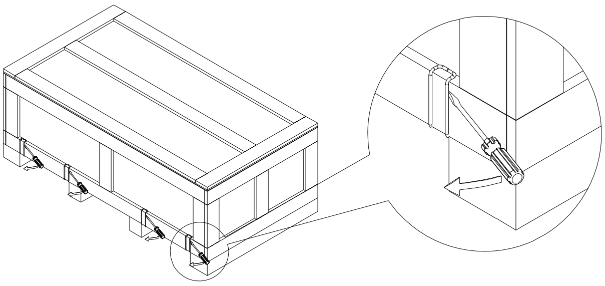
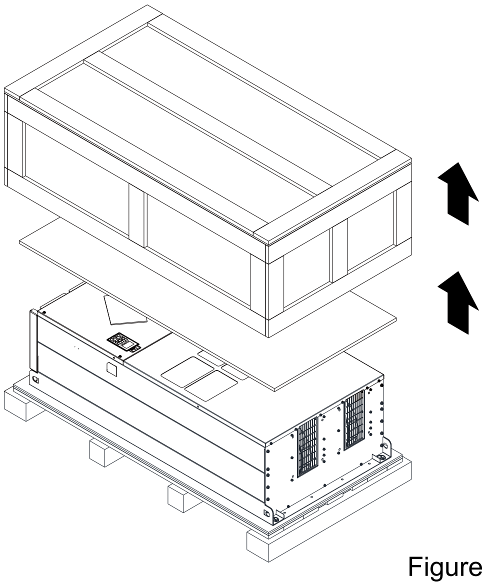
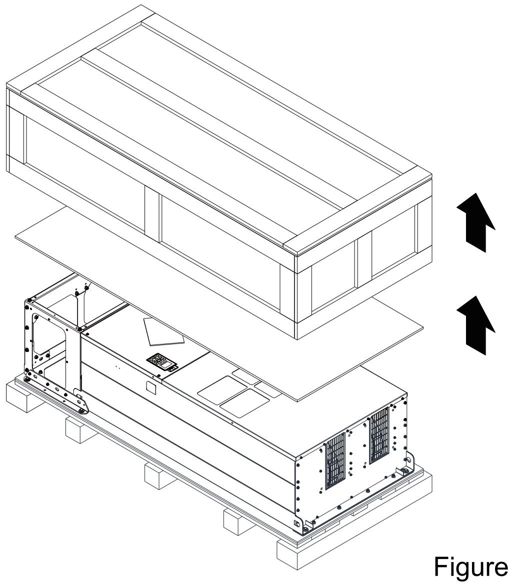
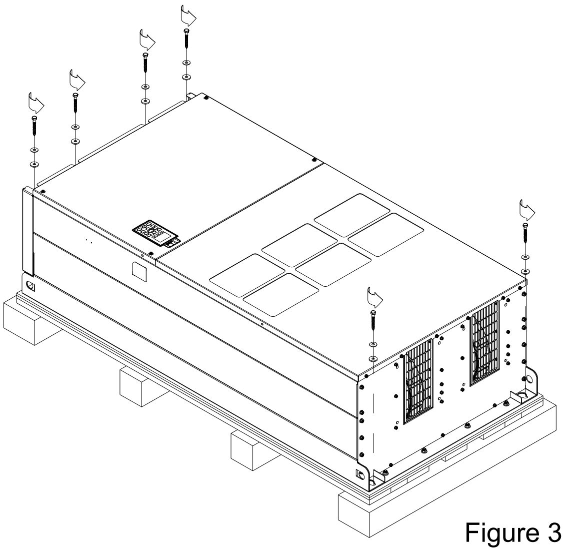
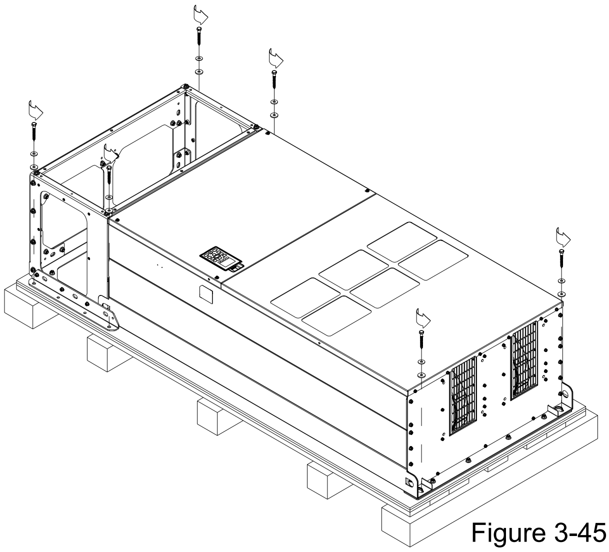
Frame F	
Unpacking 1 (VFDXXXCPXXX-00) Remove the six buckles fixed on the crate with a flat-head screwdriver, see the figure below.  Figure 3-23	Unpacking 2 (VFDXXXCPXXX-21) Remove the six buckles fixed on the crate with a flat-head screwdriver, see the figure below.  Figure 3-27
Remove the top cover, take out the EPEs and the manual.  Figure 3-24	Remove the top cover, take out the EPEs, rubber and the manual.  Figure 3-28
Loosen the five screws fasten the drive on the pallet, see the figure below.  Figure 3-25	Loosen the five screws fasten the drive on the pallet, and then remove the wood plates and the conduit box.  wood plate2 wood plate1 9 8 7 6 5 4 3 2 1 Figure 3-29

Lift the drive by hooking the lifting hole. It is now ready for installation  Figure 3-26 .	Lift the drive by hooking the lifting hole. It is now ready for installation.  Figure 3-30

Frame G

Unpacking 1 (VFDXXXXCPXXA-00)	Unpacking 2 (VFDXXXXCPXXA-21)
Remove the six buckles fixed on the crate with a flat-head screwdriver, see the figure below.  Figure 3-31	Remove the six buckles fixed on the crate with a flat-head screwdriver, see the figure below.  Figure 3-35
Remove the top cover, take out the EPEs and the manual.  Figure 3-32	Remove the top cover, take out the EPEs, rubber and the manual.  Figure 3-36
Loosen the five screws fasten the drive on the pallet, see the figure below.  Figure 3-33	Loosen the 12 screws fasten the drive on the pallet, and then remove the wood plates and the conduit box.  11 6 5 4 3 12 10 9 8 7 wood plate1 wood plate2 wood plate3 1 wood plate5 wood plate4 2 Figure 3-37

Lift the drive by hooking the lifting hole. It is now ready for installation.  Figure 3-34	Lift the drive by hooking the lifting hole. It is now ready for installation.  Figure 3-38

Frame H	
Unpacking 1 (VFDXXXXCPXXA-00) Remove the eight buckles fixed on the crate with a flat-head screwdriver, see the figure below.  Figure 3-39	Unpacking 2 (VFDXXXXCPXXC-00) Remove the eight buckles fixed on the crate with a flat-head screwdriver, see the figure below.  Figure 3-43
Remove the top cover, take out the EPEs and the manual.  Figure 3-40	Remove the top cover, take out the EPEs and the manual.  Figure 3-44
Loosen the six screws fasten the drive on the pallet, and then remove six metal washers and six plastic washers. See the figure below.  Figure 3-41	Loosen the six screws fasten the drive on the pallet, and then remove six metal washers and six plastic washers. See the figure below.  Figure 3-45

Lift the drive by hooking the lifting hole. It is now ready for installation.

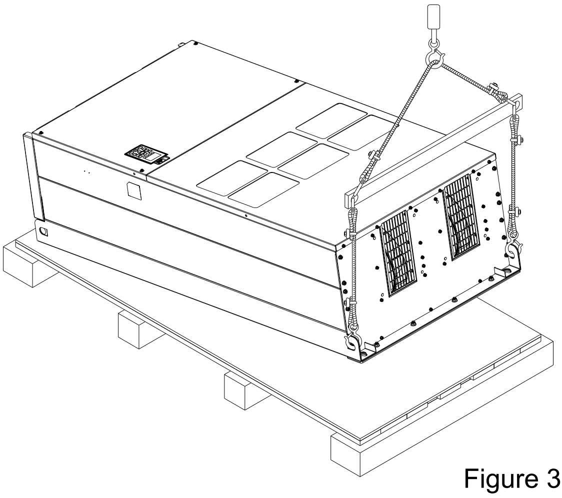


Figure 3-42

Loosen the six M6 screws and the iron plates (see the figure below). You can use the removed screws and iron plates to fix the drive from outside.

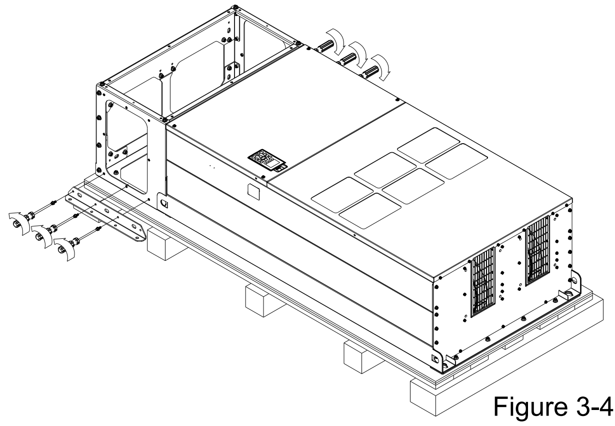


Figure 3-46

This description is how to fix the drive from the outside. You can skip to the next step if it is not necessary.
Loosen the eight M8 screws, and then use these eight M8 screws to fix the iron plates (removed at the last step) to the drive, see the figure below.

Torque: 150–180 kg-cm / [130.20–156.24 lb-in.] / [14.7–17.6 Nm]

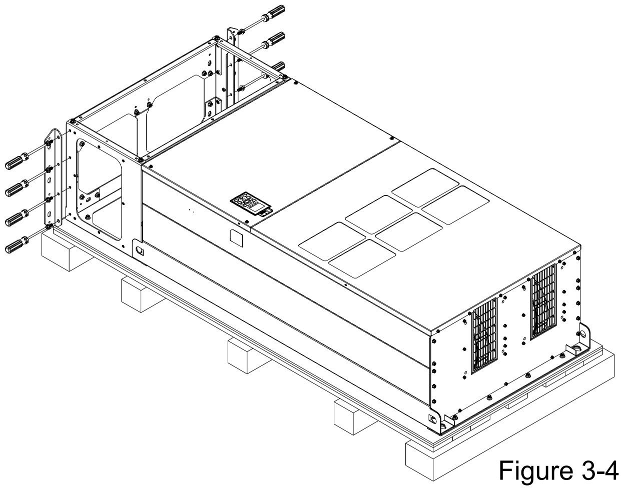


Figure 3-47

Lift the drive by hooking the lifting hole. It is now ready for installation.

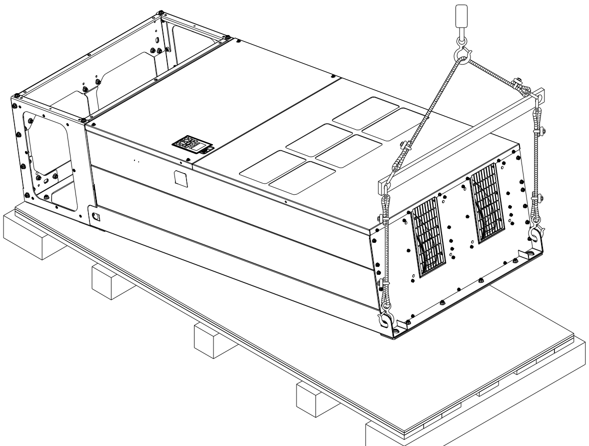


Figure 3-48

Frame H

Unpacking 3 (VFDXXXXCPXXC-21)

Remove the eight buckles fixed on the crate with a flat-head screwdriver, see the figure below.

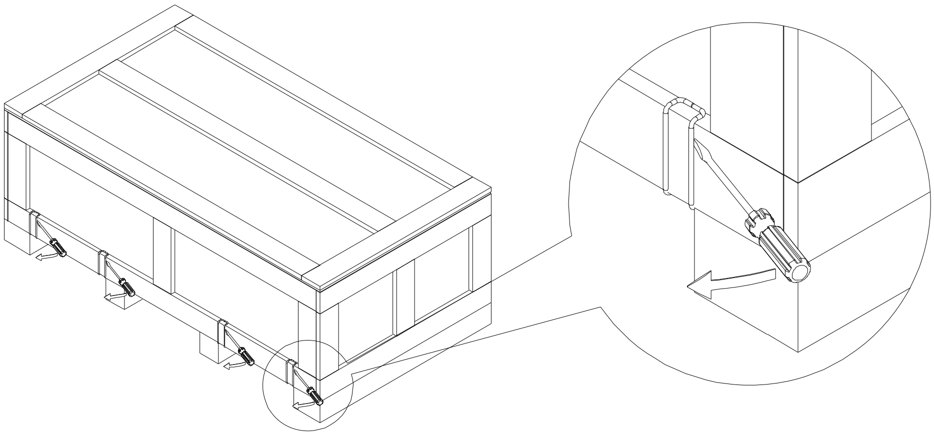


Figure 3-49

Remove the top cover, take out the EPEs and the manual.

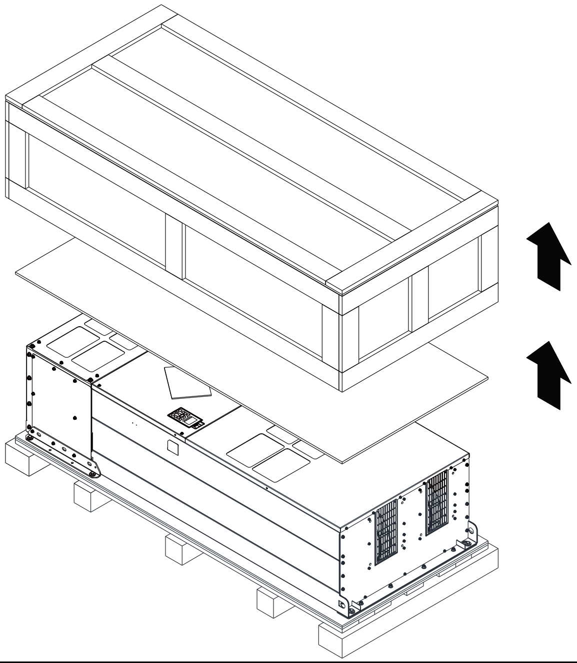


Figure 3-50

Loosen the six screws fasten the drive on the pallet, and then remove six metal washers and six plastic washers. See the figure below.

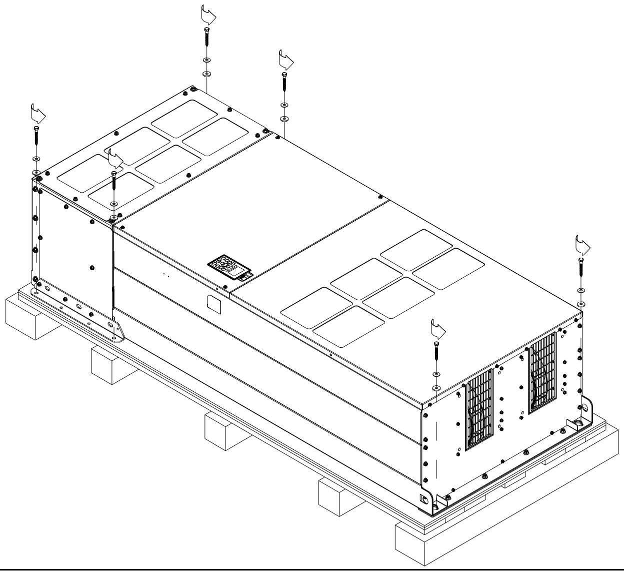


Figure 3-51

Loosen the six M6 screws and the iron plates (see the figure below). You can use the removed screws and iron plates to fix the drive from the outside.

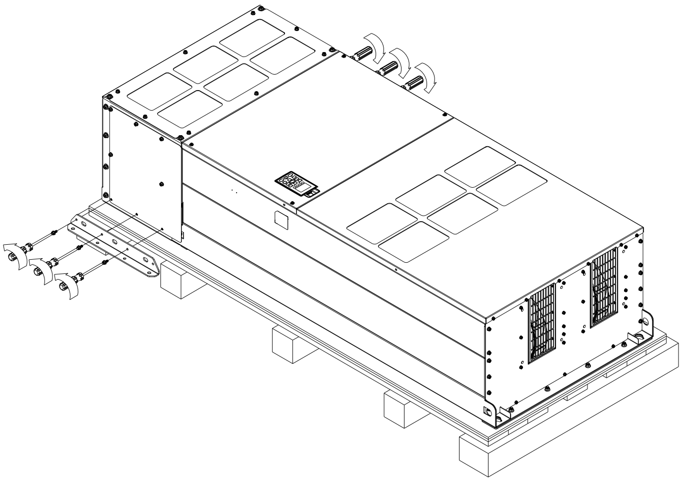


Figure 3-52

Fix the drive from the inside

Loosen the 18 M6 screws and remove the covers (see the figure 3-54). After fixing the drive and the cover for cables (see the figure 3-53), fasten the other covers back (see the figure 3-54)

Torque: 35–45 kg-cm / [30.38–39.06 lb-in.] / [3.4–4.4 Nm]

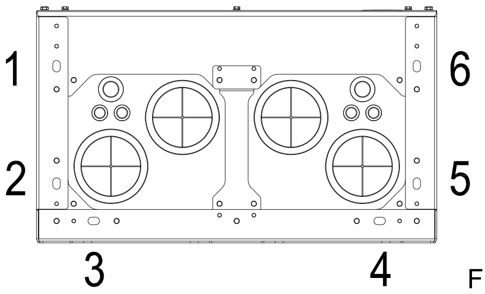


Figure 3-53

Cover for cables (use M12 screws)

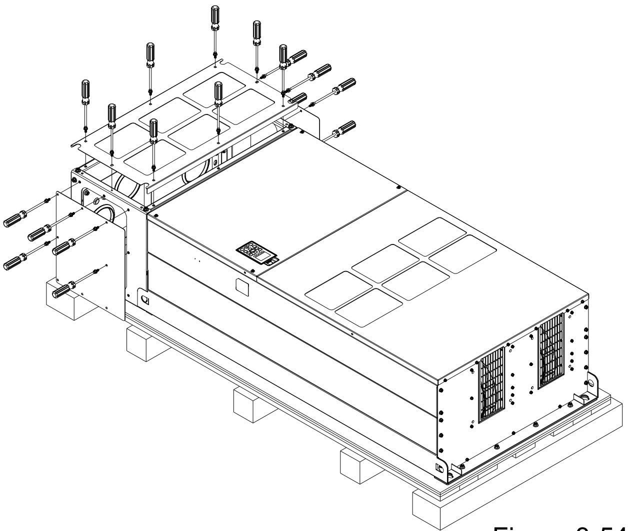


Figure 3-54

Fix the drive from the outside

Loosen the eight M8 screws, and then use these eight M8 screws to fix the iron plates (removed at the last step) to the drive, see the figure below.

Torque: 150–180 kg-cm / [130.20–156.24 lb-in.] / [14.7–17.6 Nm]

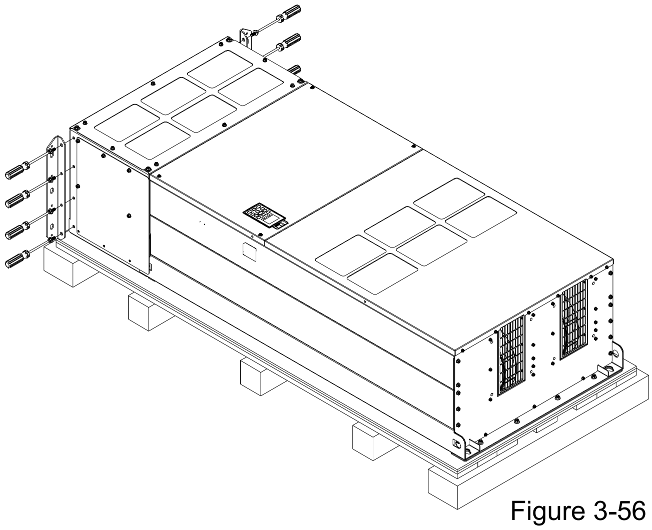


Figure 3-56

Fasten the six M6 screws back, see the figure below.

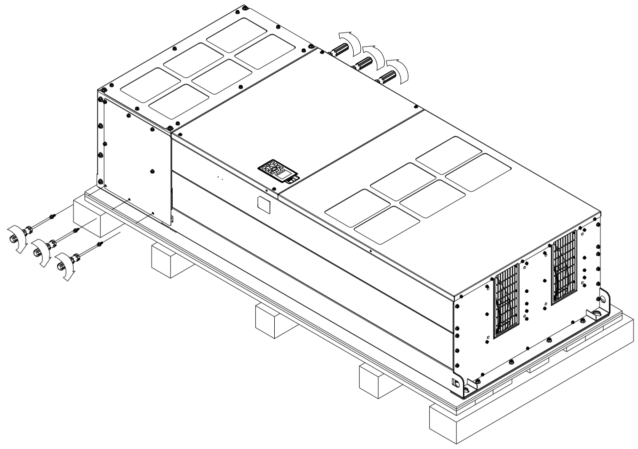


Figure 3-55

Fasten the six M6 screws back, see the figure below.

Torque: 35–45 kg-cm / [30.8–39.06 lb-in] / [3.4–4.4 Nm]

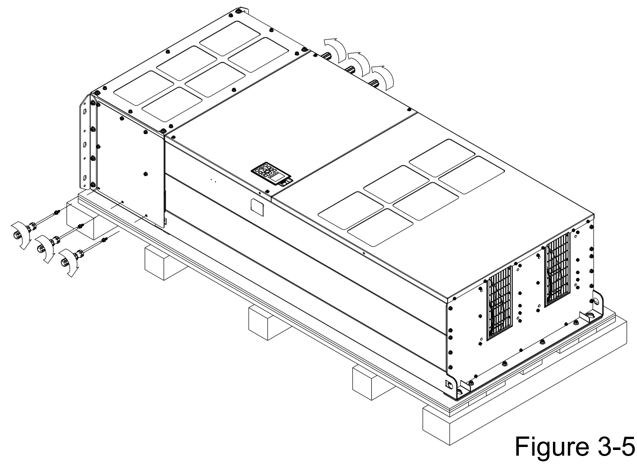


Figure 3-57

Lift the drive by hooking the lifting hole. It is now ready for installation.

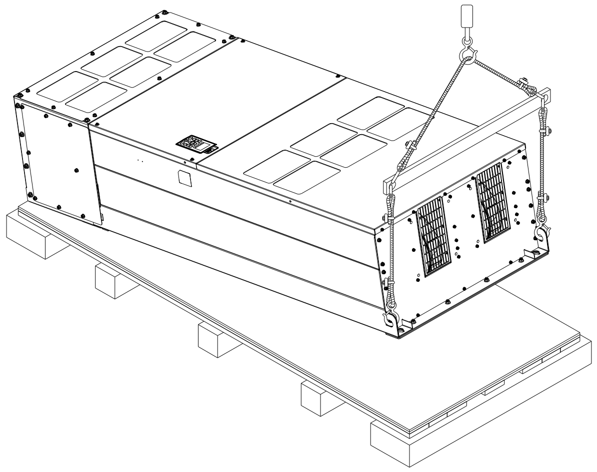


Figure 3-58

690V Frame H

Unpacking 1 (VFDXXXXCP63A-00)

Remove the eight buckles fixed on the crate with a flat-head screwdriver, see the figure below.

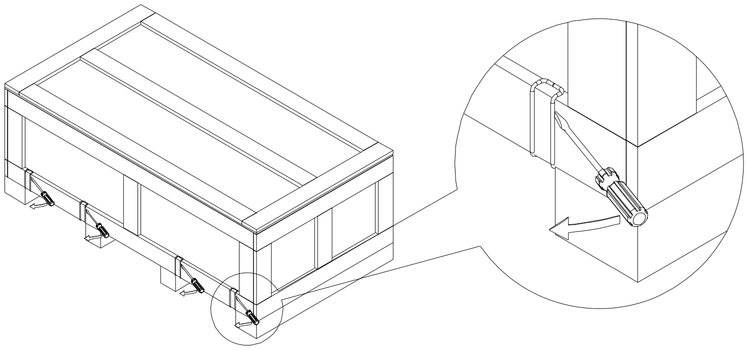


Figure 3-59

Remove the top cover, take out the EPEs and the manual.

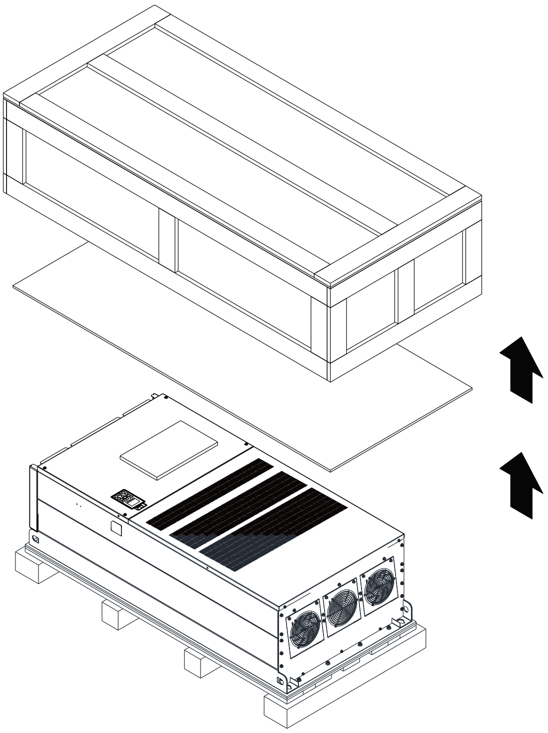


Figure 3-60

Loosen the six screws fasten the drive on the pallet, and then remove six metal washers and six plastic washers. See the figure below.

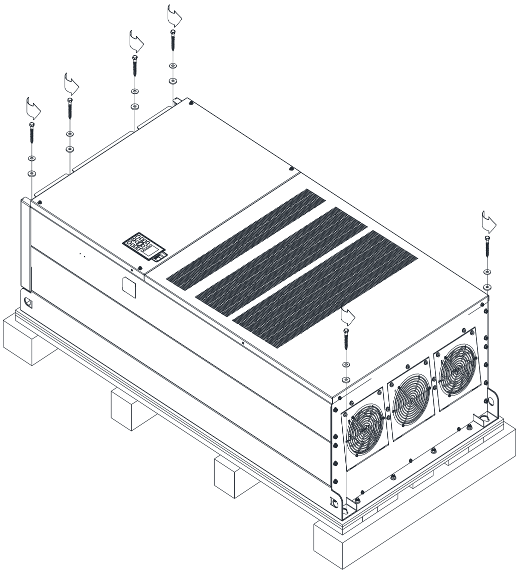


Figure 3-61

Lift the drive by hooking the lifting hole. It is now ready for installation.

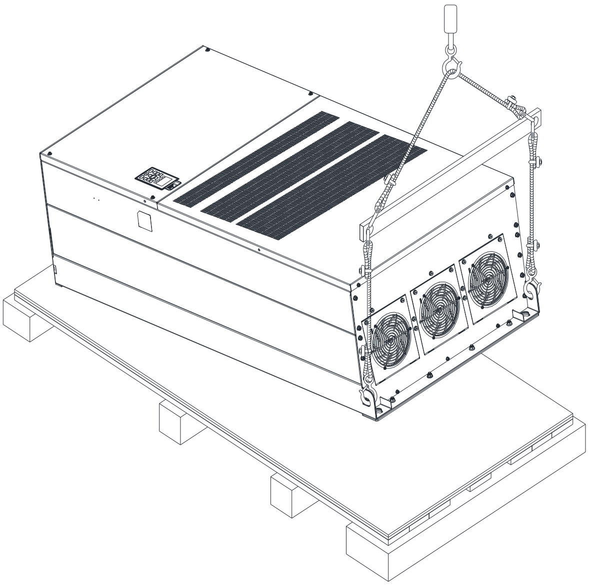


Figure 3-62

690V Frame H

Unpacking 2 (VFDXXXXCP63A-21)

Remove the eight buckles fixed on the crate with a flat-head screwdriver, see the figure below.

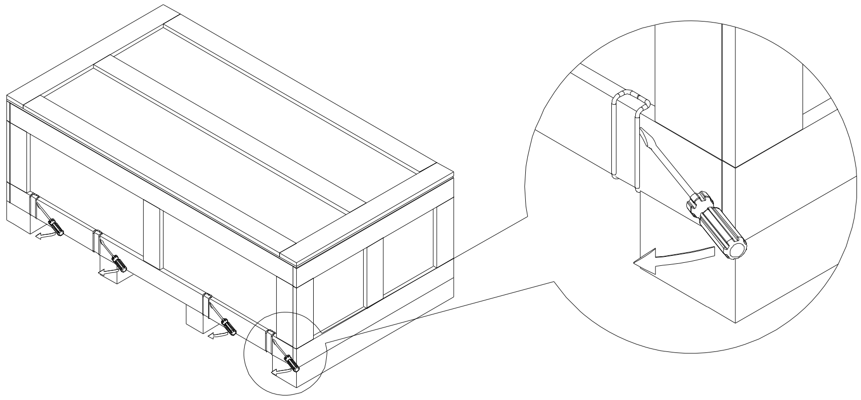


Figure 3-63

Remove the top cover, take out the EPEs and the manual.

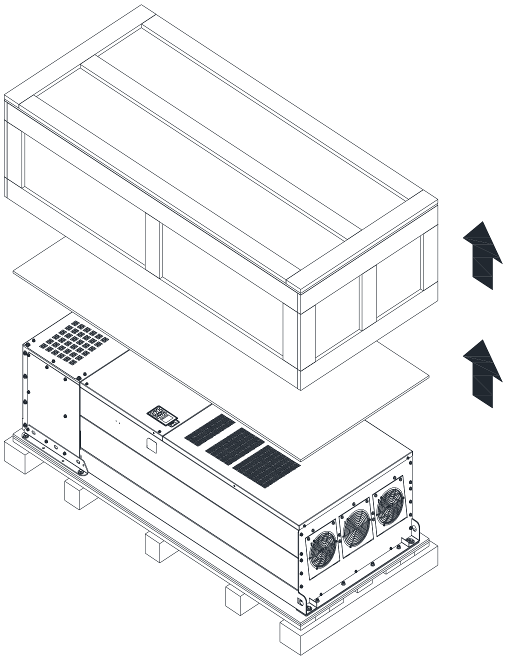


Figure 3-64

Loosen the six screws fasten the drive on the pallet, and then remove six metal washers and six plastic washers. See the figure below.

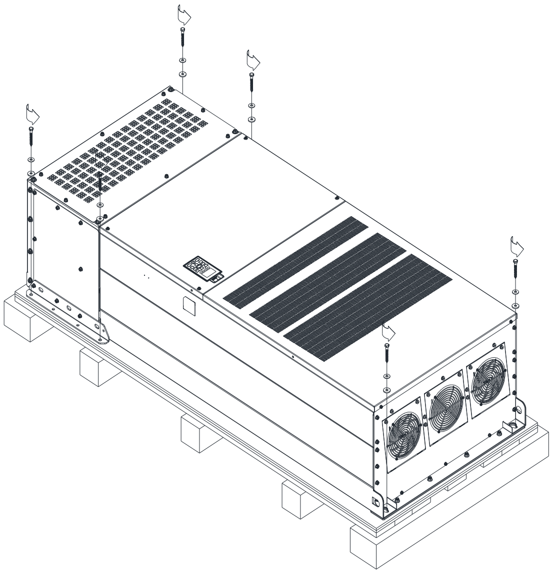


Figure 3-65

Loosen the six M6 screws and the iron plates (see the figure below). You can use the removed screws and iron plates to fix the drive from the outside.

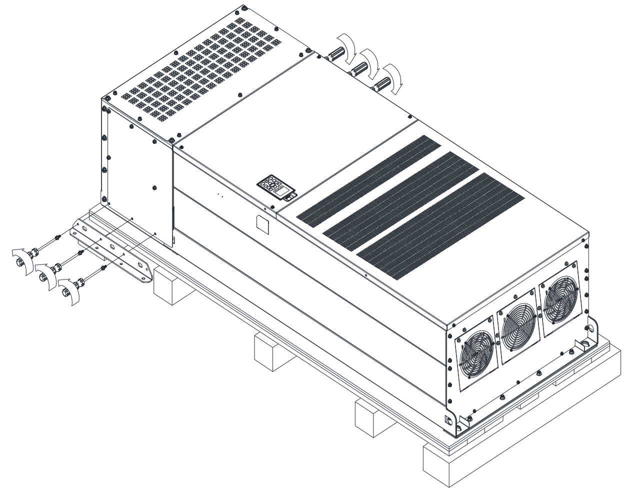


Figure 3-66

Fix the drive from the inside.

Loosen the 18 M6 screws and remove the covers (see the figure 3-68). After fixing the drive and the cover for cables (see the figure 3-67), fasten the other covers back (see the figure 3-68)

Torque: 35–45 kg-cm / [30.38–39.06 lb-in.] / [3.4–4.4 Nm]

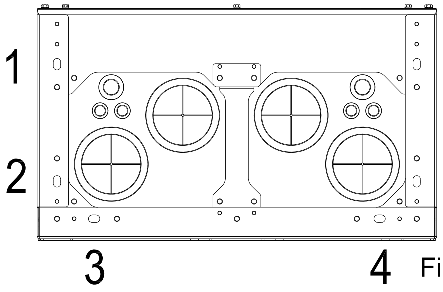


Figure 3-67

Cover for cables (use M12 screws)

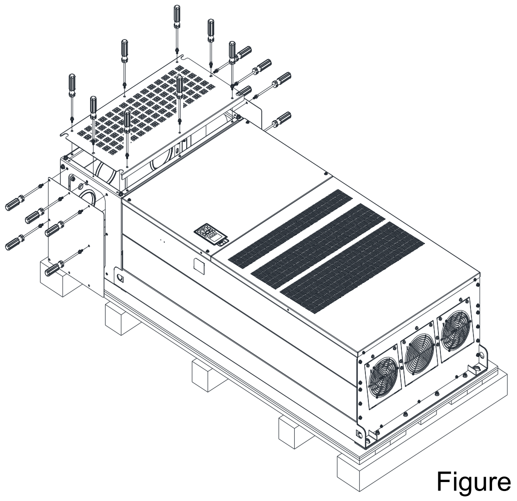


Figure 3-68

Fix the drive from the outside.

Loosen the eight M8 screws, and then use these eight M8 screws to fix the iron plates (removed at the last step) to the drive, see the figure below.

Torque: 150–180 kg-cm / [130.20–156.24 lb-in.] / [14.7–17.6 Nm]

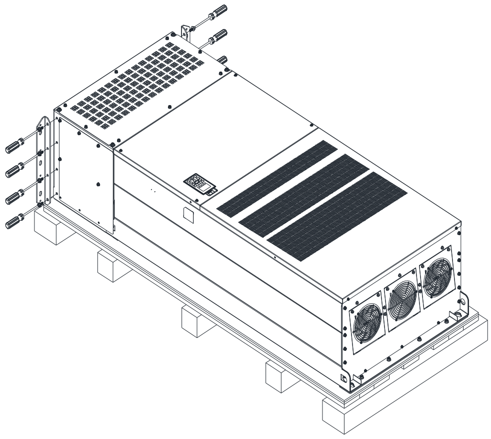


Figure 3-70

Fasten the six M6 screws back, see the figure below.

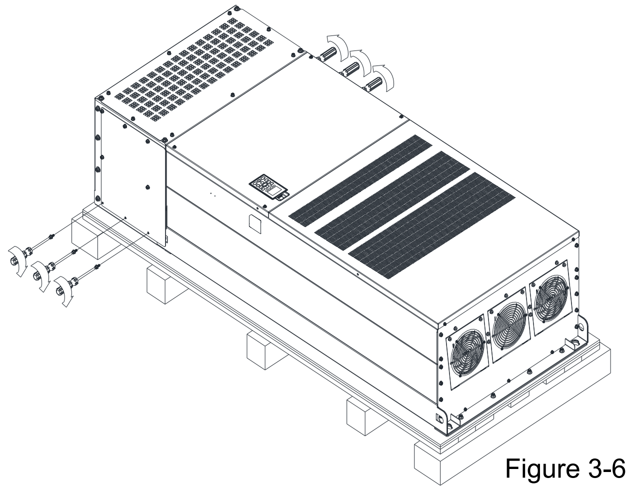


Figure 3-69

Fasten the six M6 screws back, see the figure below.

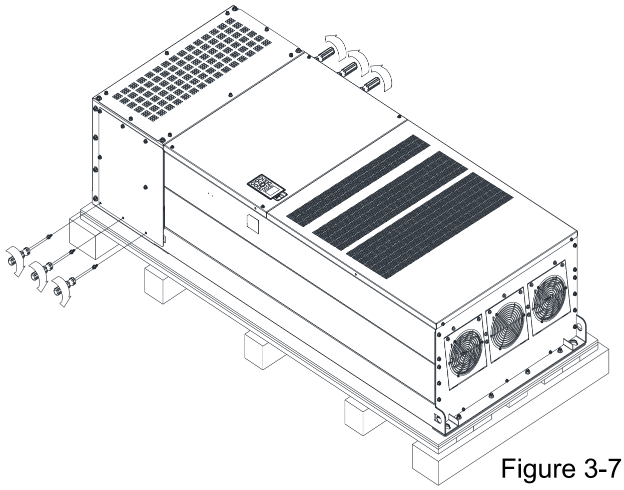


Figure 3-71

Lift the drive by hooking the lifting hole. It is now ready for installation.

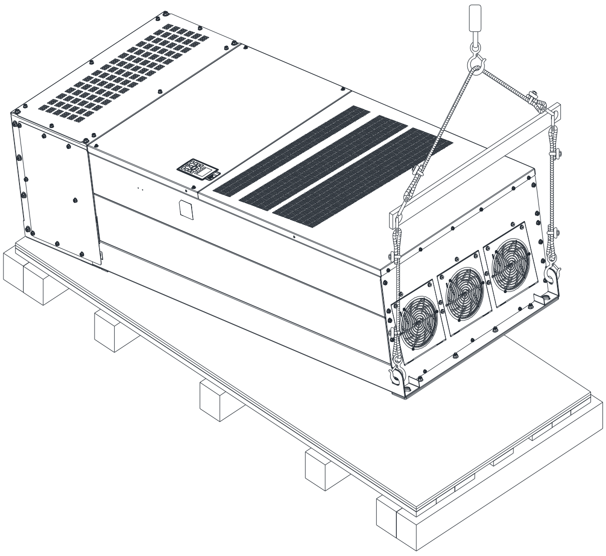
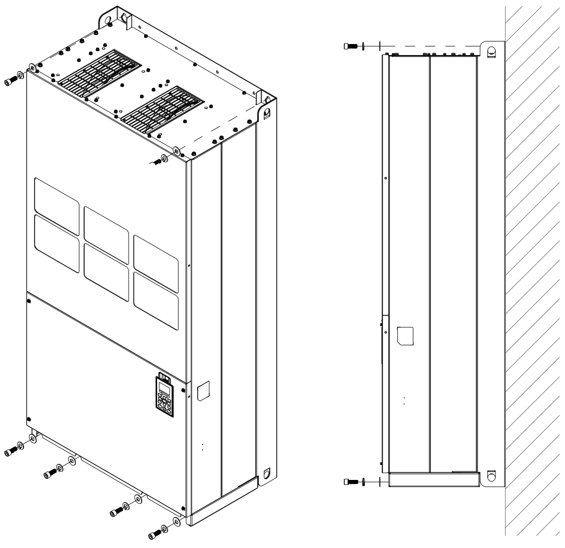


Figure 3-72

Frame H: Fix the drive

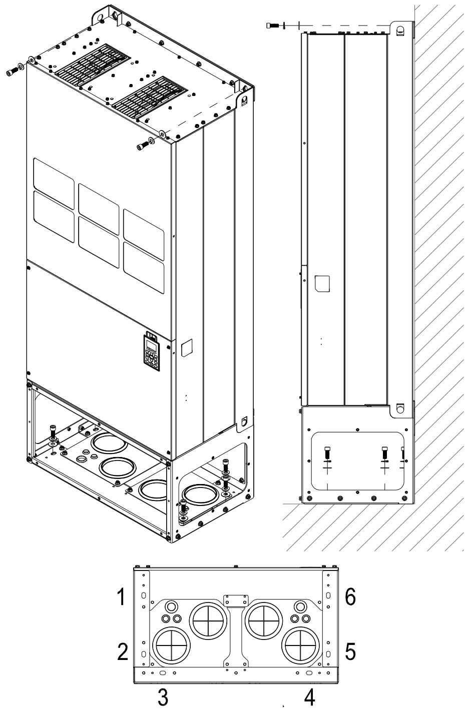
H1: VFDXXXXCPXXA-00



Screw M12*6
Torque: 340–420 kg-cm / [295.1–364.6 lb-in.] /
[33.3–41.2 Nm]

Figure 3-73

H2: VFDXXXXCPXXC-00

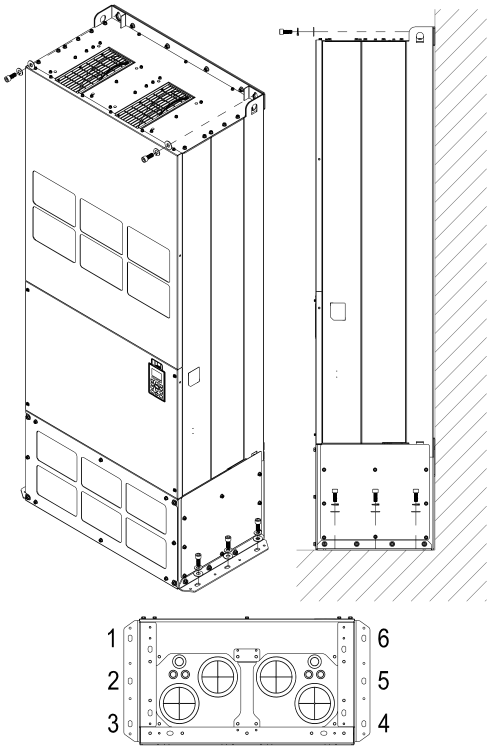


Fix the drive from the inside

Fix the drive from the inside
Screw M12*8
Torque: 340–420 kg-cm / [295.1–364.6 lb-in.] /
[33.3–41.2 Nm]

Figure 3-74

H3：VFDXXXXCPXXC-21

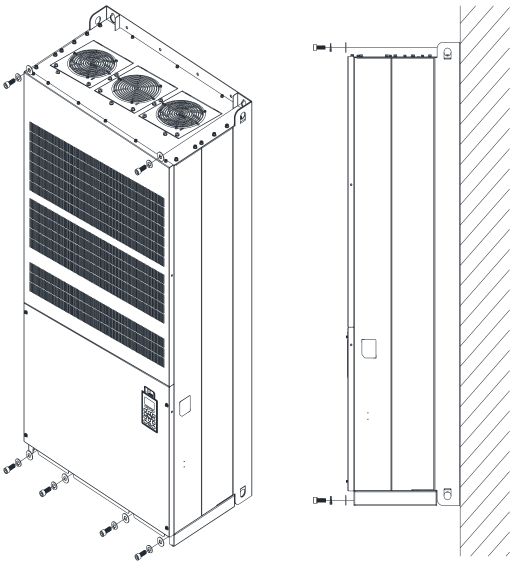


Fix the drive from the outside
Screw M12*8
Torque: 340–420 kg-cm / [295.1–364.6 lb-in.] /
[33.3–41.2 Nm]

Fix the drive from the outside

Figure 3-75

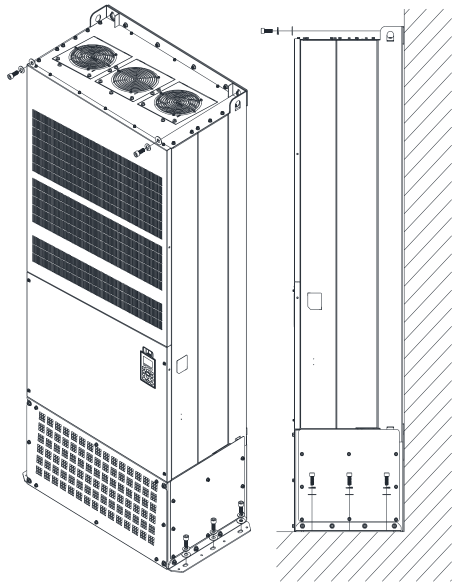
H1: VFDXXXXCP63A-00



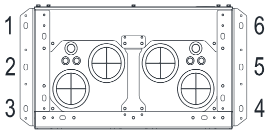
Screw M12*6
Torque: 340–420 kg-cm / [295.1–364.6 lb-in.] /
[33.3–41.2 Nm]

Figure 3-76

H2: VFDXXXXCP63A-21



Fix the drive from the outside
Screw M12*8
Torque: 340–420 kg-cm / [295.1–364.6 Ib-in.] /
[33.3–41.2 Nm]



Fix the drive from the outside

Figure 3-77

3-2 The Lifting Hook

The arrows indicate the location of the lifting holes of frame D to H, as shown in figure below:

Frame D0

Applicable models:

VFD450CP43S-00; VFD550CP43S-00;

VFD450CP43S-21; VFD550CP43S-21

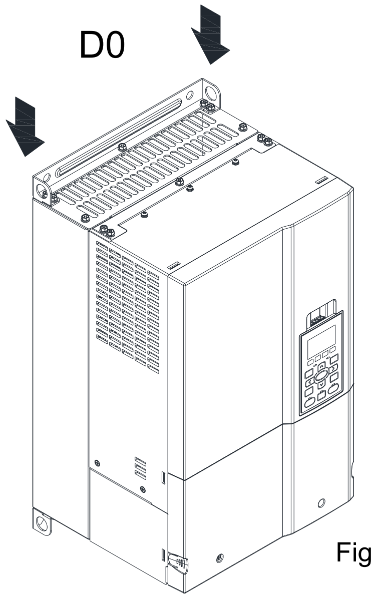


Figure 3-78

Frame D

Applicable models:

VFD370CP23A-00; VFD450CP23A-00;

VFD750CP43B-00; VFD900CP43A-00;

VFD450CP63A-00; VFD550CP63A-00;

VFD370CP23A-21; VFD450CP23A-21;

VFD750CP43B-21; VFD900CP43A-21;

VFD450CP63A-21; VFD550CP63A-21

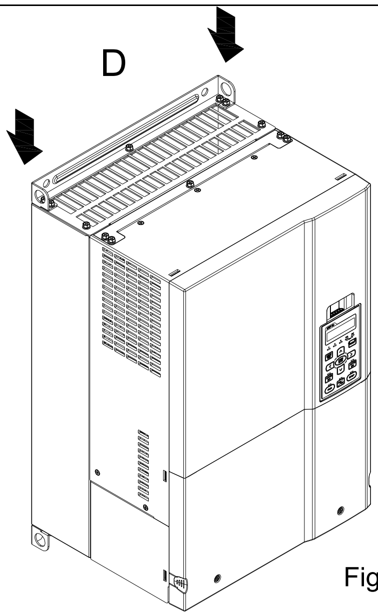


Figure 3-79

Frame E

Applicable models:

VFD550CP23A-00; VFD750CP23A-00;

VFD900CP23A-00; VFD1100CP43A-00;

VFD1320CP43B-00; VFD750CP63A-00;

VFD900CP63A-00; VFD1100CP63A-00;

VFD1320CP63A-00; VFD550CP23A-21;

VFD750CP23A-21; VFD900CP23A-21;

VFD1100CP43A-21; VFD1320CP43B-21;

VFD750CP63A-21; VFD900CP63A-21;

VFD1100CP63A-21; VFD1320CP63A-21

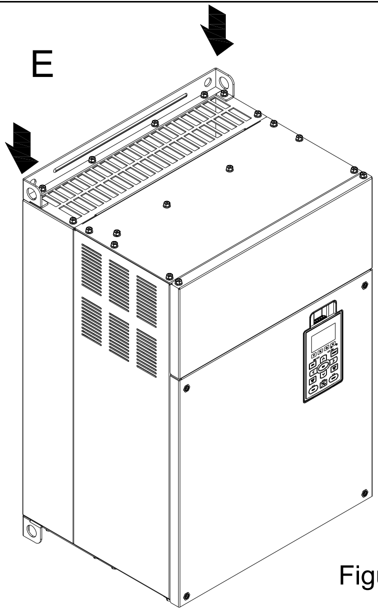


Figure 3-80

Frame F

Applicable models:

VFD1600CP43A-00; VFD1850CP43B-00;
VFD1600CP63A-00; VFD2000CP63A-00;
VFD1600CP43A-21; VFD1850CP43B-21;
VFD1600CP63A-21; VFD2000CP63A-21

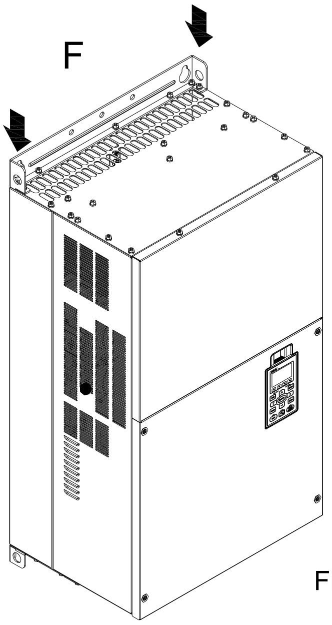


Figure 3-81

Frame G

Applicable models:

VFD2000CP43A-00; VFD2200CP43A-00;
VFD2500CP43A-00; VFD2800CP43A-00;
VFD2500CP63A-00; VFD3150CP63A-00;
VFD2000CP43A-21; VFD2200CP43A-21;
VFD2500CP43A-21; VFD2800CP43A-21;
VFD2500CP63A-21; VFD3150CP63A-21

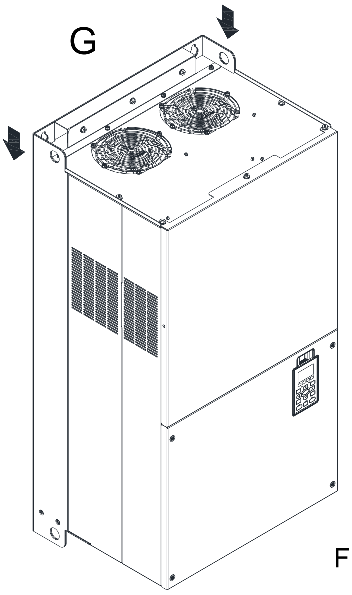


Figure 3-82

Frame H

Applicable models:

VFD3150CP43A-00; VFD3550CP43A-00;
VFD4000CP43A-00; VFD5000CP43A-00;
VFD5600CP43A-00; VFD6300CP43A-00;
VFD3150CP43C-00; VFD3550CP43C-00;
VFD4000CP43C-00; VFD5000CP43C-00;
VFD3150CP43C-21; VFD3550CP43C-21;
VFD4000CP43C-21; VFD5000CP43C-21;
VFD5600CP43C-21; VFD6300CP43C-21;
VFD4000CP63A-00; VFD4500CP63A-00;
VFD5600CP63A-00; VFD6300CP63A-00

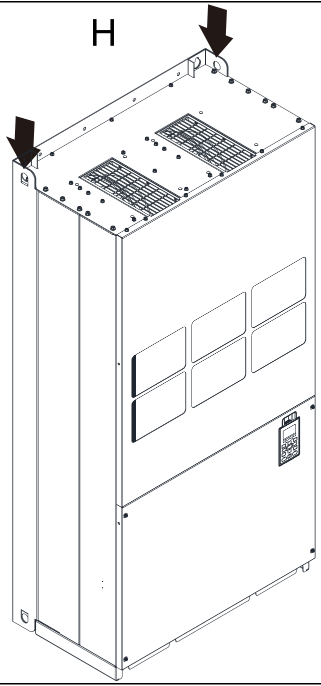


Figure 3-83

690V Frame H2

Applicable models:

VFD4000CP63A-21; VFD4500CP63A-21;

VFD5600CP63A-21; VFD6300CP63A-21

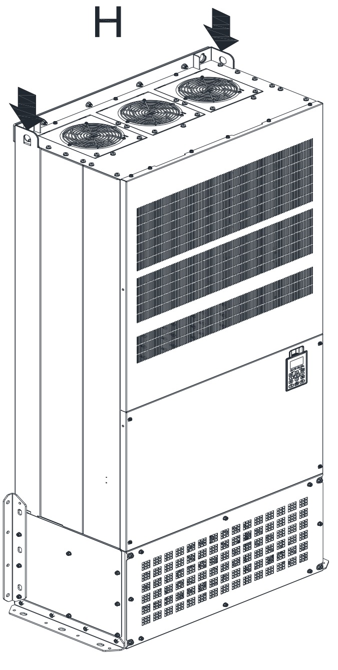


Figure 3-84

Ensure the lifting hook properly goes through the lifting hole, as shown in the following diagram.

Applicable to Frame D0–E

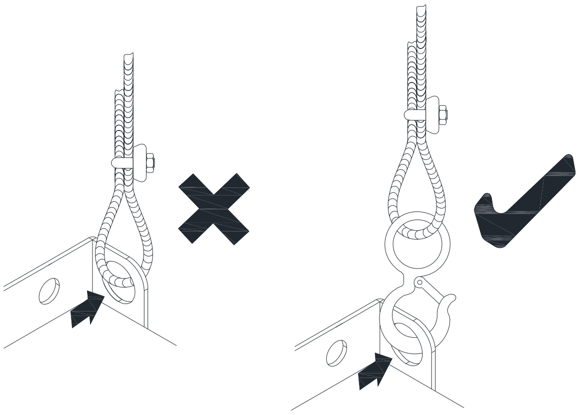


Figure 3-85

Applicable to Frame F–H

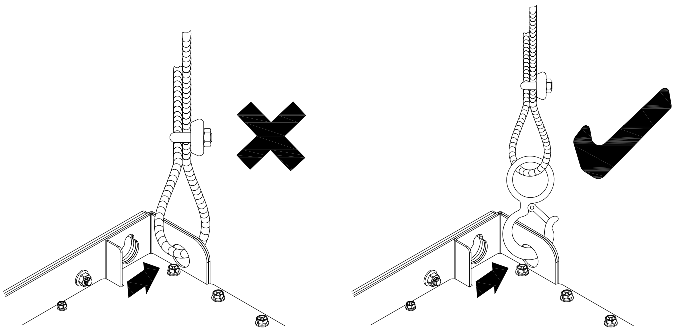


Figure 3-86

Ensure the angle between the lifting holes and the lifting device is within the specification, as shown in the following figure.

Applicable to Frame D0–E

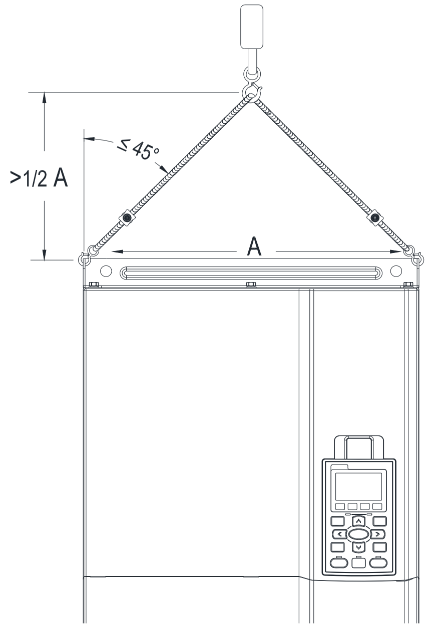


Figure 3-87

Applicable to Frame F–H, 690V Frame H3

Following drawing is only for demonstration, it may be slightly different with the machine you have.

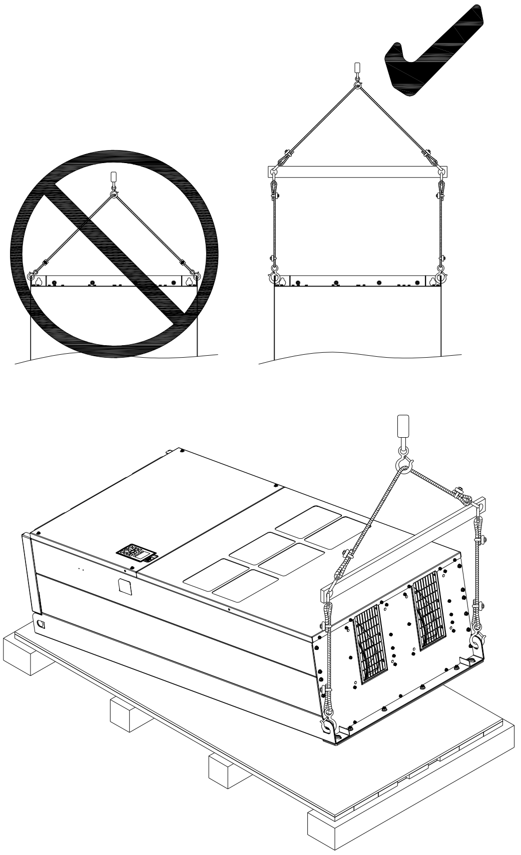


Figure 3-88

Weight

D0

VFDXXXXCPXXS-00: 27 kg / [59.5 lbs]

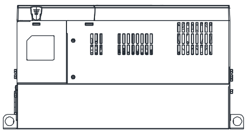


Figure 3-89

VFDXXXXCPXXS-21: 29 kg / [63.9 lbs]

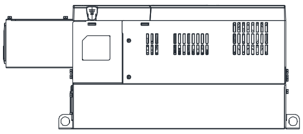


Figure 3-90

D

VFDXXXCPXXX-00: 37.6 kg / [82.9 lbs]
VFDXXXCP63A-00: 39.0 kg / [86.0 lbs]

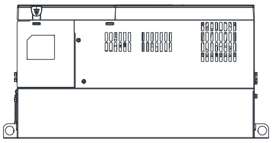


Figure 3-91

VFDXXXCPXXX-21: 40 kg / [88.2 lbs]
VFDXXXCP63A-21: 41.1 kg / [91.3 lbs]

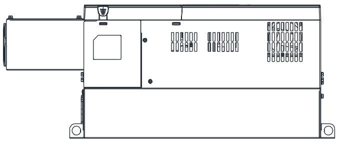


Figure 3-92

E

VFDXXXCPXXX-00: 63.6 kg / [140.2 lbs]
VFDXXXCP63A-00: 61.0 kg / [134.5 lbs]

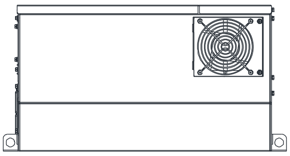


Figure 3-93

VFDXXXCPXXX-21: 66 kg / [145.5 lbs]
VFDXXXCP63A-21: 63.4 kg / [139.8 lbs]

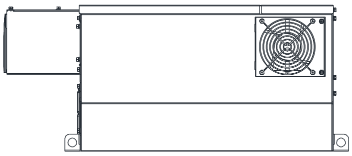


Figure 3-94

F

VFDXXXCPXXX-00: 85 kg / [187.2 lbs]
VFDXXXCP63A-00: 88.0 kg / [194.0 lbs]

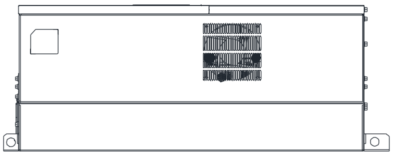


Figure 3-95

VFDXXXCPXXX-21: 88 kg / [193.8 lbs]
VFDXXXCP63A-21: 91.0 kg / [200.7 lbs]

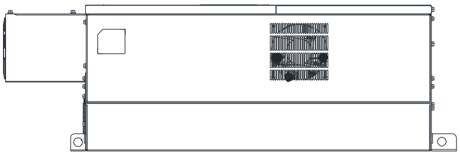


Figure 3-96

G

VFDXXXCPXXX-00: 130 kg / [286.5 lbs]
VFDXXXCP63A-00: 135.0 kg / [297.6 lbs]

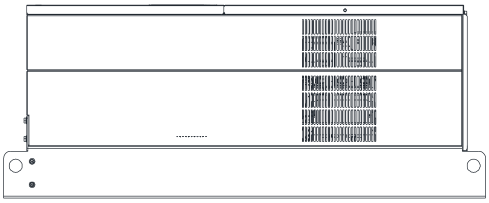


Figure 3-97

VFDXXXCPXXX-21: 138 kg / [303.9 lbs]
VFDXXXCP63A-21: 143.0 kg / [315.3 lbs]

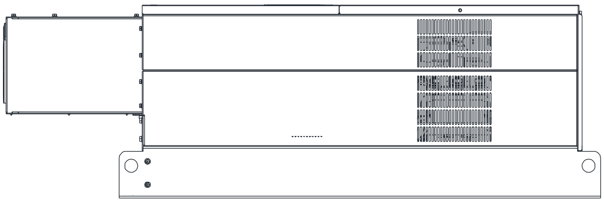


Figure 3-98

VFDXXXXCP43A-00: 244 kg / [537.9 lbs]
VFD5600CP43A-00, VFD6300CP43A-00: 270 kg / [595.2 lbs]
VFDXXXXCP63A-00: 243.0 kg / [535.7 lbs]

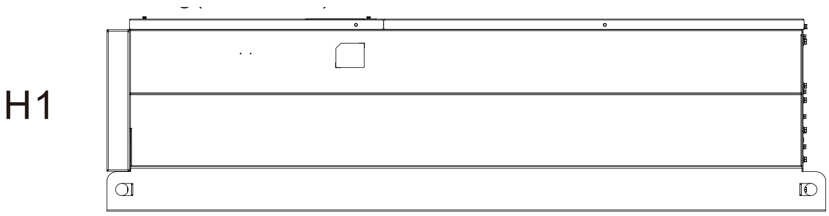


Figure 3-99

VFDXXXXCP43C-00: 260 kg / [573.2 lbs]

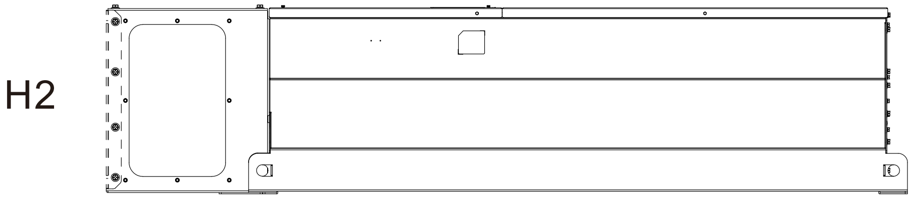


Figure 3-100

VFDXXXXCP63A-21: 251.0 kg / [553.5 lbs]

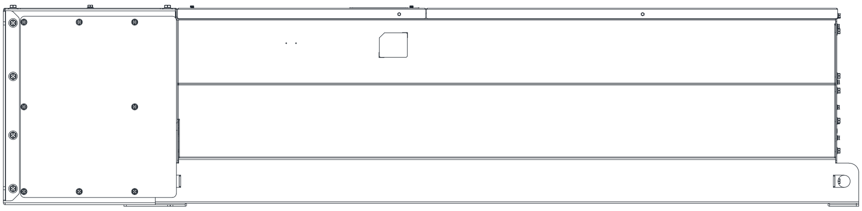


Figure 3-101

VFDXXXXCP43C-21: 269 kg / [593.0 lbs]

VFD5600CP43C-21, VFD6300CP43C-21: 295 kg / [650.4 lbs]

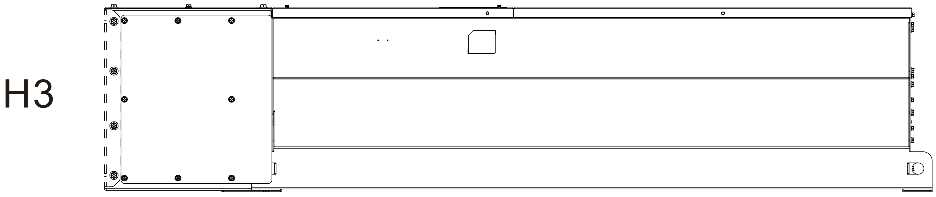


Figure 3-102

Chapter 4 Wiring

After removing the front cover, please check if the power and control terminals are clearly noted. Please read following precautions to avoid wiring mistakes.

DANGER

☑ It is crucial to cut off the AC motor drive power before any wiring installation are made. A charge may still remain in the DC BUS capacitors with hazardous voltages even if the power has been turned off. Therefore, it is suggested for users to measure the remaining voltage by DC voltage meter before wiring. For your personnel safety, please do not perform any wiring before the voltage drops to a safe level < 25 V_{DC}. Wiring installation with remaining voltage condition may cause sparks and short circuit.

☑ Only qualified personnel familiar with AC motor drives is allowed to perform installation, wiring and commissioning. Make sure the power is turned off before wiring to prevent electric shock.

☑ Make sure that power is only applied to the R/L1, S/L2, and T/L3 terminals. Failure to comply may result in damage to the equipment. The voltage and current should lie within the range as indicated on the nameplate (Chapter 1-1 Nameplate Information).

☑ All the units must be grounded directly to a common ground terminal to prevent lightning strike or electric shock.

☑ Please make sure to fasten the screw of the main circuit terminals to prevent sparks which is made by the loose screws due to vibration.

CAUTION

☑ When wiring, please choose the wires with specification that complies with local regulation for your personnel safety.

☑ Check following items after finishing the wiring:

1. Are all connections correct?
2. Any loosen wires?
3. Any short-circuits between the terminals or to ground?

4-1 System Wiring Diagram

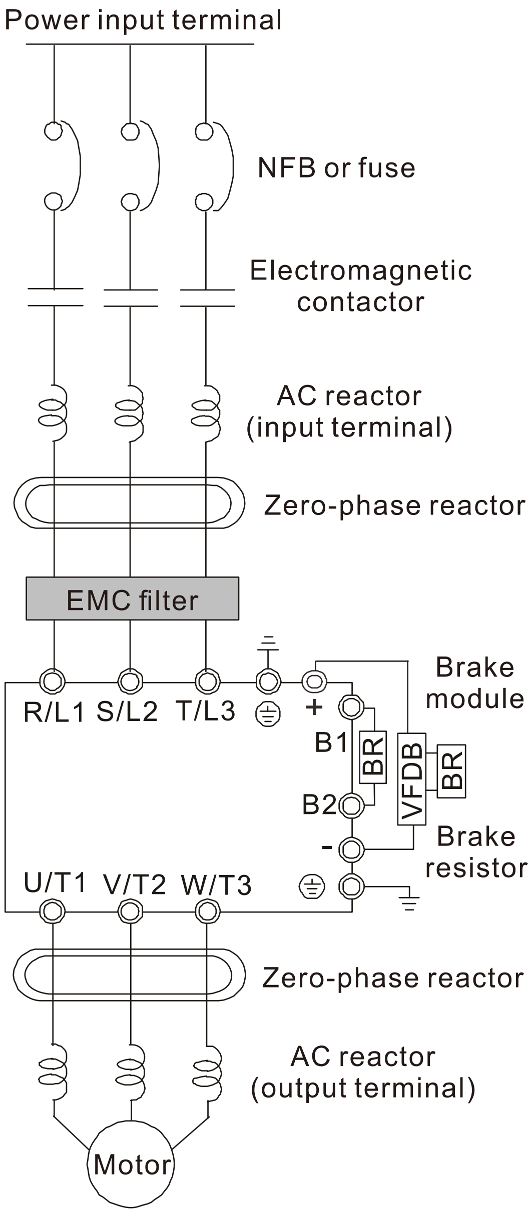


Figure 4-1

Power input terminal	Please refer to Chapter 9 Specification Table in user manual for detail.
NFB or fuse	There may be a large inrush current during power on. Refer to 7-2 NFB to select a suitable NFB or 7-3 Fuse Specification Chart.
Electromagnetic contactor	Switching the power ON/OFF before the magnetic contactor more than 1 x per hour can cause damage to the drive.
AC reactor (input terminal)	When the mains power capacity is > 500 kVA or when the drive is preceded by a capacitor bank, the instantaneous peaks voltages and current may destroy the drive. In that case it is recommended to install an AC input reactor which will also improve the power factor and harmonics. The cable between reactor and drive should be < 10 m. Please refer to Chapter 7-4.
Zero-phase reactor	Used to reduce radiated emission, especially in environments with audio devices, and reduce input and output side interference. The effective range is AM band to 10 MHz. Please refer to Chapter 7-5.
EMC filter	Can be used to reduce electromagnetic interference. Please refer to Chapter 7-6.
Brake module & Brake resistor (BR)	Used to shorten the deceleration time of the motor. Please refer to Chapter 7-1.
AC reactor (output terminal)	The wiring length of the motor will affect switching current peaks. It is recommended to install an AC output reactor when the motor wiring length exceeds the value listed in Chapter 7-4.

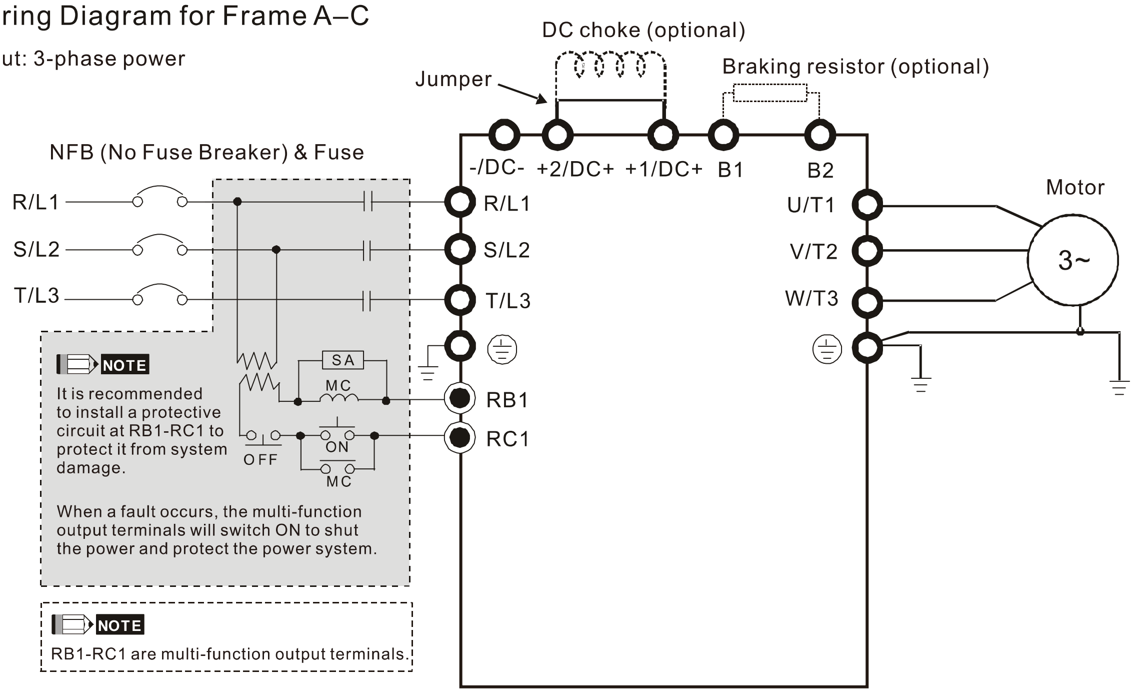
Table 4-1

NOTE Please refer to Chapter 4-2 Wiring Diagram for detailed wiring information.

4-2 Wiring

Wiring Diagram for Frame A–C

Input: 3-phase power



It is recommended to install a protective circuit at RB1-RC1 to protect it from system damage.

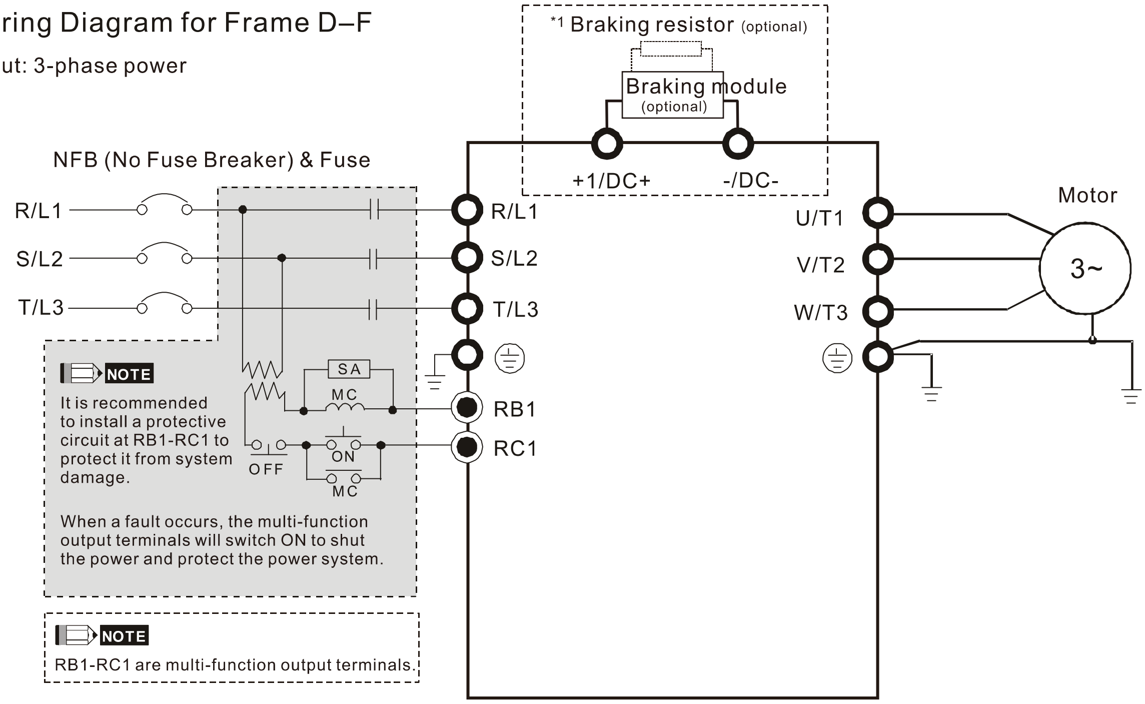
When a fault occurs, the multi-function output terminals will switch ON to shut the power and protect the power system.

RB1-RC1 are multi-function output terminals.

Figure 4-2

Wiring Diagram for Frame D–F

Input: 3-phase power



It is recommended to install a protective circuit at RB1-RC1 to protect it from system damage.

When a fault occurs, the multi-function output terminals will switch ON to shut the power and protect the power system.

RB1-RC1 are multi-function output terminals.

Figure 4-3

*1 Please refer to Chapter 7-1 for brake units and resistors selection

Wiring Diagram for Frame G–H

Input: 3-phase power

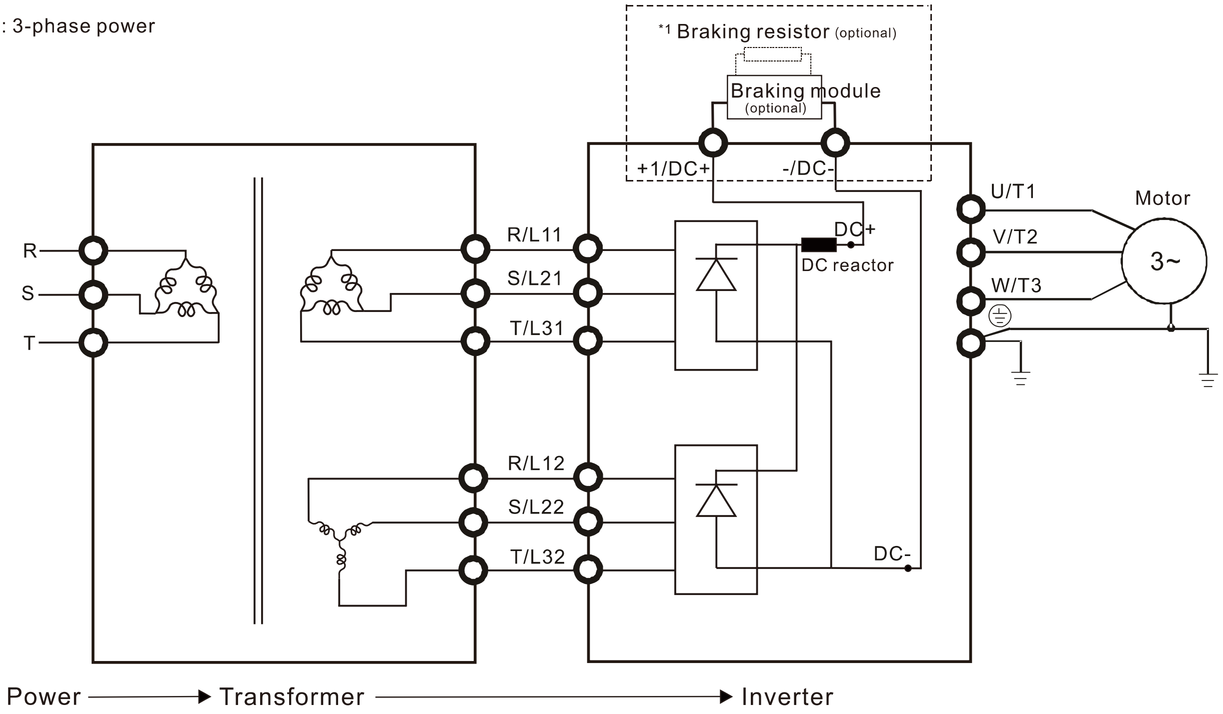


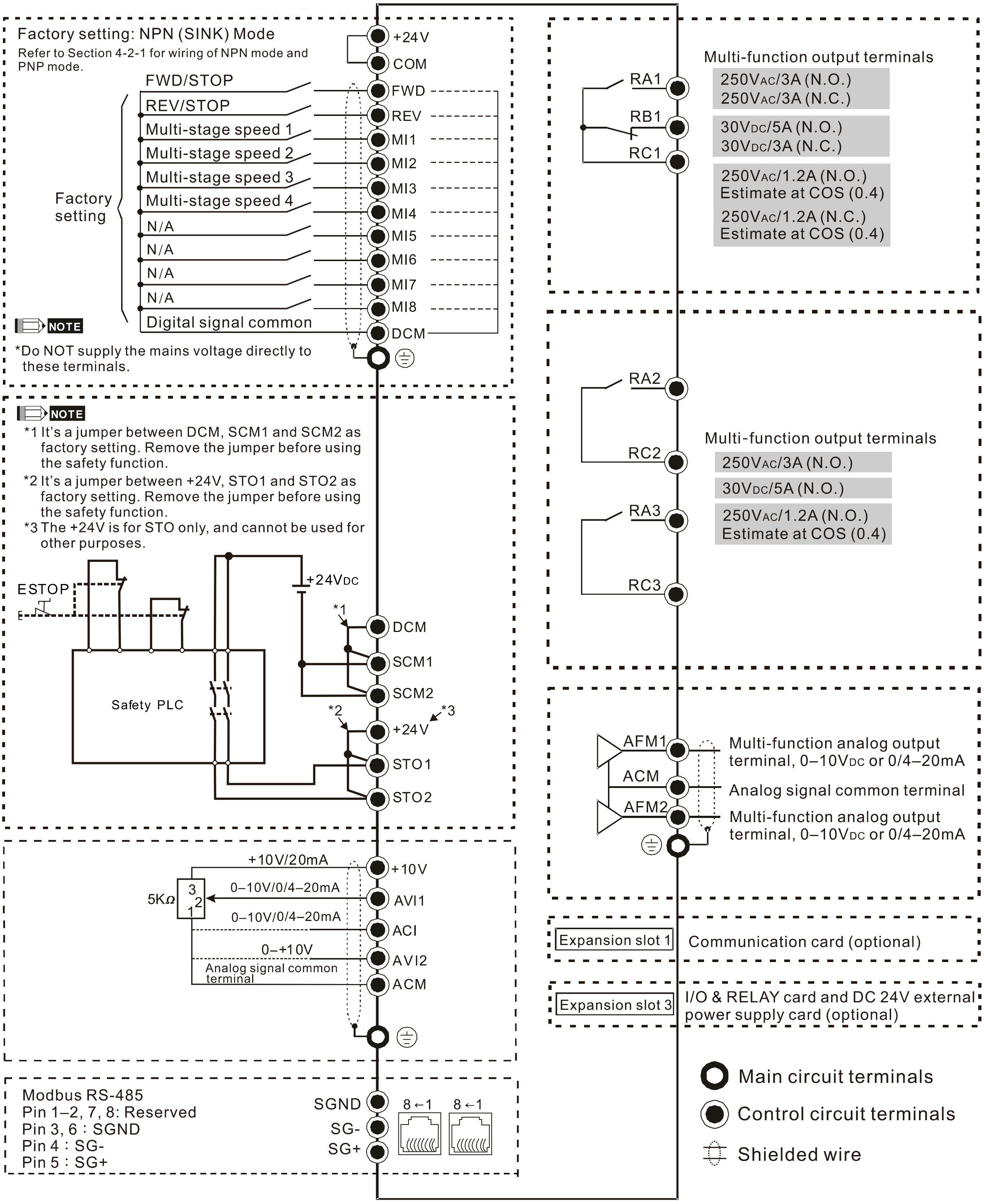
Figure 4-4

*1 Please refer to Chapter 7-1 for brake units and resistors selection

NOTE When wiring for 12 Pulse Input, please strictly follow above wiring diagram.

Wiring Diagram for Frame A–H

Input: 3-phase power



*Do NOT supply the mains voltage directly to these terminals.

NOTE

*1 It's a jumper between DCM, SCM1 and SCM2 as factory setting. Remove the jumper before using the safety function.

*2 It's a jumper between +24V, STO1 and STO2 as factory setting. Remove the jumper before using the safety function.

*3 The +24V is for STO only, and cannot be used for other purposes.

Figure 4-5

4-2-1 SINK (NPN) / SOURCE (PNP) Mode

① Sink Mode
with internal power (+24V$_{DC}$)

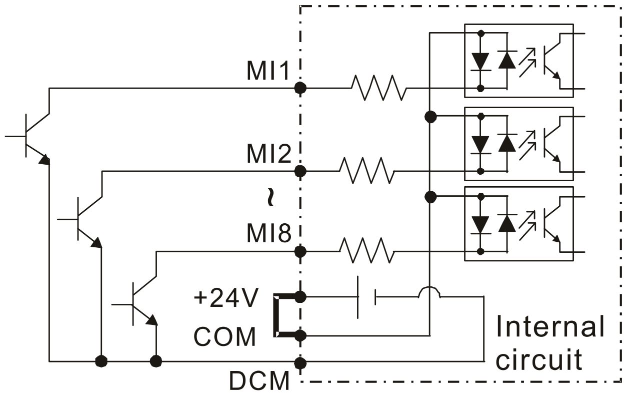


Figure 4-6

② Source Mode
with internal power (+24V$_{DC}$)

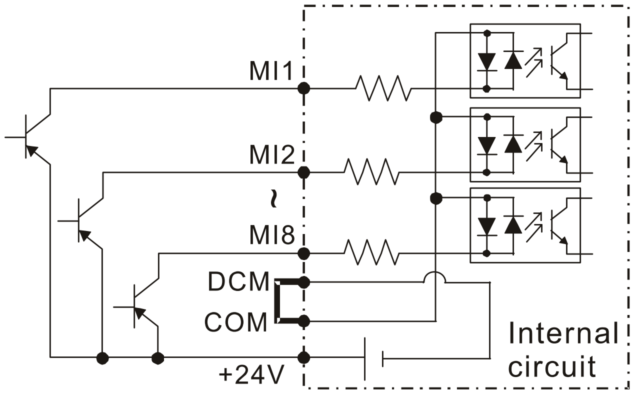


Figure 4-7

③ Sink Mode
with external power

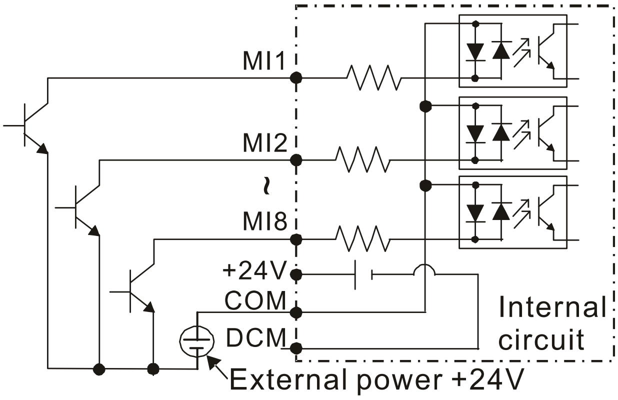


Figure 4-8

④ Source Mode
with external power

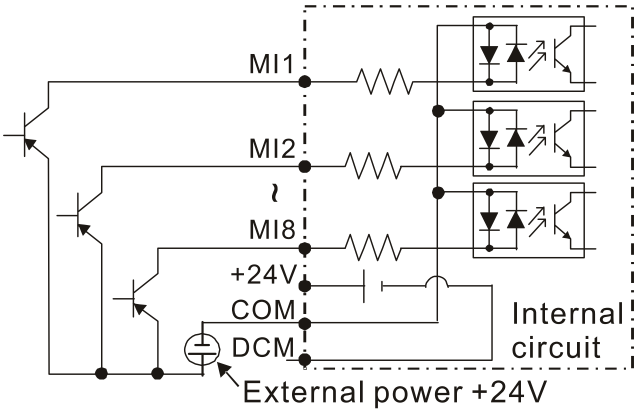


Figure 4-9

[This page intentionally left bank.]

Chapter 5 Main Circuit Terminals

DANGER

☑ Tighten the screws in the main circuit terminal to prevent sparks caused by screws loosened due to vibration.

☑ If necessary, use an inductive filter only at the motor output terminals U/T1, V/T2, W/T3 of the AC motor drive. Do NOT use phase-compensation capacitors or L-C (Inductance-Capacitance) or R-C (Resistance-Capacitance), unless approved by Delta.

☑ DO NOT connect phase-compensation capacitors or surge absorbers at the output terminals of AC motor drives.

☑ DO NOT connect brake resistors directly to [+1, -], [+2, -], [+1/DC+, -/DC-] to prevent damage to the drive or to the brake resistors.

☑ Ensure proper insulation of the main circuit wiring in accordance with the relevant safety regulations.

CAUTION

Main input power terminals

☑ Do not connect three-phase model to one-phase power. R/L1, S/L2 and T/L3 have no phase-sequence requirement; they can be connected in any sequence.

☑ Add a magnetic contactor (MC) to the power input wiring to cut off power quickly and reduce malfunctions when the AC motor drive protection function activates. Both ends of the MC should have an R-C surge absorber.

☑ Use voltage and current within the specification in Chapter 09. Refer to Chapter 09 Specifications for details.

☑ When using a general GFCI (Ground Fault Circuit Interrupter), select a current sensor with sensitivity of 200 mA or above, and its operation time should not be less than 0.1 second to avoid nuisance tripping.

☑ Use shield wire or conduit for the power wiring and ground the two ends of the shielding or tube.

☑ Do NOT run and stop the AC motor drives by turning the power ON and OFF. Run and stop the AC motor drives by sending the RUN and STOP commands through the control terminals or the keypad. If you still need to run and stop the AC motor drives by turning the power ON and OFF, do so no more often than ONCE per hour.

☑ To comply with UL standards, connect the drive to a three-phase three-wire or three-phase four-wire Wye system type of mains power system.

Output terminals for the main circuit

☑ Use well-insulated motors to prevent any electric leakage from motors.

☑ When the AC drive output terminals U/T1, V/T2 and W/T3 are connected to the motor terminals U/T1, V/T2, and W/T3 respectively, the motor rotates counterclockwise (as viewed on the shaft end of the motor, refer to the pointed direction in the figure below) when a forward operation command is received. To permanently reverse the direction of motor rotation, exchange any two of the motor leads.

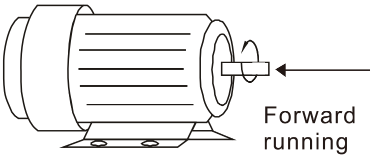


Figure 5-1

Terminals for connecting DC reactor, external brake resistor and DC circuit

☑ Use the terminals, as shown in Figure 5-2, to connect a DC reactor to improve the power factor. A jumper is connected to these terminals at the factory. Remove that jumper before connecting to a DC reactor.

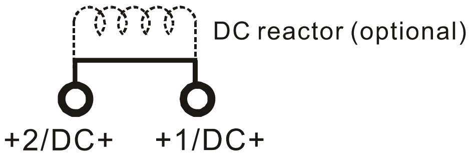


Figure 5-2

☑ Install and external brake resistor for applications in frequent deceleration to stop, short deceleration time (such as high frequency operation and heavy load operation), too low braking torque, or increased braking torque.

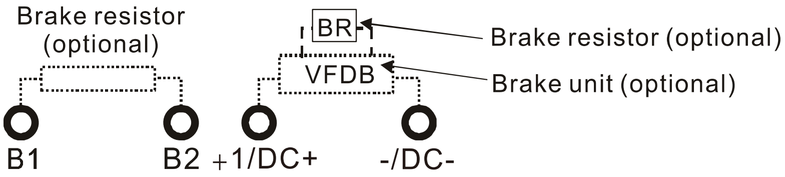


Figure 5-3

☑ For Frame A, B and C, connect the external brake resistor to B1 and B2 terminals of the AC motor drives.

☑ For those models without built-in brake resistor, connect external brake unit and brake resistor (both of them are optional) to increase brake torque.

☑ When the terminals +1, +2 and - are not used, leave the terminals open.

☑ When connecting DC+ and DC- in common DC bus applications, refer to Section 5-1 (Main Circuit Terminal) for the wiring terminal specification and the wire gauge information.

☑ Refer to the VFDB manual for more information on wire gauge when installing the brake unit.

5-1 Main Circuit Diagram

Wiring Diagram for Frame A~C

Input: 3-phase power

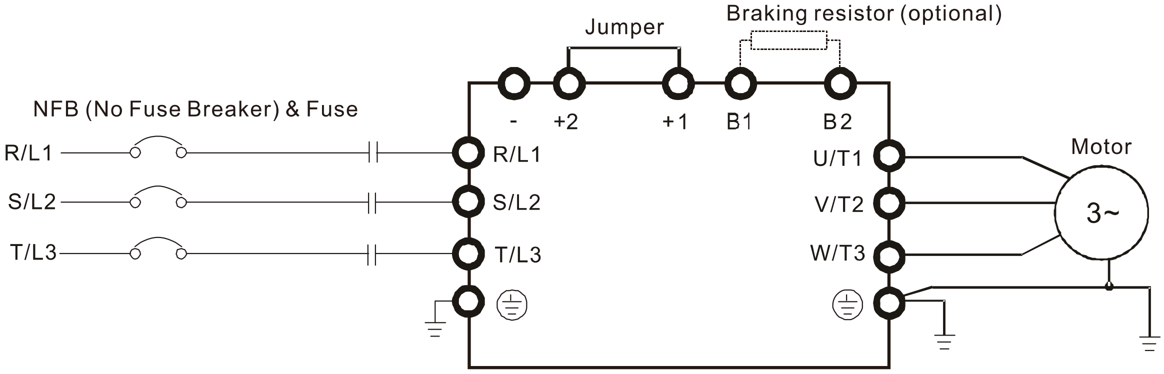


Figure 5-4

Wiring Diagram for Frame A~C

Input: 3-phase power

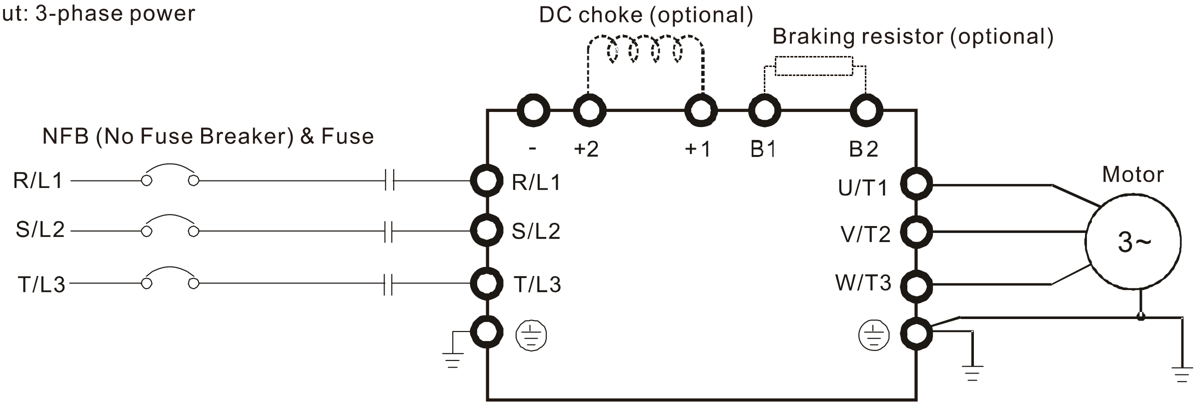


Figure 5-5

Wiring Diagram for Frame D~F

Input: 3-phase power

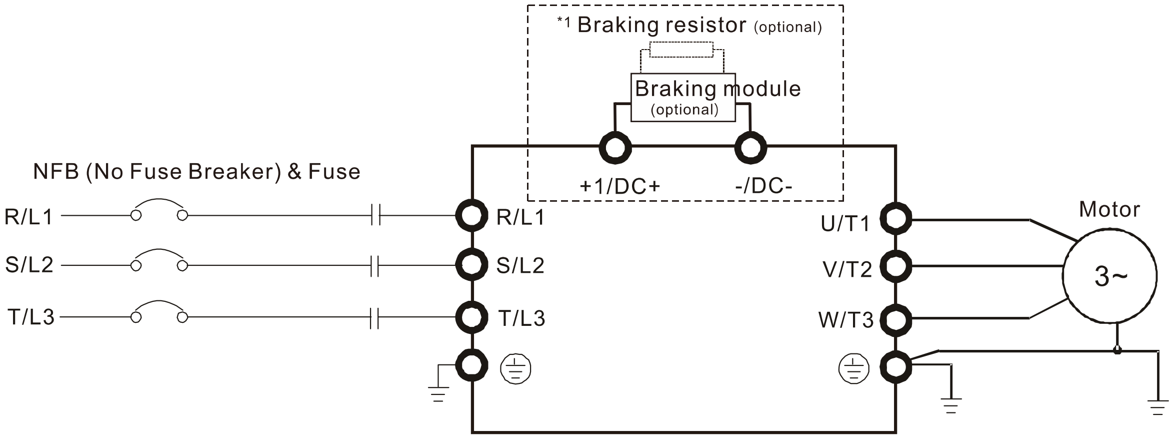


Figure 5-6

*1 Refer to Section 7-1 for brake units and resistors selection

Wiring Diagram for Frame G~H

Input: 3-phase power

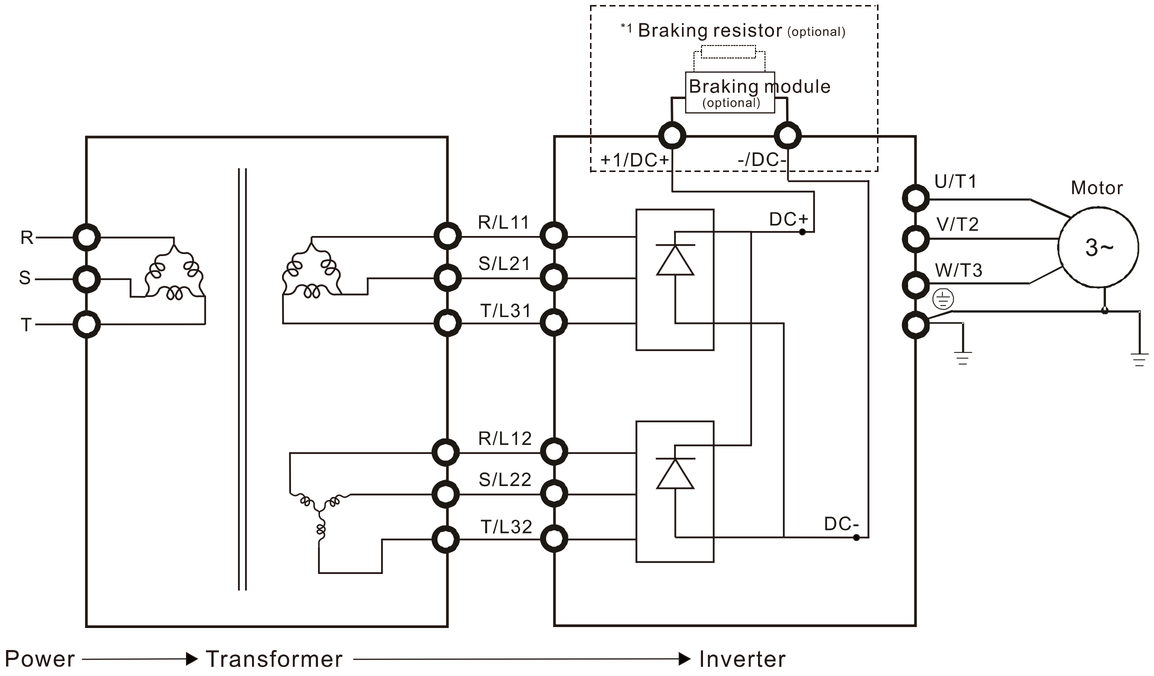


Figure 5-7

*1 Refer to Section 7-1 for brake units and resistors selection

Note: When wiring for 12 Pulse Input, strictly follow the wiring diagram above.

NOTE

- If the wiring between motor drive and motor is over 75 meters, please refer to Section 7-4 Specifications of limits for motor cable length.
- Remove the short circuit plate of Frame G and H if 12 pulse is implemented. Before implementing 12 pulse, consult Delta for more detail.

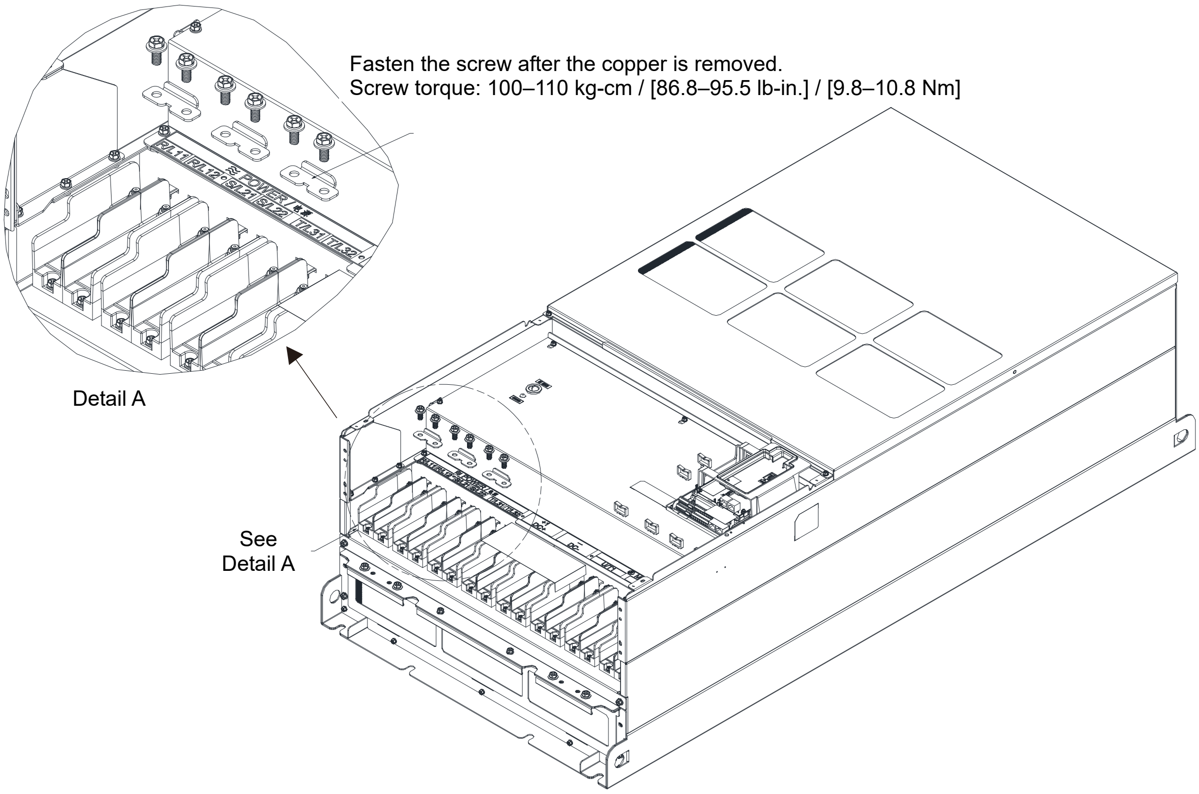

Fasten the screw after the copper is removed.
Screw torque: 100–110 kg-cm / [86.8–95.5 lb-in.] / [9.8–10.8 Nm]

Figure 5-8

Terminals	Descriptions
R/L1, S/L2, T/L3	AC line input terminals 3-phase
U/T1, V/T2, W/T3	AC drive output terminals for connecting 3-phase induction motor
+1, +2	Applicable to frame A–C Connections for DC reactor to improve the power factor. It needs to remove the jumper for installation.
+1/DC+, -/DC-	Connections for brake module (VFDB series) (for 230V models: ≤ 22 kW, built-in brake module) (for 460V models: ≤ 30 kW, built-in brake module) (for 690V models: ≤ 37 kW, built-in brake module) Common DC bus
B1, B2	Connections for brake resistor (optional)
⏚	Earth connection, please comply with local regulations.

5-2 Specifications of Main Circuit Terminals

- Use the specified ring lug for main circuit terminal wiring.
  See figure 5-9 and figure 5-10 for ring lug specifications. For other types of wiring, use the wires that comply with the local regulations.
- After crimping the wire to the ring lug (must be UL and CSA approved R/C (YDPU2)), install heat shrink tubing rated at a minimum of 600V_{AC} insulation over the live part. Refer to figure 5-10 below.

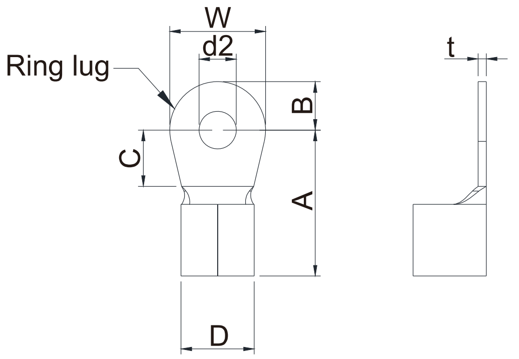


Figure 5-9

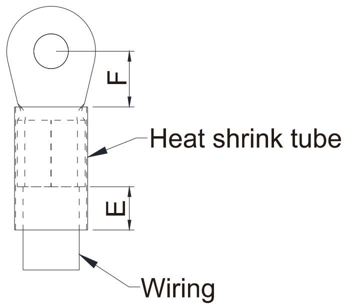


Figure 5-10

Dimensions of Ring Lug

The part number of the ring lugs (produced by K.S. Terminals Inc.) in the table below are for reference only. You can buy other ring lugs of your choice to match with different frame sizes.

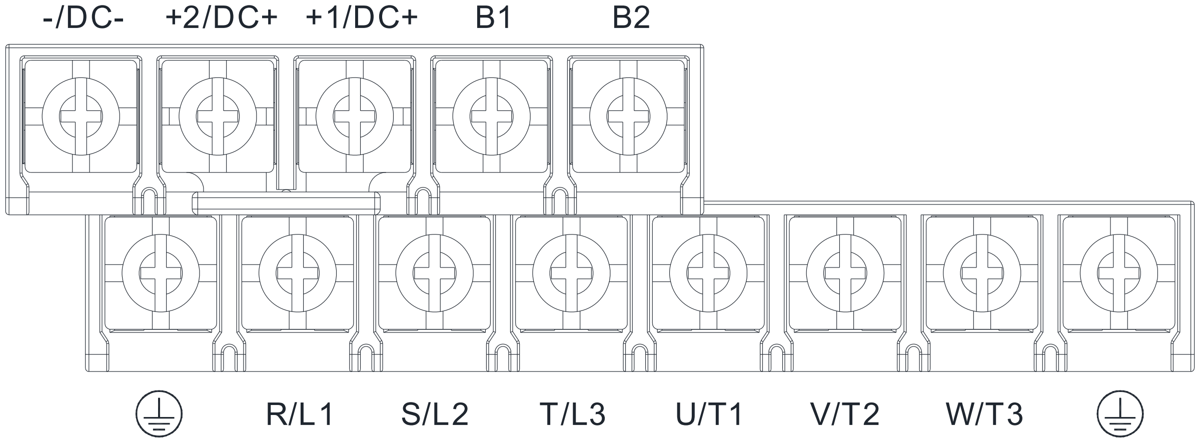
Frame	AWG	Kit P/N	A (MAX)	B (MAX)	C (MIN)	D (MAX)	d2 (MIN)	E (MIN)	F (MIN)	W (MAX)	t (MAX)
A	16	RNBL2-4	20	5	5.5	9	4.3	8	5.5	10	1.5
	14										
	12	RNBL5-4									
	10										
	8	RNBS8-4									
B	8	RNBM8-5	28.0	7.0	7.5	14.0	5.2	13.0	12.0	14.0	1.5
	6	RNB14-5									
	4	RNBS22-5									
C	6	RNB14-8	40	12	12.5	22	8.3	13	12.5	24	2.5
	4	RNB22-8									
	2	RNBS38-8									
	1/0	RNB60-8									
D0	4	RNB22-8	44.0	13.0	10.0	15.0	8.3	13.0	17.0	26.0	3.0
	2	RNBS38-8									
	1/0	SQNBS60-8	40.0	11.0	10.0	23.0	8.3	13.0	14.0*	24.0	4.5
	2/0	SQNBS80-8									
D	4	RNB22-8	50.0	16.0	10.0	27.0	8.3	13.0	14.0	28.0	6.0
	2	RNBS38-8									
	1/0	RNB60-8									
	2/0	RNB70-8									
	3/0	RNB80-8									
	4/0	SQNBS100-8									
	250MCM	SQNBS150-8									
	300MCM	SQNBS150-8									
E	4/0	RNB100-8	53.0	16.0	17.0	26.5	8.4	13.0	17.0	31.0	5.0
	3/0	RNB80-8									
	2/0	RNB70-8									
	1/0	RNB60-8									
F	3/0	RNB80-8	55.0	15.0	10.0	27.0	8.3	13.0	17.5	31.0	6.0
	4/0	SQNBS100-8									
	300MCM	SQNBS150-8									

Frame	AWG	Kit P/N	A (MAX)	B (MAX)	C (MIN)	D (MAX)	d2 (MIN)	E (MIN)	F (MIN)	W (MAX)	t (MAX)
G	1/0	SQNB60-6	54	15.5	18	26.5	8.2	13	18	31	3.5
	2/0	SQNBS80-8									
	3/0										
	4/0	SQNBS100-8									
	250MCM	SQNBS150-8									
	300MCM	SQNBS180-12	70	21	27	32.7	12.2	13	27	42	4.0
	400MCM	SQNBS200-12									
	500MCM										
H	3/0	SQNBS80-8	54	15.5	18	26.5	8.2	13	18	31	3.5
	4/0	SQNBS100-8									
	250MCM	SQNBS150-8									
	300MCM										
	350MCM										
	400MCM	SQNBS200-12	70.0	21.0	27.0	32.7	12.2	13.0	27.0	42.0	4.5
	500MCM	SQNBS200-12									
	600MCM	SQNBS325-12									

*F (MAX.) = 16.5 Unit: mm

*AWG: Refer to the table below for the wire size specification for models in each frame.

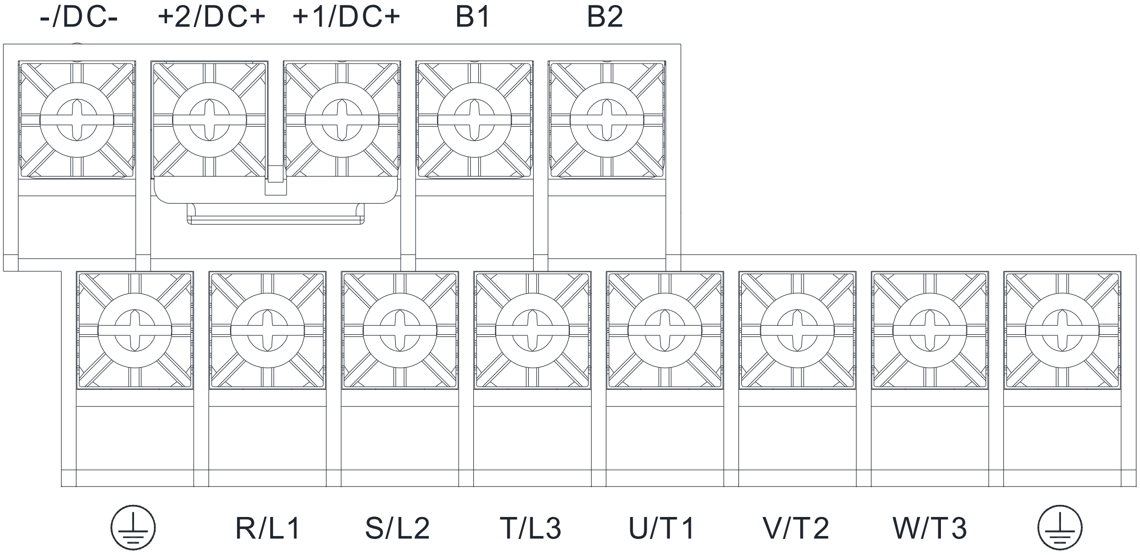
Frame A



- If you install at Ta 50°C environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations. Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, B1, B2, -/DC-, +2/DC+, +1/DC+			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD007CP23A-21	10 mm^2 [8 AWG]	2.5 mm^2 [14 AWG]	M4 20kg-cm [17.4lb-in.] [1.96Nm]	2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	M4 20kg-cm [17.4lb-in.] [1.96Nm]
VFD015CP23A-21		4.0 mm^2 [12 AWG]		4.0 mm^2 [12 AWG]	4.0 mm^2 [12 AWG]	
VFD022CP23A-21		6.0 mm^2 [10 AWG]		6.0 mm^2 [10 AWG]	6.0 mm^2 [10 AWG]	
VFD037CP23A-21		10.0 mm^2 [8 AWG]		10.0 mm^2 [8 AWG]	10.0 mm^2 [8 AWG]	
VFD055CP23A-21		10.0 mm^2 [8 AWG]		10.0 mm^2 [8 AWG]	10.0 mm^2 [8 AWG]	
VFD007CP43A-21		1.5 mm^2 [16 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD015CP43B-21		1.5 mm^2 [16 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD022CP43B-21		2.5 mm^2 [14 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD037CP43B-21		6.0 mm^2 [10 AWG]		6.0 mm^2 [10 AWG]	6.0 mm^2 [10 AWG]	
VFD040CP43A-21		6.0 mm^2 [10 AWG]		6.0 mm^2 [10 AWG]	6.0 mm^2 [10 AWG]	
VFD055CP43B-21		10.0 mm^2 [8 AWG]		10.0 mm^2 [8 AWG]	10.0 mm^2 [8 AWG]	
VFD075CP43B-21		10.0 mm^2 [8 AWG]		10.0 mm^2 [8 AWG]	10.0 mm^2 [8 AWG]	
VFD007CP4EA-21		1.5 mm^2 [16 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD015CP4EB-21		1.5 mm^2 [16 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD022CP4EB-21		2.5 mm^2 [14 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD037CP4EB-21		6.0 mm^2 [10 AWG]		6.0 mm^2 [10 AWG]	6.0 mm^2 [10 AWG]	
VFD040CP4EA-21		6.0 mm^2 [10 AWG]		6.0 mm^2 [10 AWG]	6.0 mm^2 [10 AWG]	
VFD055CP4EB-21		10.0 mm^2 [8 AWG]		10.0 mm^2 [8 AWG]	10.0 mm^2 [8 AWG]	
VFD075CP4EB-21		10.0 mm^2 [8 AWG]		10.0 mm^2 [8 AWG]	10.0 mm^2 [8 AWG]	
VFD015CP53A-21		2.5 mm^2 [14 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD022CP53A-21		2.5 mm^2 [14 AWG]		2.5 mm^2 [14 AWG]	2.5 mm^2 [14 AWG]	
VFD037CP53A-21		4.0 mm^2 [12 AWG]		4.0 mm^2 [12 AWG]	4.0 mm^2 [12 AWG]	

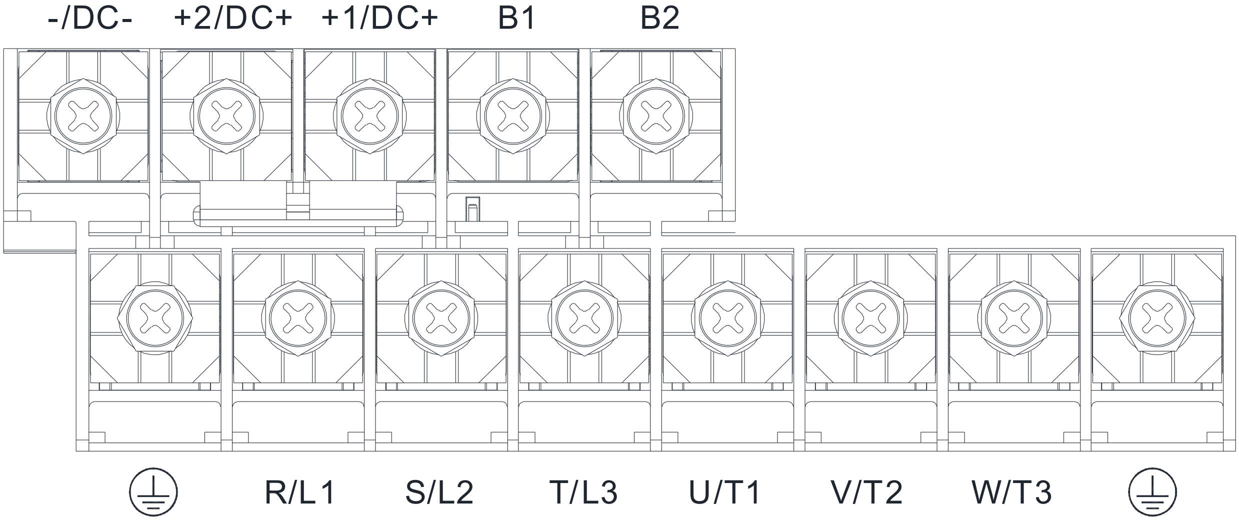
Frame B



- If you install at Ta 50°C environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD150CP23A-21 model: If you install at Ta 30°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations. Do not reduce the wire gauge when using higher-temperature resistant wire.
- Wire fix to pole +2/DC+ and +1/DC+: 45 kg-cm / [39.0 lb-in] / [4.42 Nm] (±10%)

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, B1, B2, -/DC-, +2/DC+, +1/DC+			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD075CP23A-21	25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	M5 35kg-cm [30.4lb-in.] [3.43Nm]	16 mm^2 [6 AWG]	16 mm^2 [6 AWG]	M5 35kg-cm [30.4lb-in.] [3.43Nm]
VFD110CP23A-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	
VFD150CP23A-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	
VFD110CP43B-21		10 mm^2 [8 AWG]		10 mm^2 [8 AWG]	10 mm^2 [8 AWG]	
VFD150CP43B-21		16 mm^2 [6 AWG]		16 mm^2 [6 AWG]	16 mm^2 [6 AWG]	
VFD185CP43B-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	
VFD110CP4EB-21		10 mm^2 [8 AWG]		10 mm^2 [8 AWG]	10 mm^2 [8 AWG]	
VFD150CP4EB-21		16 mm^2 [6 AWG]		16 mm^2 [6 AWG]	16 mm^2 [6 AWG]	
VFD185CP4EB-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	25 mm^2 [4 AWG]	
VFD055CP53A-21		6 mm^2 [10 AWG]		6 mm^2 [10 AWG]	6 mm^2 [10 AWG]	
VFD075CP53A-21		6 mm^2 [10 AWG]		6 mm^2 [10 AWG]	6 mm^2 [10 AWG]	
VFD110CP53A-21		10 mm^2 [8 AWG]		10 mm^2 [8 AWG]	10 mm^2 [8 AWG]	
VFD150CP53A-21		10 mm^2 [8 AWG]		10 mm^2 [8 AWG]	10 mm^2 [8 AWG]	

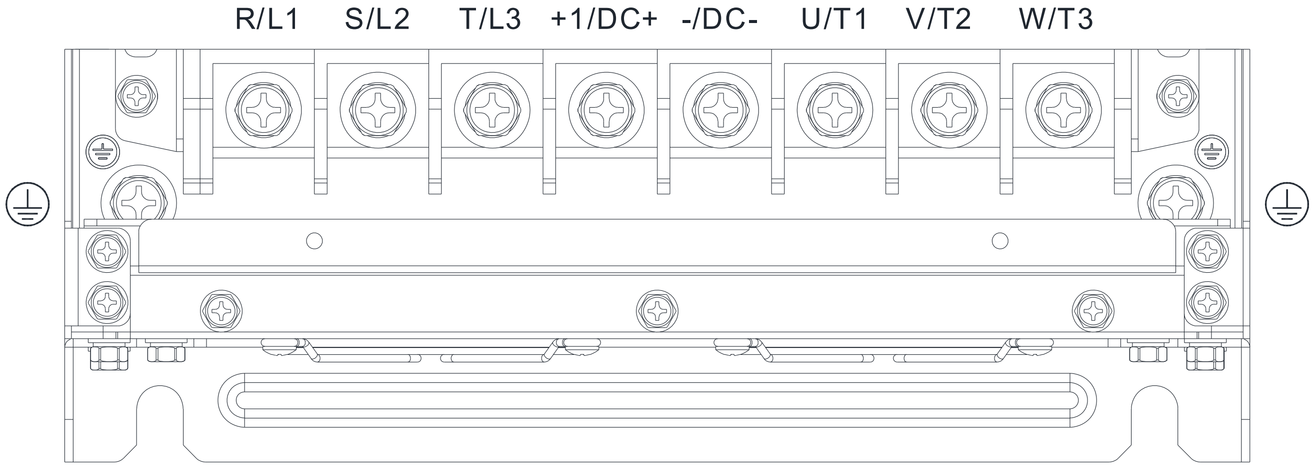
Frame C



- If you install at Ta 50°C environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD220CP23A-21 model, if you install at Ta 40°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD300CP23A-21 model, if you install at Ta 30°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations. Do not reduce the wire gauge when using higher-temperature resistant wire.
- Wire fix to pole +2/DC+ and +1/DC+: 90 kg-cm / [78.2 lb-in] / [8.83 Nm] (±10%)

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, B1, B2, -/DC-, +2/DC+, +1/DC+			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD185CP23A -21	50 mm^2 [1/0 AWG]	50 mm^2 [1/0 AWG]	M8 80kg-cm [69.4lb-in.] [7.84Nm]	50 mm^2 [1/0 AWG]	25 mm^2 [4 AWG]	M8 80kg-cm [69.4lb-in.] [7.84Nm]
VFD220CP23A-21		50 mm^2 [1/0 AWG]		50 mm^2 [1/0 AWG]	25 mm^2 [4 AWG]	
VFD300CP23A-21		50 mm^2 [1/0 AWG]		50 mm^2 [1/0 AWG]	25 mm^2 [4 AWG]	
VFD220CP43A-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	
VFD300CP43B-21		35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	
VFD370CP43B-21		50 mm^2 [1/0 AWG]		50 mm^2 [1/0 AWG]	25 mm^2 [4 AWG]	
VFD220CP4EA-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	
VFD300CP4EB-21		35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	
VFD370CP4EB-21		50 mm^2 [1/0 AWG]		50 mm^2 [1/0 AWG]	25 mm^2 [4 AWG]	
VFD185CP63A-21		10 mm^2 [8 AWG]		10 mm^2 [8 AWG]	10 mm^2 [8 AWG]	
VFD220CP63A-21		16 mm^2 [6 AWG]		16 mm^2 [6 AWG]	16 mm^2 [6 AWG]	
VFD300CP63A-21		25 mm^2 [4 AWG]		25 mm^2 [4 AWG]	16 mm^2 [6 AWG]	
VFD370CP63A-21		35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	

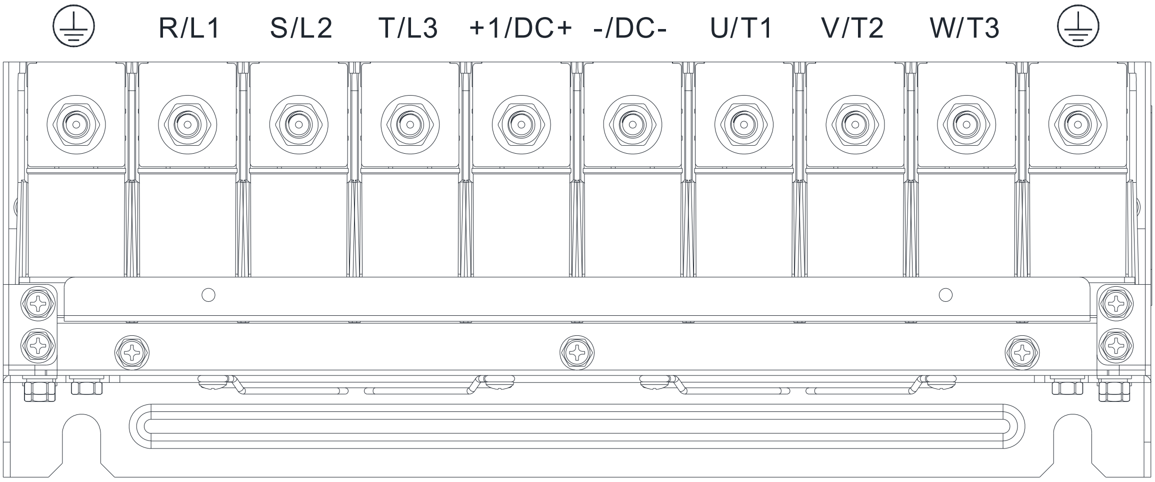
Frame D0



- If you install at Ta 50°C (for 460V model names with last digit -00) / 40°C (for 460V model names with last digit -21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C (for 460V model names with last digit -00) / 40°C (for 460V model names with last digit -21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD550CP43S-00 model: If you install at Ta 45°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations.
  Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, -/DC-, +1/DC+			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD450CP43S-00	70 mm^2 [2/0 AWG]	70 mm^2 [2/0 AWG]	M8 80kg-cm [69.4lb-in.] [7.84Nm]	35mm^2 [2AWG]	25mm^2 [4AWG]	M8 80kg-cm [69.4lb-in.] [7.84Nm]
VFD550CP43S-00		70 mm^2 [2/0 AWG]				
VFD450CP43S-21		50 mm^2 [1 AWG]				
VFD550CP43S-21		70 mm^2 [2/0 AWG]				

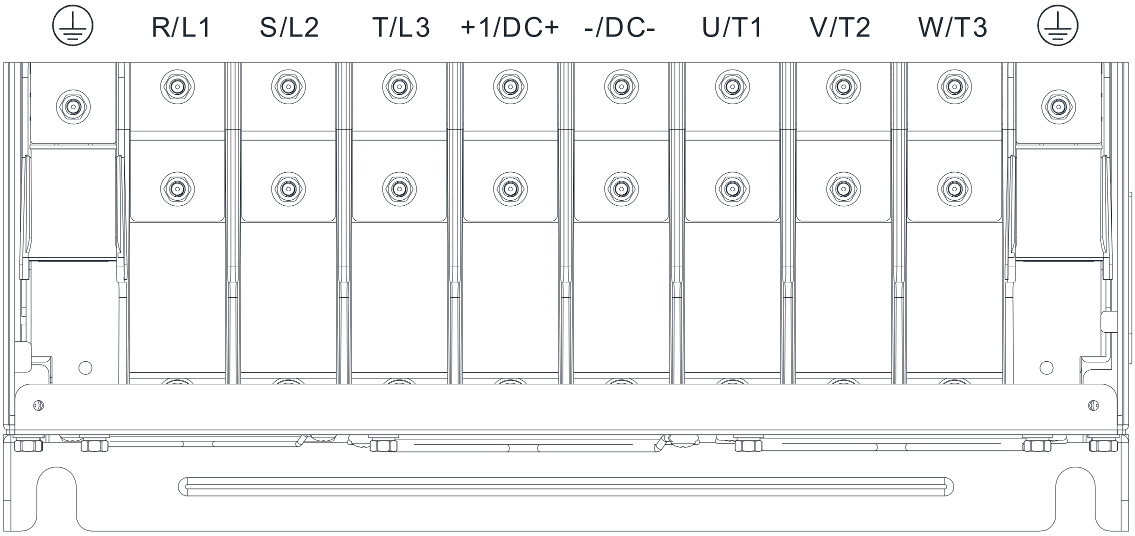
Frame D



- If you install at Ta 50°C (for 230V / 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 230V / 460V model names with last digit -21; for 690V model names end with 63A-21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C (for 230V / 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 230V / 460V model names with last digit -21; for 690V model names end with 63A-21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD450CP23A-00 and VFD900CP43A-00 models: If you install at Ta 45°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD450CP23A-21 and VFD900CP43A-21 models: If you install at Ta 30°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations. Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, DC-, DC+/+1, +2/B1, B2			Terminal⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD370CP23A-00	150 mm^2 [300 MCM]	120 mm^2 [250 MCM]	M8 180kg-cm [156.2lb-in.] [17.65Nm]	120 mm^2 [250 MCM]	70 mm^2 [2/0 AWG]	M8 180kg-cm [156.2lb-in.] [17.65Nm]
VFD450CP23A-00		150 mm^2 [300 MCM]		150 mm^2 [300 MCM]	95 mm^2 [3/0 AWG]	
VFD750CP43B-00		120 mm^2 [250 MCM]		120 mm^2 [250 MCM]	70 mm^2 [2/0 AWG]	
VFD900CP43A-00		150 mm^2 [300 MCM]		150 mm^2 [300 MCM]	95 mm^2 [3/0 AWG]	
VFD370CP23A-21	120 mm^2 [4/0 AWG]	120 mm^2 [4/0 AWG]		120 mm^2 [4/0 AWG]	70 mm^2 [2/0 AWG]	
VFD450CP23A-21		120 mm^2 [4/0 AWG]		120 mm^2 [4/0 AWG]	70 mm^2 [2/0 AWG]	
VFD750CP43B-21		120 mm^2 [4/0 AWG]		120 mm^2 [4/0 AWG]	70 mm^2 [2/0 AWG]	
VFD900CP43A-21		120 mm^2 [4/0 AWG]		120 mm^2 [4/0 AWG]	70 mm^2 [2/0 AWG]	
VFD450CP63A-00	150 mm^2 [300 MCM]	35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	
VFD550CP63A-00		35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	
VFD450CP63A-21		35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	
VFD550CP63A-21		35 mm^2 [2 AWG]		35 mm^2 [2 AWG]	16 mm^2 [6 AWG]	

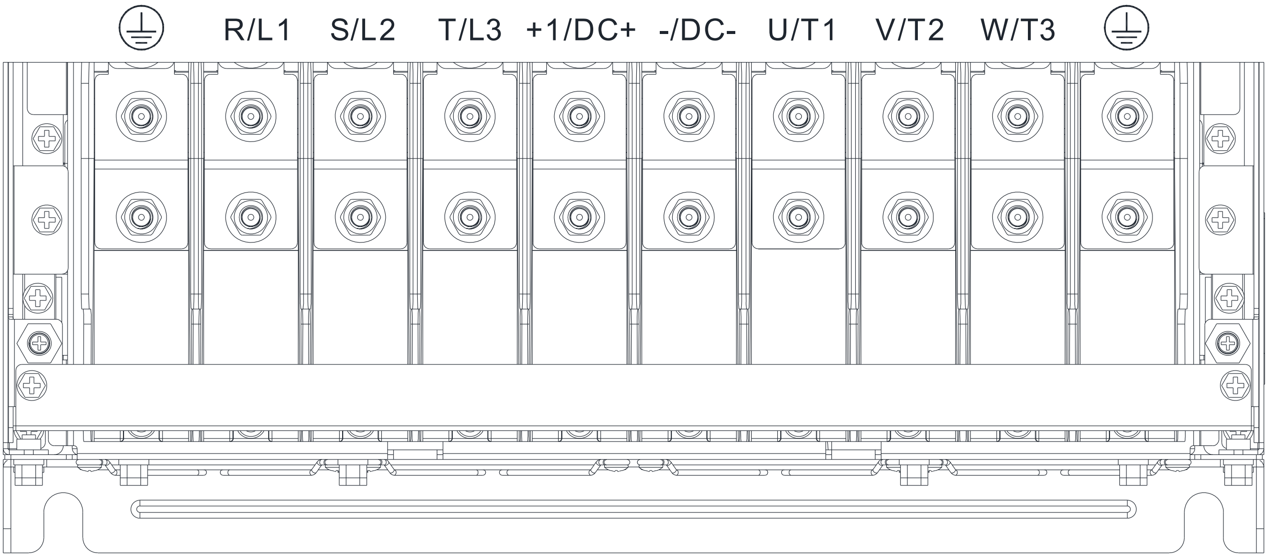
Frame E



- If you install at Ta 50°C (for 230V / 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 230V / 460V model names with last digit -21; for 690V model names end with 63A-21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C (for 230V / 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 230V / 460V model names with last digit -21; for 690V model names end with 63A-21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD900CP23A-00 model: If you install at Ta 40°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations.
  Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, +1/DC+, -/DC-			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD550CP23A-00	120 mm^{2}*2 [4/0 AWG*2]	95mm^{2}*2 [3/0 AWG*2]	M8 180kg-cm [156.2lb-in.] [17.65Nm]	95 mm^{2}*2 [3/0 AWG*2]	95mm^{2}*1 [3/0 AWG*1]	M8 180kg-cm [156.2lb-in.] [17.76Nm]
VFD750CP23A-00		120mm^{2}*2 [4/0 AWG*2]		120mm^{2}*2 [4/0 AWG*2]	120 mm^{2}*1 [4/0 AWG*1]	
VFD900CP23A-00		120mm^{2}*2 [4/0AWG*2]		120 mm^{2}*2 [4/0AWG*2]	120 mm^{2}*1 [4/0AWG*1]	
VFD1100CP43A-00		95mm^{2}*2 [3/0 AWG*2]		95 mm^{2}*2 [3/0 AWG*2]	95 mm^{2}*1 [3/0 AWG*1]	
VFD1320CP43A-00		120mm^{2}*2 [4/0 AWG*2]		120mm^{2}*2 [4/0 AWG*2]	120 mm^{2}*1 [4/0 AWG*1]	
VFD550CP23A-21		70mm^{2}*2 [2/0 AWG*2]		70 mm^{2}*2 [2/0 AWG*2]	70 mm^{2}*1 [2/0 AWG*1]	
VFD750CP43A-21		95mm^{2}*2 [3/0 AWG*2]		95 mm^{2}*2 [3/0 AWG*2]	95 mm^{2}*1 [3/0 AWG*1]	
VFD900CP43A-21		120mm^{2}*2 [4/0AWG*2]		120 mm^{2}*2 [4/0AWG*2]	120 mm^{2}*1 [4/0AWG*1]	
VFD1100CP23A-21		70mm^{2}*2 [2/0 AWG*2]		70 mm^{2}*2 [2/0 AWG*2]	70 mm^{2}*1 [2/0 AWG*1]	
VFD1320CP43A-21		95mm^{2}*2 [3/0 AWG*2]		95 mm^{2}*2 [3/0 AWG*2]	95 mm^{2}*1 [3/0 AWG*1]	
VFD750CP63A-00		25mm^{2}*2 [4 AWG*2]		25 mm^{2}*2 [4 AWG*2]	25 mm^{2}*1 [4 AWG*1]	
VFD900CP63A-00		35mm^{2}*2 [2 AWG*2]		35 mm^{2}*2 [2 AWG*2]	35 mm^{2}*1 [2 AWG*1]	
VFD1100CP63A-00		35mm^{2}*2 [2 AWG*2]		35 mm^{2}*2 [2 AWG*2]	35 mm^{2}*1 [2 AWG*1]	
VFD1320CP63A-00		50mm^{2}*2 [1/0 AWG*2]		50 mm^{2}*2 [1/0 AWG*2]	50 mm^{2}*1 [1/0 AWG*1]	
VFD750CP63A-21		25mm^{2}*2 [4 AWG*2]		25 mm^{2}*2 [4 AWG*2]	25 mm^{2}*1 [4 AWG*1]	
VFD900CP63A-21		35mm^{2}*2 [2 AWG*2]		35 mm^{2}*2 [2 AWG*2]	35 mm^{2}*1 [2 AWG*1]	
VFD1100CP63A-21		35mm^{2}*2 [2 AWG*2]		35 mm^{2}*2 [2 AWG*2]	35 mm^{2}*1 [2 AWG*1]	
VFD1320CP63A-21		50mm^{2}*2 [1/0 AWG*2]		50 mm^{2}*2 [1/0 AWG*2]	50 mm^{2}*1 [1/0 AWG*1]	

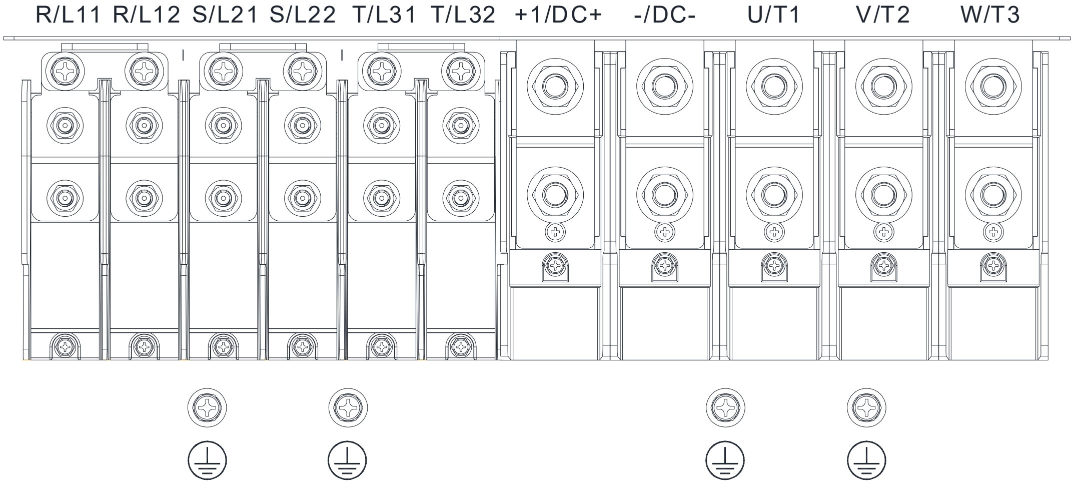
Frame F



- If you install at Ta 50°C (for 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 460V model names with last digit -21; for 690V model names end with 63A-21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C (for 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 460V model names with last digit -21; for 690V model names end with 63A-21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD1850CP43B-21 model: If you install at Ta 45°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD1850CP43B-21 model: If you install at Ta 30°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations. Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, -/DC-, +1/DC+			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD1600CP43A-00	150mm^2*2 [300MCM*2]	150mm^2*2 [300 MCM*2]	M8 180kg-cm [156.2lb-in.] [17.65Nm]	150mm^2*2 [300 MCM*2]	150mm^2*1 [300 MCM*1]	M8 180kg-cm [156.2lb-in.] [17.76Nm]
VFD1850CP43B-00		150mm^2*2 [300 MCM*2]		150mm^2*2 [300MCM*2]	150mm^2*1 [300MCM*1]	
VFD1600CP43A-21	120mm^2*2 [4/0AWG*2]	120mm^2*2 [4/0 AWG*2]		120mm^2*2 [4/0AWG*2]	120mm^2*1 [4/0AWG*1]	
VFD1850CP43B-21		120mm^2*2 [4/0 AWG*2]		120mm^2*2 [4/0AWG*2]	120mm^2*1 [4/0AWG*1]	
VFD1600CP63A-00	150mm^2*2 [300MCM*2]	70mm^2*2 [2/0 AWG*2]		70mm^2*2 [2/0 AWG*2]	70mm^2*1 [2/0 AWG*1]	
VFD2000CP63A-00		95mm^2*2 [3/0 AWG*2]		95mm^2*2 [3/0 AWG*2]	95mm^2*1 [3/0 AWG*1]	
VFD1600CP63A-21		70mm^2*2 [2/0 AWG*2]		70mm^2*2 [2/0 AWG*2]	70mm^2*1[2/0 AWG*1]	
VFD2000CP63A-21		95mm^2*2 [3/0 AWG*2]		95mm^2*2 [3/0 AWG*2]	95mm^2*1 [3/0 AWG*1]	

Frame G

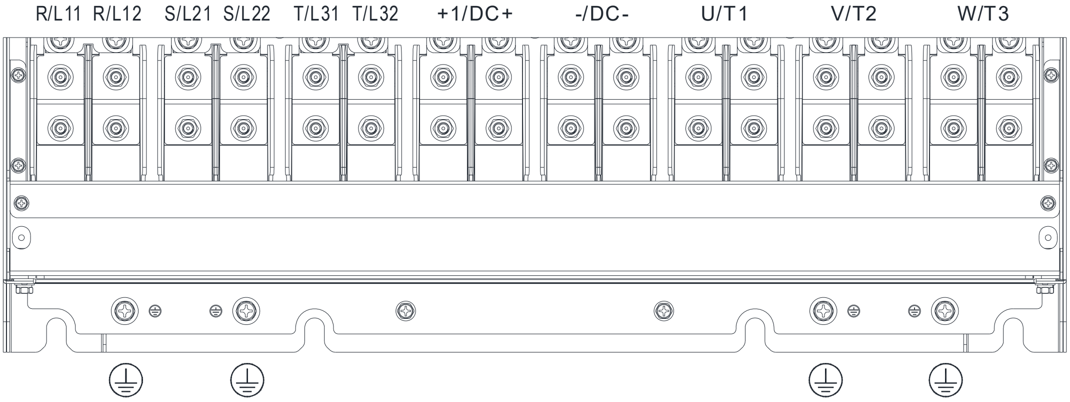


- If you install at Ta 50°C (for 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 460V model names with last digit -21; for 690V model names end with 63A-21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C (for 460V model names with last digit -00; for 690V model names end with 63A-00) / 40°C (for 460V model names with last digit -21; for 690V model names end with 63A-21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD2200CP43A-00 and VFD2500CP43A-00 models (Terminals U/T1, V/T2, W/T3, -/DC- and +1/DC+): If you install at Ta 45°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD2800CP43A-00 model (Terminals U/T1, V/T2, W/T3, -/DC- and +1/DC+): If you install at Ta 40 °C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations.
  Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L11, R/L12, S/L21, S/L22, T/L31, T/L32			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD2000CP43A-00	120mm^2*4 [250MCM*4]	70mm^2*4 [2/0AWG*4]	M8 180kg-cm [156.2lb-in.] [17.65Nm]	70mm^2*4 [2/0AWG*4]	70mm^2*2 [2/0AWG*2]	M8 180kg-cm [156.2lb-in.] [17.65Nm]
VFD2200CP43A-00		95mm^2*4 [3/0AWG*4]		95mm^2*4 [3/0AWG*4]	95mm^2*2 [3/0AWG*2]	
VFD2500CP43A-00		120mm^2*4 [4/0AWG*4]		120mm^2*4 [4/0AWG*4]	120mm^2*2 [4/0AWG*2]	
VFD2800CP43A-00		120mm^2*4 [4/0AWG*4]		120mm^2*4 [4/0AWG*4]	120mm^2*2 [4/0AWG*2]	
VFD2000CP43A-21		50mm^2*4 [1/0AWG*4]		50mm^2*4 [1/0AWG*4]	50mm^2*2 [1/0AWG*2]	
VFD2200CP43A-21		70mm^2*4 [2/0AWG*4]		70mm^2*4 [2/0AWG*4]	70mm^2*2 [2/0AWG*2]	
VFD2500CP43A-21		70mm^2*4 [2/0AWG*4]		70mm^2*4 [2/0AWG*4]	70mm^2*2 [2/0AWG*2]	
VFD2800CP43A-21		95mm^2*4 [3/0AWG*4]		95mm^2*4 [3/0AWG*4]	95mm^2*2 [3/0AWG*2]	
VFD2500CP63A-00	150mm^2*4 [300MCM*4]	50mm^2*4 [1/0AWG*4]		50mm^2*4 [1/0AWG*4]	50mm^2*2 [1/0AWG*2]	
VFD3150CP63A-00		50mm^2*4 [1/0AWG*4]		50mm^2*4 [1/0AWG*4]	50mm^2*2 [1/0AWG*2]	
VFD2500CP63A-21		50mm^2*4 [1/0AWG*4]		50mm^2*4 [1/0AWG*4]	50mm^2*2 [1/0AWG*2]	
VFD3150CP63A-21		50mm^2*4 [1/0AWG*4]		50mm^2*4 [1/0AWG*4]	50mm^2*2 [1/0AWG*2]	

Model Name	Main Circuit Terminals U/T1, V/T2, W/T3, +1/DC+, -/DC-			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD2000CP43A-00	240mm^2*2 [500MCM*2]	240mm^2*2 [400MCM*2]	M12 408kg-cm [354.1lb-in.] [39.98Nm]	240mm^2*2 [400MCM*2]	240mm^2*1 [400MCM*1]	M8 180kg-cm [156.2lb-in.] [17.65Nm]
VFD2200CP43A-00		240mm^2*2 [500MCM*2]		240mm^2*2 [500MCM*2]	240mm^2*1 [500MCM*1]	
VFD2500CP43A-00		240mm^2*2 [500MCM*2]		240mm^2*2 [500MCM*2]	240mm^2*1 [500MCM*1]	
VFD2800CP43A-00		240mm^2*2 [500MCM*2]		240mm^2*2 [500MCM*2]	240mm^2*1 [500MCM*1]	
VFD2000CP43A-21		150mm^2*2 [300MCM*2]		150mm^2*2 [300MCM*2]	150mm^2*1 [300MCM*1]	
VFD2200CP43A-21		240mm^2*2 [400MCM*2]		240mm^2*2 [400MCM*2]	240mm^2*1 [400MCM*1]	
VFD2500CP43A-21		240mm^2*2 [500MCM*2]		240mm^2*2 [500MCM*2]	240mm^2*1 [500MCM*1]	
VFD2800CP43A-21		240mm^2*2 [500MCM*2]		240mm^2*2 [500MCM*2]	240mm^2*1 [500MCM*1]	
VFD2500CP63A-00		120mm^2*2 [250MCM*2]		120mm^2*2 [250MCM*2]	120mm^2*1 [250MCM*1]	
VFD3150CP63A-00		150mm^2*2 [350MCM*2]		150mm^2*2 [350MCM*2]	150mm^2*1 [350MCM*1]	
VFD2500CP63A-21		120mm^2*2 [250MCM*2]		120mm^2*2 [250MCM*2]	120mm^2*1 [250MCM*1]	
VFD3150CP63A-21		150mm^2*2 [350MCM*2]		150mm^2*2 [350MCM*2]	150mm^2*1 [350MCM*1]	

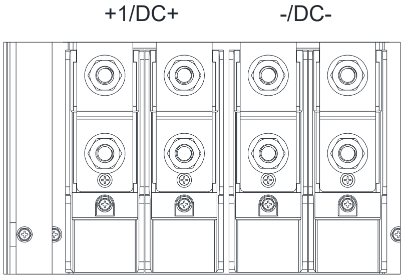
Frame H

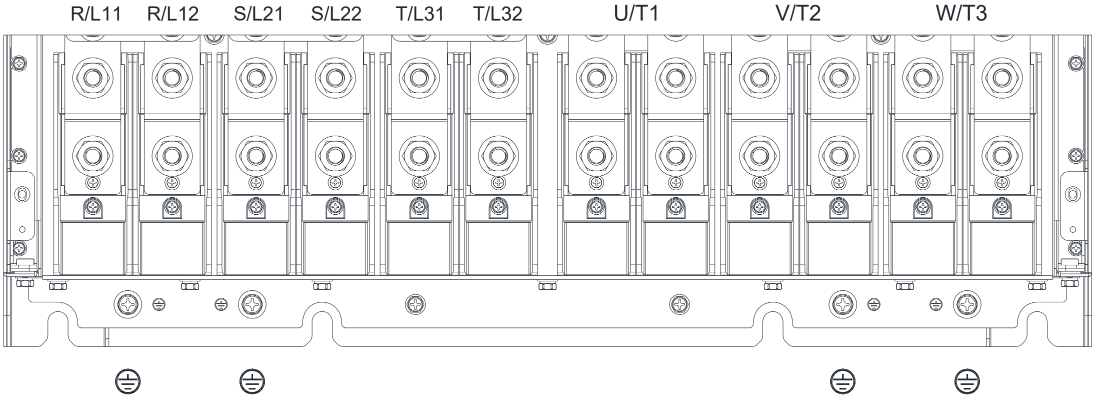


- If you install at Ta 50°C (for 460V model names with last digit A-00 / C-00; for 690V model names end with 63A-00) / 40°C (for 460V model names with last digit C-21; for 690V model names end with 63A-21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 75°C or 90°C.
- If you install at Ta 50°C (for 460V model names with last digit A-00 / C-00; for 690V model names end with 63A-00) / 40°C (for 460V model names with last digit C-21; for 690V model names end with 63A-21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD4000CP43A-00 and VFD4000CP43C-00 models: If you install at Ta 40°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- For VFD5000CP43A-00, VFD5000CP43C-00 and VFD5000CP43C-21 models: If you install at Ta 30°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations.
  Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L11, R/L12, S/L21, S/L22, T/L31, T/L32, U/T1, V/T2, W/T3, +1/DC+, -/DC-			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD3150CP43A-00	185mm^2*4 [350MCM*4]	150mm^2*4 [300MCM*4]	M8 180kg-cm [156.2lb-in.] [17.65Nm]	150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	M8 180kg-cm [156.2lb-in.] [17.65Nm]
VFD3550CP43A-00		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD4000CP43A-00		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD5000CP43A-00		185mm^2*4 [350MCM*4]		185mm^2*4 [350MCM*4]	185mm^2*2 [350MCM*2]	
VFD3150CP43C-00		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD3550CP43C-00		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD4000CP43C-00		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD5000CP43C-00		185mm^2*4 [350MCM*4]		185mm^2*4 [350MCM*4]	185mm^2*2 [350MCM*2]	
VFD3150CP43C-21		120mm^2*4 [4/0AWG*4]		120mm^2*4 [4/0AWG*4]	120mm^2*2 [4/0AWG*2]	
VFD3550CP43C-21		120mm^2*4 [250MCM*4]		120mm^2*4 [250MCM*4]	120mm^2*2 [250MCM*2]	
VFD4000CP43C-21		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD5000CP43C-21		185mm^2*4 [350MCM*4]		185mm^2*4 [350MCM*4]	185mm^2*2 [350MCM*2]	
VFD4000CP63A-00		95mm^2*4 [3/0AWG*4]		95mm^2*4 [3/0AWG*4]	95mm^2*2 [3/0AWG*2]	
VFD4500CP63A-00		95mm^2*4 [3/0AWG*4]		95mm^2*4 [3/0AWG*4]	95mm^2*2 [3/0AWG*2]	
VFD5600CP63A-00		120mm^2*4 [250MCM*4]		120mm^2*4 [250MCM*4]	120mm^2*2 [250MCM*2]	
VFD6300CP63A-00		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	
VFD4000CP63A-21		95mm^2*4 [3/0AWG*4]		95mm^2*4 [3/0AWG*4]	95mm^2*2 [3/0AWG*2]	
VFD4500CP63A-21		95mm^2*4 [3/0AWG*4]		95mm^2*4 [3/0AWG*4]	95mm^2*2 [3/0AWG*2]	
VFD5600CP63A-21		120mm^2*4 [250MCM*4]		120mm^2*4 [250MCM*4]	120mm^2*2 [250MCM*2]	
VFD6300CP63A-21		150mm^2*4 [300MCM*4]		150mm^2*4 [300MCM*4]	150mm^2*2 [300MCM*2]	

Frame H





- If you install at Ta 50°C (model names with last digit A-00) / 40°C (models names with last digit C-21) environment, use copper wires that have a voltage rating 600V and are temperature resistant to 70°C or 90°C.
- If you install at Ta 50°C (model names with last digit A-00) / 40°C (models names with last digit C-21) above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- If you install at Ta 30°C above environment, use copper wires that have a voltage rating 600V and are temperature resistant to 90°C or above.
- To be UL installation compliant, you must use copper wires when installing. The wire gauge is based on a temperature resistant of 75°C, in accordance with UL requirements and recommendations. Do not reduce the wire gauge when using higher-temperature resistant wire.

Model Name	Main Circuit Terminals R/L11, R/L12, S/L21, S/L22, T/L31, T/L32, U/T1, V/T2, W/T3, +1/DC+, -/DC-			Terminal ⏚		
	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)	Max. Wire Gauge	Min. Wire Gauge	Screw Spec. and Torque (±10%)
VFD5600CP43A-00	300mm^2*4 [600MCM*4]	240mm^2*4 [500MCM*4]	M12 408kg-cm [354.1lb-in.] [39.98Nm]	240mm^2*4 [500MCM*4]	240mm^2*2 [500MCM*2]	M8 180kg-cm [156.2lb-in.] [17.65Nm]
VFD6300CP43A-00		300mm^2*4 [600MCM*4]		300mm^2*4 [600MCM*4]	300mm^2*2 [600MCM*2]	
VFD5600CP43C-21	240mm^2*4 [500MCM*4]	240mm^2*4 [500MCM*4]		240mm^2*4 [500MCM*4]	240mm^2*2 [500MCM*2]	
VFD6300CP43C-21		240mm^2*4 [500MCM*4]		240mm^2*4 [500MCM*4]	240mm^2*2 [500MCM*2]	

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Chapter 6 Control Terminals

CAUTION

Analog input terminals (AVI1, AVI2, ACI, ACM)

☑ Analog input signals are easily affected by external noise. Use shielded wiring and keep it as short as possible (< 20 m) with proper grounding. If the noise is inductive, connecting the shield to the ACM terminal can reduce interference.

☑ Use twisted-pair wire for weak analog signals.

☑ If the analog input signals are affected by noise from the AC motor drive, connect a capacitor and a ferrite core as shown in Figure 6-1.

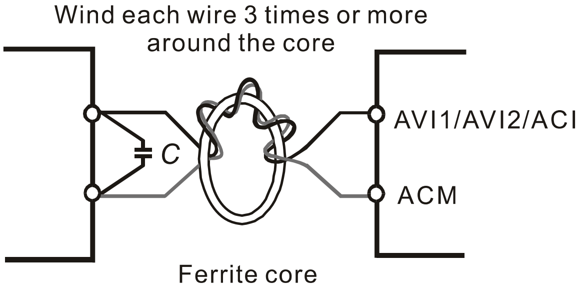


Figure 6-1

Contact input terminals (FWD, REV, MI1–MI8, COM)

☑ The “COM” terminal is a common terminal of the photo-coupler in all the wiring methods.

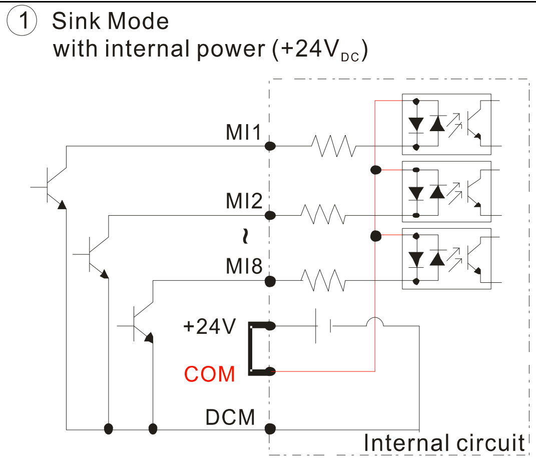


Figure 6-2

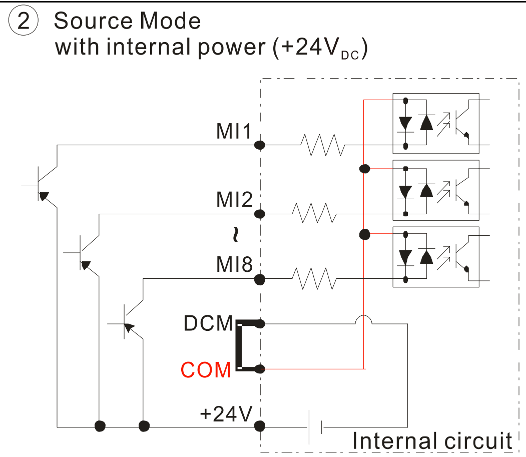


Figure 6-3

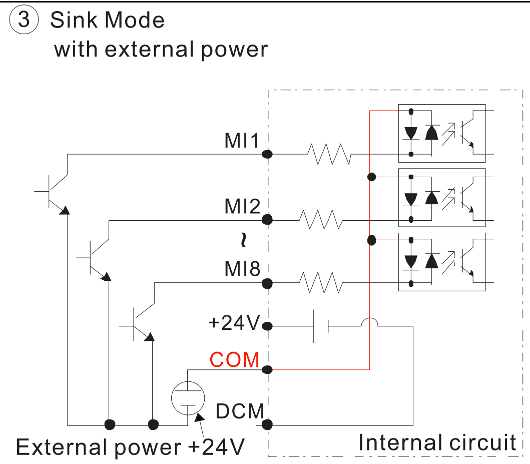


Figure 6-4

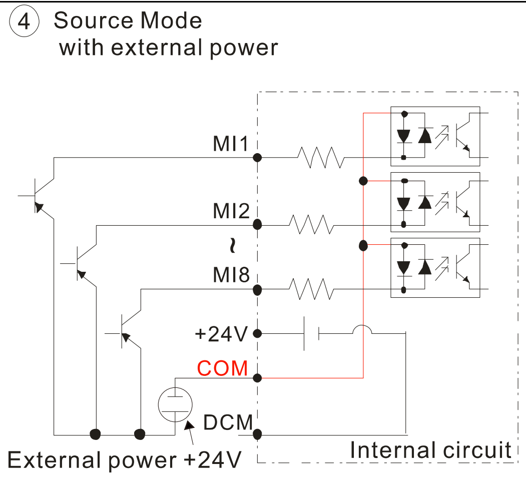


Figure 6-5

	☑ When the photo coupler uses the internal power supply, the switch connection for Sink and Source modes shows as Figure 6-2 and Figure 6-3: MI-DCM: Sink mode MI-+24V: Source mode ☑ When the photo coupler uses the external power supply, remove the short-circuit cable between +24V and COM terminals. The switch connection for Sink and Source modes shows as Figure 6-4 and Figure 6-5: The “+” of 24V connecting to “COM: Sink mode The “-“ of 24V connecting to COM: Source mode

6-1 Remove the Cover for Wiring

Remove the top cover before wiring the multi-function input and output terminals,

NOTE The drive appearances shown in the figures are for reference only, a real drive may look different.

Frame A & B

Applicable models:

VFD007CP23A-21; VFD015CP23A-21; VFD022CP23A-21; VFD037CP23A-21; VFD055CP23A-21; VFD007CP43A-21; VFD015CP43B-21; VFD022CP43B-21; VFD037CP43B-21; VFD040CP43A-21; VFD055CP43B-21; VFD075CP43B-21; VFD007CP4EA-21; VFD015CP4EB-21; VFD022CP4EB-21; VFD037CP4EB-21; VFD040CP4EB-21; VFD055CP4EB-21; VFD075CP4EB-21; VFD015CP53A-21; VFD022CP53A-21; VFD037CP53A-21; VFD075CP23A-21; VFD110CP23A-21; VFD150CP23A-21; VFD110CP43B-21; VFD150CP43B-21; VFD185CP43B-21; VFD110CP4EB-21; VFD150CP4EB-21; VFD185CP4EB-21; VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21; VFD150CP53A-21

Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
Loosen the screw and press the tabs on both sides to remove the cover.

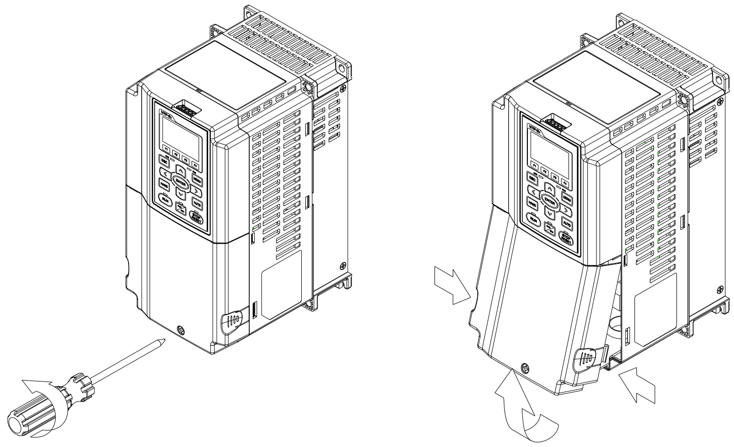


Figure 6-6

Frame C

Applicable models:

VFD185CP23A-21; VFD220CP23A-21; VFD300CP23A-21; VFD220CP43A-21; VFD300CP43B-21; VFD370CP43B-21; VFD220CP4EA-21; VFD300CP4EB-21; VFD370CP4EB-21; VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21

Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
Loosen the screws and press the tabs on both sides to remove the cover.

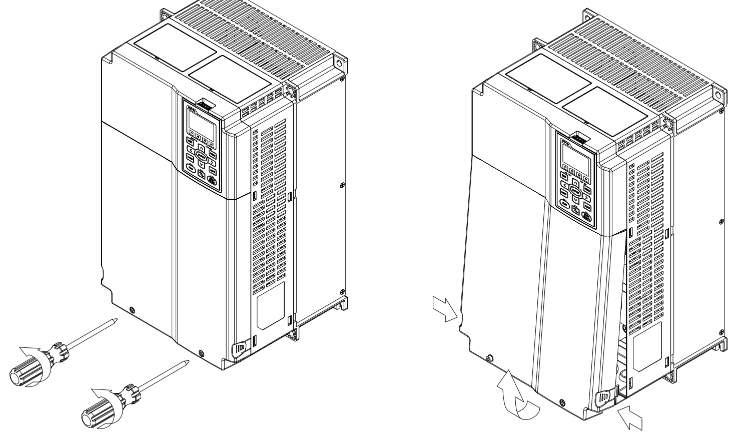


Figure 6-7

Frame D0 & D

Applicable models:
VFD450CP43S-00; VFD550CP43S-00; VFD450CP43S-21; VFD550CP43S-21; VFD370CP23A-00/-21; VFD450CP23A-00/-21; VFD750CP43B-00/-21; VFD900CP43A-00/-21; VFD450CP63A-00/-21; VFD550CP63A-00/-21

Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
To remove the cover, lift it slightly and pull outward.
Loosen the screws and press the tabs on both sides to remove the cover.

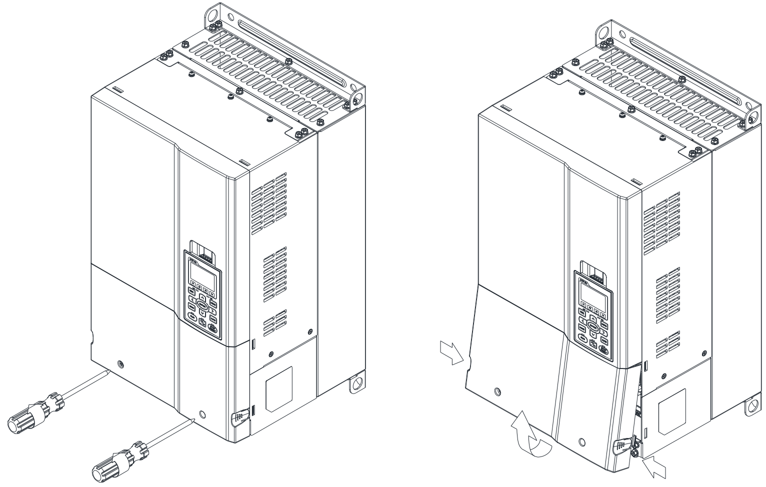


Figure 6-8

Frame E

Applicable models:
VFD550CP23A-00/-21; VFD750CP23A-00/-21; VFD900CP23A-00/-21; VFD1100CP43A-00/-21; VFD1320CP43B-00/-21; VFD750CP63A-00/-21; VFD900CP63A-00/-21; VFD1100CP63A-00/-21; VFD1320CP63B-21

Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
To remove the cover, lift it slightly and pull outward.

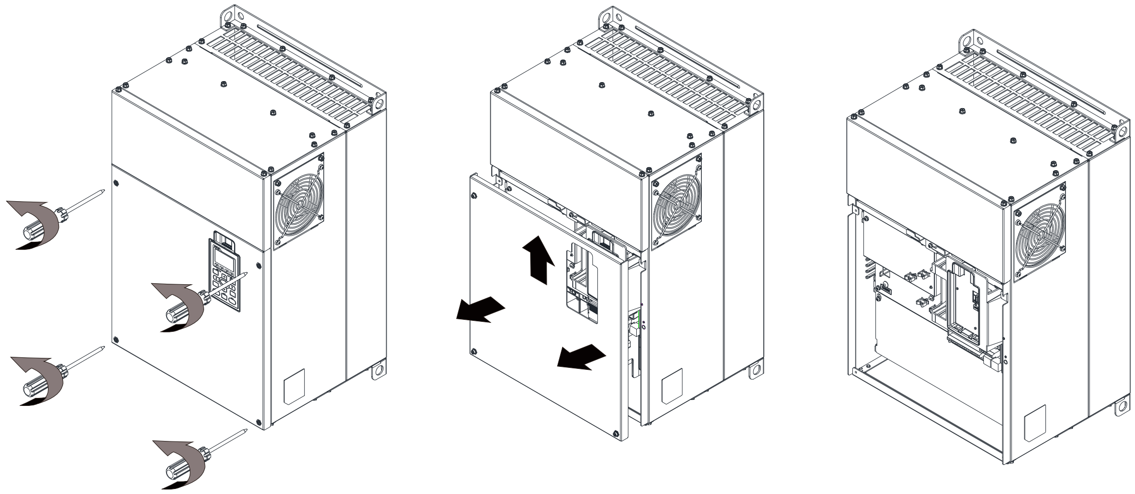


Figure 6-9

Frame F

Applicable models:
VFD1600CP43A-00/-21; VFD1850CP43B-00/-21; VFD1600CP63A-00/-21; VFD2000CP63A-00/-21

Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
To remove the cover, lift it slightly and pull outward

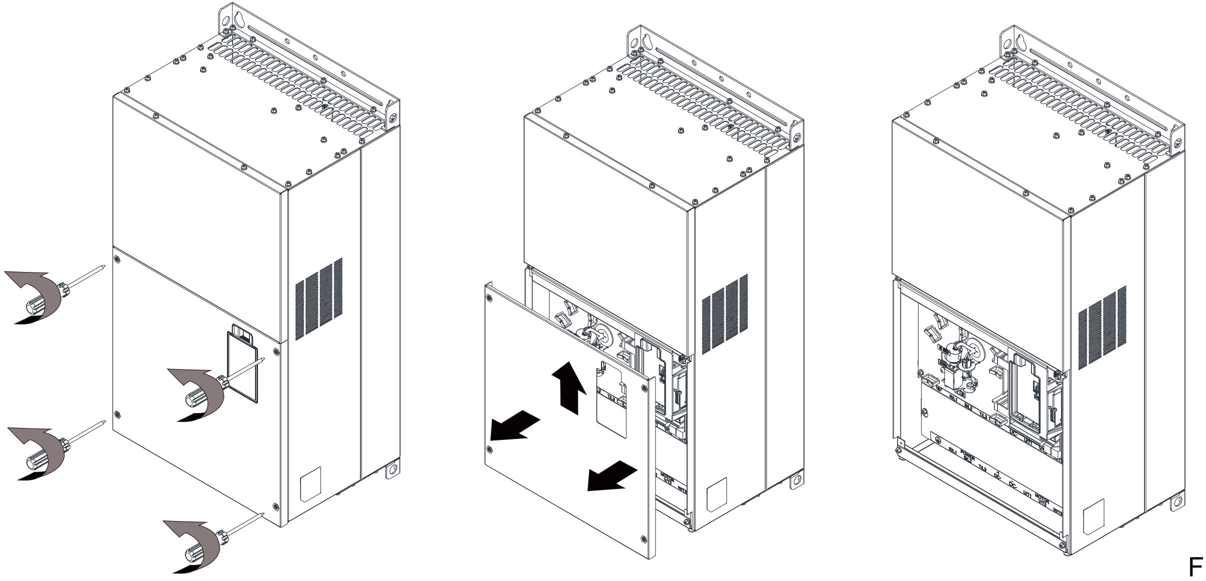


Figure 6-10

Frame G

Applicable models:
VFD2000CP43A-00/-21; VFD2200CP43A-00/-21; VFD2500CP43A-00/-21; VFD2800CP43A-00/-21;
VFD2500CP63A-00/-21; VFD3150CP63A-00/-21

Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
To remove the cover, lift it slightly and pull outward

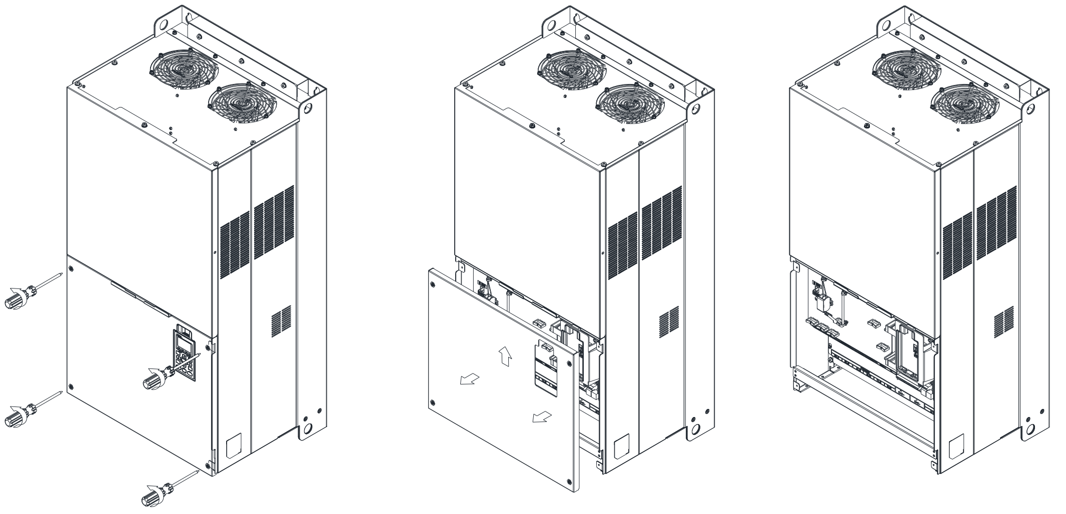


Figure 6-11

Frame H

Applicable models:
VFD3150CP43A-00; VFD3550CP43A-00; VFD4000CP43A-00; VFD5000CP43A-00; VFD5600CP43A-00; VFD6300CP43A-00; VFD3150CP43C-00/-21; VFD3550CP43C-00/-21; VFD4000CP43C-00/-21; VFD5000CP43C-00/-21; VFD5600CP43C-21; VFD6300CP43C-21

Screw torque: 14–16 kg-cm / [12.15–13.89 lb-in.] / [1.4–1.6 Nm]
To remove the cover, lift it slightly and pull outward

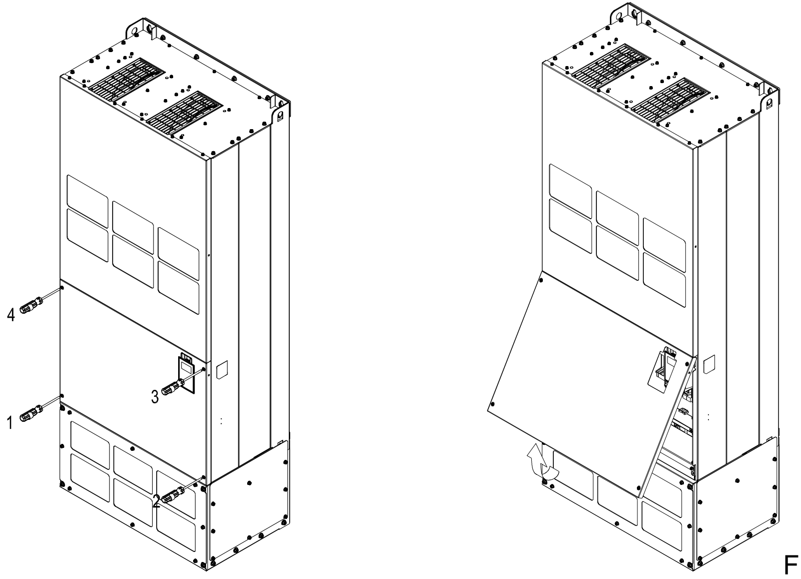


Figure 6-12

690V Frame H
Applicable models:
VFD4000CP63A-00/-21; VFD4500CP63A-00/-21; VFD5600CP63A-00/-21; VFD6300CP63A-00/-21

Screw torque: 14–16 kg-cm / [12.15–13.89 lb-in.] / [1.4–1.6 Nm]
To remove the cover, lift it slightly and pull outward

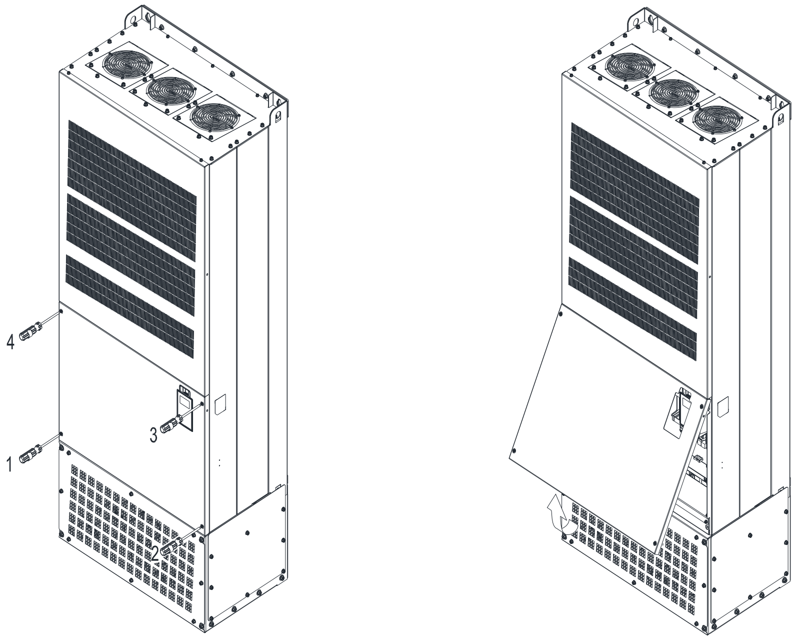
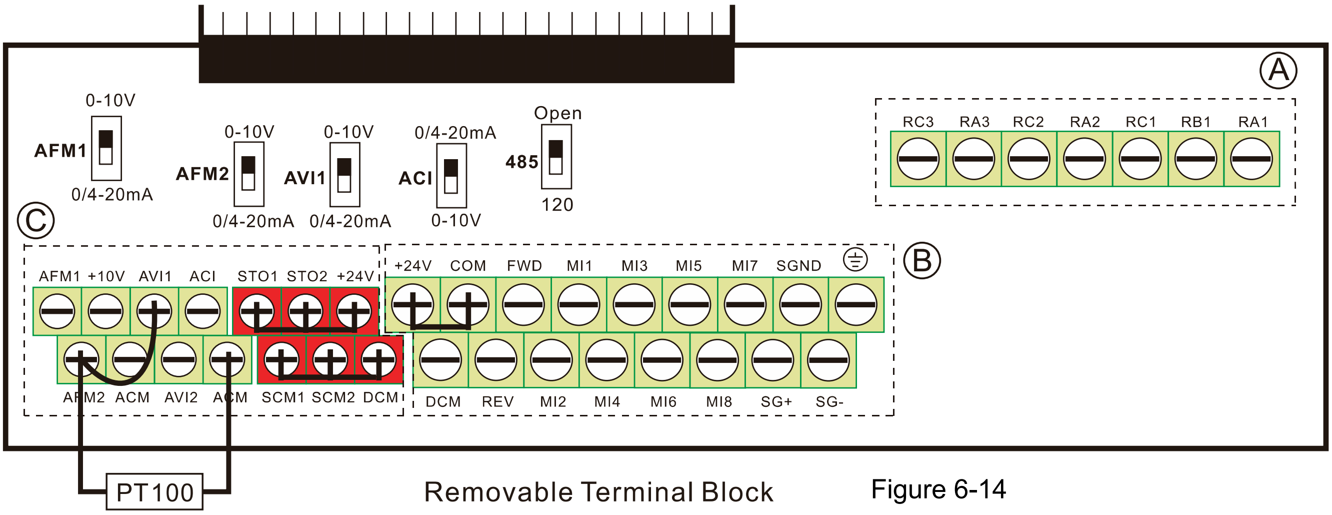


Figure 6-13

6-2 Specifications of Control Terminal



Removable Terminal Block

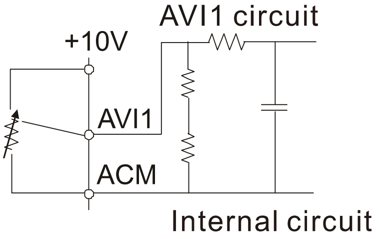
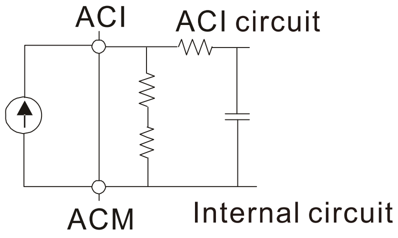
Figure 6-14

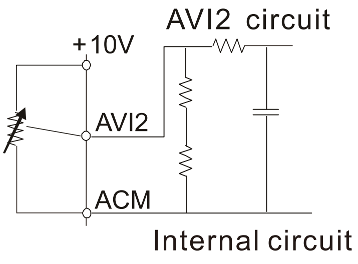
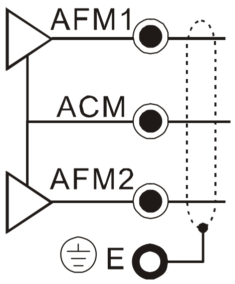
Terminal Function	Group	Conductor	Stripping Length [mm]	Maximum Wire Gauge	Minimum Wire Gauge	Torque (±10%)
Relay	Ⓐ	Solid	4–5	1.5 mm² [16 AWG]	0.2 mm² [26 AWG]	5 kg-cm [4.3 lb-in] [0.49 Nm]
		Strand				
Control board	Ⓑ	Solid	6–7			8 kg-cm [6.9 lb-in] [0.78 Nm]
		Strand				
Control board	Ⓒ	Solid				2 kg-cm [1.7 lb-in] [0.20 Nm]
		Strand				

Wiring precautions:

- In the figure above, the default for STO1, STO2, +24V and SCM1, SCM2, DCM are short circuit. The +24V from section Ⓒ of above figure is for STO only, and cannot be used for other purposes. The default for +24V-COM is short circuit and SINK mode (NPN); please refer to Section 4 Wiring for more detail.
- Tighten the wiring with slotted screwdriver:
  Ⓐ Ⓑ is 3.5 mm (wide) x 0.6 mm (thick); Ⓒ is 2.5 mm (wide) x 0.4 mm (thick)
- When wiring bare wires, ensure that they are perfectly arranged to go through the wiring holes.

Terminals	Terminal Function	Default (NPN mode)
+24V	Digital control signal common (Source)	+24V ± 5% 200mA
COM	Digital control signal common (Sink)	Common for multi-function input terminals
FWD	Forward-Stop command	FWD-DCM: ON➔ forward running OFF➔ deceleration to stop
REV	Reverse-Stop command	REV-DCM: ON➔ reverse running OFF➔ deceleration to stop

Terminals	Terminal Function	Default (NPN mode)
MI1 | MI8	Multi-function input 1–8	Refer to Pr.02-01–02-08 to program the multi-function inputs MI1–MI8. Source Mode ON: activation voltage ≥ 11 V_{DC} OFF: cut-off voltage ≤ 5 V_{DC} Sink Mode ON: the activation voltage ≤ 13 V_{DC} OFF: cut-off current voltage ≥ 19 V_{DC} The internal resistance is 3.6 kΩ.
DCM	Digital frequency signal common	Digital frequency signal common
RA1	Multi-function relay output 1 (N.O.) a	Resistive Load: 3 A (N.O.) / 3 A (N.C.) 250 V_{AC} 5 A (N.O.) / 3 A (N.C.) 30 V_{DC} Inductive Load (COS 0.4): 1.2 A (N.O) / 1.2 A (N.C.) 250 V_{AC} Various kinds of monitor signals output, e.g. operation, frequency reached, overload indication, etc.
RB1	Multi-function relay output 1 (N.C.) b	
RC1	Multi-function relay common	
RA2	Multi-function relay output 2 (N.O.) a	Resistive Load: 3 A (N.O.) / 250 V_{AC} 5 A (N.O.) / 30 V_{DC} Inductive Load (COS 0.4): 1.2 A (N.O.) / 250 V_{AC} Various kinds of monitor signals output, e.g. operation, frequency reached, overload indication, etc.
RC2	Multi-function relay common	
RA3	Multi-function relay output 3 (N.O.) a	
RC3	Multi-function relay common	
+10V	Potentiometer power supply	Analog frequency setting: +10 V_{DC} 20 mA
AVI1	Analog voltage input  Figure 6-16	Impedance: 20 kΩ Range: 0–20 mA / 4–20 mA / 0–10 V = 0–Max. Output Frequency (Pr.01-00) AVI1 switch, default is 0–10 V
ACI	Analog current input  Figure 6-17	Impedance: 250 Ω Range: 0–20 mA / 4–20 mA / 0–10 V = 0–Max. Output Frequency (Pr.01-00) ACI Switch, default is 4–20 mA

Terminals	Terminal Function	Default (NPN mode)
AVI2	Auxiliary analog voltage input  Figure 6-18	Impedance: 20 kΩ Range: 0–10 V_{DC} = 0–Max. Output Frequency (Pr.01-00)
AFM1	Multi-function analog voltage output  Figure 6-19	0–10 V Max. output current 2 mA, Max. load 5 kΩ 0–20 mA Max. load 500 Ω Output current: 20 mA max Resolution: 0–10 V corresponds to Max. operation frequency Range: 0–10 V → 4–20 mA AFM1/ AFM2 Switch, default is 0–10 V
AFM2		
ACM	Analog Signal Common	Common for analog terminals
STO1	Default setting is shorted Power removal safety function for EN ISO 13849 and IEC 61508 When STO1–SCM1; STO2–SCM2 is activated, the voltage of STO1–SCM1 / STO2–SCM2 must be ≥ 11 V_{DC}, the internal resistance for STO1–SCM1 / STO2–SCM2 is 3.6 kΩ Note: Refer to Section 18 Safe Torque Off Function.	
SCM1		
STO2		
SCM2		
SG+	Modbus RS-485 Note: Refer to Section 12 DESCRIPTION OF PARAMETER SETTINGS group 09 Communication Parameters for more information.	
SG-		
SGND		
RJ45	PIN 1, 2, 7, 8 : Reserved PIN 3, 6: SGND PIN 4: SG- PIN 5: SG+	

NOTE: Wire size of analog control signals: 0.75 mm^2 [18 AWG] with shielded wire

6-3 Remove the Terminal Block

1. Loosen the screws by screwdriver. (As shown in figure below).
   Screw torque: 6–8 kg-cm / [5.2–6.9 lb-in] / [0.59–0.78 Nm]

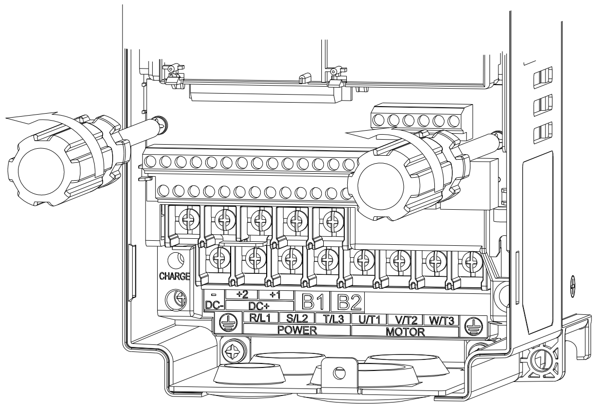


Figure 6-19

2. Remove the control board by pulling it out for a distance 6–8 cm (as 1 in the figure) then lift the control board upward (as 2 in the figure).

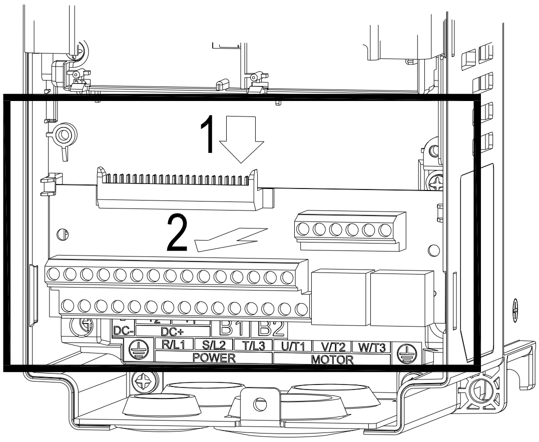


Figure 6-20

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Chapter 7 Optional Accessories

7-1 Brake Resistors and Brake Units Used in AC Motor Drive

7-2 Magnetic Contactor / Air Circuit Breaker and Non-fuse Circuit Breaker

7-3 Fuse Specification Chart

7-4 AC / DC Reactor

7-5 Zero Phase Reactor

7-6 EMC Filter

7-7 Panel Mounting (MKC-KPPK)

7-8 Conduit Box Kit

7-9 Fan Kit

7-10 Flange Mounting Kit

7-11 Power Terminal Kit

7-12 USB/RS-485 Communication Interface IF6530

The optional accessories listed in this chapter are available upon request. Installing additional accessories to your drive can substantially improve the drive's performance. Select accessories according to your needs or contact your local distributor for suggestions.

7-1 Brake Resistors and Brake Units Used in AC Motor Drives

230V Model

Applicable Motor		125% Braking Torque 10%ED *1							Max. Braking Torque *2		
HP	kW	Braking Torque [kg-m]	Brake Unit	Brake Resistor for Each Brake Unit *3			Resistor Value Spec. for Each AC Motor Drive	Total Braking Current [A]	Min. Resistor Value [Ω]	Max. Total Braking Current [A]	Peak Power [kW]
			VFDB *4	P/N	Q'ty	Usage					
1	0.7	0.5	-	BR080W200	1	-	80W 200Ω	1.9	63.3	6	2.3
2	1.5	0.5	-	BR080W200	1	-	80W 200Ω	1.9	63.3	6	2.3
3	2.2	1.0	-	BR200W091	1	-	200W 91Ω	4.2	47.5	8	3.0
5	3.7	1.5	-	BR300W070	1	-	300W 70Ω	5.4	38.0	10	3.8
7.5	5.5	2.5	-	BR400W040	1	-	400W 40Ω	9.5	19.0	20	7.6
10	7.5	3.7	-	BR1K0W020	1	-	1000W 20Ω	19	14.6	26	9.9
15	11	5.1	-	BR1K0W020	1	-	1000W 20Ω	19	14.6	26	9.9
20	15	7.4	-	BR1K5W013	1	-	1500W 13Ω	29	12.6	29	11.0
25	18	10.2	-	BR1K0W4P3	2	2 in series	2000W 8.6Ω	44	8.3	46	17.5
30	22	12.2	-	BR1K0W4P3	2	2 in series	2000W 8.6Ω	44	8.3	46	17.5
40	30	14.9	-	BR1K5W3P3	2	2 in series	3000W 6.6Ω	58	5.8	66	25.1
50	37	20.3	2015*2	BR1K0W5P1	2	2 in series	4000W 5.1Ω	75	4.8	80	30.4
60	45	25	2022*2	BR1K2W3P9	2	2 in series	4800W 3.9Ω	97	3.2	120	45.6
75	55	30.5	2022*2	BR1K5W3P3	2	2 in series	6000W 3.3Ω	118	3.2	120	45.6
100	75	37.2	2022*3	BR1K2W3P9	2	2 in series	7200W 2.6Ω	145	2.1	180	68.4
125	90	50.8	2022*4	BR1K2W3P9	2	2 in series	9600W 2Ω	190	1.6	240	91.2

Table 7-1

460V Model

Applicable Motor		125%Braking Torque 10%ED *1							Max. Braking Torque *2		
HP	kW	Braking Torque [kg-m]	Brake Unit	Brake Resistor for Each Brake Unit *3			Resistor Value Spec. for Each AC Motor Drive	Total Braking Current [A]	Min. Resistor Value [Ω]	Max. Total Braking Current [A]	Peak Power [kW]
			VFDB *4	P/N	Q'ty	Usage					
1	0.7	0.5	-	BR080W750	1	-	80W 750Ω	1	190.0	4	3.0
2	1.5	0.5	-	BR080W750	1	-	80W 750Ω	1	190.0	4	3.0
3	2.2	1.0	-	BR200W360	1	-	200W 360Ω	2.1	126.7	6	4.6
5	3.7	1.5	-	BR300W250	1	-	300W 250Ω	3	108.6	7	5.3
5.5	4.0	2.5	-	BR400W150	1	-	400W 150Ω	5.1	84.4	9	6.8
7.5	5.5	2.7	-	BR1K0W075	1	-	1000W 75Ω	10.2	54.3	14	10.6
10	7.5	3.7	-	BR1K0W075	1	-	1000W 75Ω	10.2	54.3	14	10.6
15	11	5.1	-	BR1K0W075	1	-	1000W 75Ω	10.2	47.5	16	12.2
20	15	7.4	-	BR1K5W043	1	-	1500W 43Ω	17.6	42.2	18	13.7
25	18	10.2	-	BR1K0W016	2	2 in series	2000W 32Ω	24	26.2	29	22.0
30	22	12.2	-	BR1K0W016	2	2 in series	2000W 32Ω	24	23.0	33	25.1
40	30	14.9	-	BR1K5W013	2	2 in series	3000W 26Ω	29	23.0	33	25.1
50	37	20.3	-	BR1K0W016	4	2 parallel, 2 in series	4000W 16Ω	47.5	14.1	54	41.0
60	45	25	4045*1	BR1K2W015	4	2 parallel, 2 in series	4800W 15Ω	50	12.7	60	45.6
75	55	30.5	4045*1	BR1K5W013	4	2 parallel, 2 in series	6000W 13Ω	59	12.7	60	45.6
100	75	37.2	4030*2	BR1K0W5P1	4	4 series	8000W 10.2Ω	76	9.5	80	60.8
125	90	50.8	4045*2	BR1K2W015	4	2 parallel, 2 in series	9600W 7.5Ω	100	6.3	120	91.2
150	110	60.9	4045*2	BR1K5W013	4	2 parallel, 2 in series	12000W 6.5Ω	117	6.3	120	91.2
175	132	74.5	4110*1	BR1K2W015	10	5 parallel, 2 in series	12000W 6Ω	126	6.0	126	95.8
215	160	89.4	4160*1	BR1K5W012	12	6 parallel, 2 in series	18000W 4Ω	190	4.0	190	144.4

Applicable Motor		125%Braking Torque 10%ED *1							Max. Braking Torque *2		
HP	kW	Braking Torque [kg-m]	Brake Unit	Brake Resistor for Each Brake Unit *3			Resistor Value Spec. for Each AC Motor Drive	Total Braking Current [A]	Min. Resistor Value [Ω]	Max. Total Braking Current [A]	Peak Power [kW]
			VFDB *4	P/N	Q'ty	Usage					
250	185	108.3	4160*1	BR1K5W012	12	6 parallel, 2 in series	18000W 4Ω	190	4.0	190	144.4
270	200	108.3	4185*1	BR1K5W012	12	6 parallel, 2 in series	18000W 4Ω	190	4.0	190	144.4
300	220	125.2	4185*1	BR1K5W012	14	7 parallel, 2 in series	21000W 3.4Ω	225	3.4	225	172.0
340	250	135.4	4110*2	BR1K2W015	10	5 parallel, 2 in series	24000W 3Ω	252	3.0	252	191.5
375	280	148.9	4110*2	BR1K2W015	10	5 parallel, 2 in series	24000W 3Ω	252	3.0	252	191.5
425	315	189.6	4160*2	BR1K5W012	12	6 parallel, 2 in series	36000W 2Ω	380	2.0	380	288.8
475	355	213.3	4160*2	BR1K5W012	12	6 parallel, 2 in series	36000W 2Ω	380	2.0	380	288.8
536	400	240.3	4185*2	BR1K5W012	14	7 parallel, 2 in series	42000W 1.7Ω	450	1.7	450	344.2
675	500	304.7	4185*3	BR1K5W012	12	6 parallel, 2 in series	54000W 1.3Ω	600	1.1	675	513.0
745	560	379.1	4185*3	BR1K5W012	14	7 parallel, 2 in series	63000W 1.1Ω	675	1.1	675	513.0
850	630	426.5	4160*4	BR1K5W012	12	6 parallel, 2 in series	72000W 1.0Ω	760	1.0	760	577.6

Table 7-2

575V Model

Applicable Motor [kW]		125%Braking Torque 10%ED *1							Max. Braking Torque *2		
ND	LD	Braking Torque [kg-m]	Brake Unit	Brake Resistor for Each Brake Unit *3			Resistor Value Spec. for Each AC Motor Drive	Total Braking Current [A]	Min. Resistor Value [Ω]	Max. Total Braking Current [A]	Peak Power [kW]
			VFDB *4	P/N	Q'ty	Usage					
0.75	1.5	0.5	-	BR080W750	1	-	80W 750Ω	1.2	280.0	4	4.5
1.5	2.2	1	-	BR200W360	1	-	200W 360Ω	2.6	186.7	6	6.7
2.2	3.7	1.5	-	BR300W400	1	-	300W 400Ω	2.3	160.0	7	7.8
3.7	5.5	2.5	-	BR500W100	1	-	500W 100Ω	9.2	93.3	12	13.4
5.5	7.5	3.7	-	BR750W140	1	-	750W 140Ω	6.6	80.0	14	15.7
7.5	11	5.1	-	BR1K0W075	1	-	1000W 75Ω	12.3	70.0	16	17.9
11	15	7.4	-	BR1K1W091	1	-	1100W 91Ω	10.1	62.2	18	20.2

Table 7-3

690V Model

Applicable Motor [kW]		125%Braking Torque 10%ED *1							Max. Braking Torque*2		
LD	ND	Braking Torque [kg-m]	Brake Unit	Brake Resistor for Each Brake Unit *3			Resistor Value Spec. for Each AC Motor Drive	Total Braking Current [A]	Min. Resistor Value [Ω]	Max. Total Braking Current [A]	Peak Power [kW]
			VFDB*4	P/N	Q'ty	Usage					
18.5	15	10.2	-	BR1K0W039	2	2 in series	2000W 78Ω	14.4	58.9	19	21.3
22	18.5	12.5	-	BR1K2W033	2	2 in series	2400W 66Ω	17.0	58.9	19	21.3
30	22	14.9	-	BR1K5W027	2	2 in series	3000W 54Ω	20.7	43.1	26	29.1
37	30	20.3	-	BR1K2W015	3	3 in series	3600W 45Ω	24.9	43.1	26	29.1
45	37	25	6055*1	BR1K2W033	4	2 parallel, 2 in series	4800W 33Ω	33.9	24.3	46	51.5
55	45	30.5	6055*1	BR1K5W027	4	2 parallel, 2 in series	6000W 27Ω	41.5	24.3	46	51.5
75	55	37.2	6110*1	BR1K2W033	6	3 parallel, 2 in series	7200W 22Ω	50.9	12.2	92	103.0
90	75	50.8	6110*1	BR1K5W027	6	3 parallel, 2 in series	9000W 18Ω	62.2	12.2	92	103.0

Applicable Motor [kW]		125%Braking Torque 10%ED *1							Max. Braking Torque*2		
LD	ND	Braking Torque [kg-m]	Brake Unit	Brake Resistor for Each Brake Unit *3			Resistor Value Spec. for Each AC Motor Drive	Total Braking Current [A]	Min. Resistor Value [Ω]	Max. Total Braking Current [A]	Peak Power [kW]
			VFDB*4	P/N	Q'ty	Usage					
110	90	60.9	6110*1	BR1K5W027	8	4 parallel, 2 in series	12000W 13.5Ω	83.0	12.2	92	103.0
132	110	74.5	6160*1	BR1K2W015	12	4 parallel, 3 in series	14400W 11.3Ω	99.6	8.2	136	152.3
160	132	89.4	6160*1	BR1K5W027	10	5 parallel, 2 in series	15000W 10.8Ω	103.7	8.2	136	152.3
200	160	108.3	6200*1	BR1K5W027	12	6 parallel, 2 in series	18000W 9.0Ω	124.4	6.9	162	181.4
250	200	135.4	6110*2	BR1K5W027	8	4 parallel, 2 in series	24000W 6.8Ω	165.9	6.1	184	206.1
315	250	169.3	6160*2	BR1K5W027	10	5 parallel, 2 in series	30000W 5.4Ω	207.4	4.1	272	304.6
400	315	213.3	6200*2	BR1K5W027	12	6 parallel, 2 in series	36000W 4.5Ω	248.9	3.5	324	362.9
450	355	240.3	6200*2	BR1K5W027	14	7 parallel, 2 in series	42000W 3.9Ω	290.4	3.5	324	362.9
560	450	304.7	6200*3	BR1K5W027	12	6 parallel, 2 in series	54000W 3.0Ω	373.3	2.3	486	544.3
630	630	426.5	6200*4	BR1K5W027	12	6 parallel, 2 in series	72000W 2.3Ω	497.8	1.7	648	725.8

Table 7-4

*1 Calculation for 125% braking toque: (kW) × 125% × 0.8; where 0.8 is motor efficiency.
Because of the limited resistor power, the longest operation time for 10%ED is 10 seconds (ON: 10 sec. / OFF: 90 sec.).

*2 Refer to Chapter 7 "Brake Module and Brake Resistors" in the application manual for "Operation Duration & ED" vs. "Braking Current".

*3 For heat dissipation, a resistors of 400 W or lower should be fixed to the frame and maintain the surface temperature below 250°C; a resistor of 1000 W and above should maintain the surface temperature below 350°C. (If the surface temperature is higher than the temperature limit, install extra cooling or increase the size of the resistor.)

*4 The calculation of the brake resistor is based on a four-pole motor (1800 rpm). Refer to VFDB series Braking Module Instruction for more details on brake resistor.

NOTE

1. Specification and Appearance of Brake Resistors

1-1 Wire wound resistors: For 1000 W and above, refer to the following appearance of wire wound resistor (Figure 7-1) and its model and specification comparison table (Table 7-5) for details.

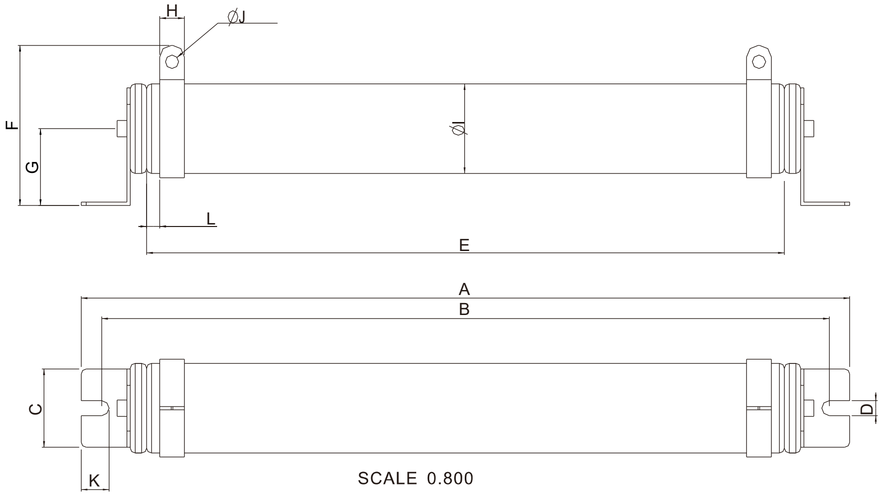


Figure 7-1

Models and Specifications Comparison Table of Wire Wound Resistors:

Unit: mm

MODEL	A	B	C	D	E	F	G	H	∅I	∅J	K	L
BR1K0W4P3	470±10	445±5	48±0.2	9.1±0.1	390±3	98±5	47±5	15±1	55±5	8.1±0.1	21±0.2	8±1
BR1K0W5P1												
BR1K0W016												
BR1K0W020												
BR1K0W075												
BR1K2W3P9												
BR1K2W015												
BR1K5W3P3												
BR1K5W012												
BR1K5W013												
BR1K5W043												

Table 7-5

1-2 Aluminum housed resistors: For below 1000 W, refer to the following appearance of aluminum-housed resistor (Figure 7-2) and its model and specification comparison table (Table 7-6) for details.

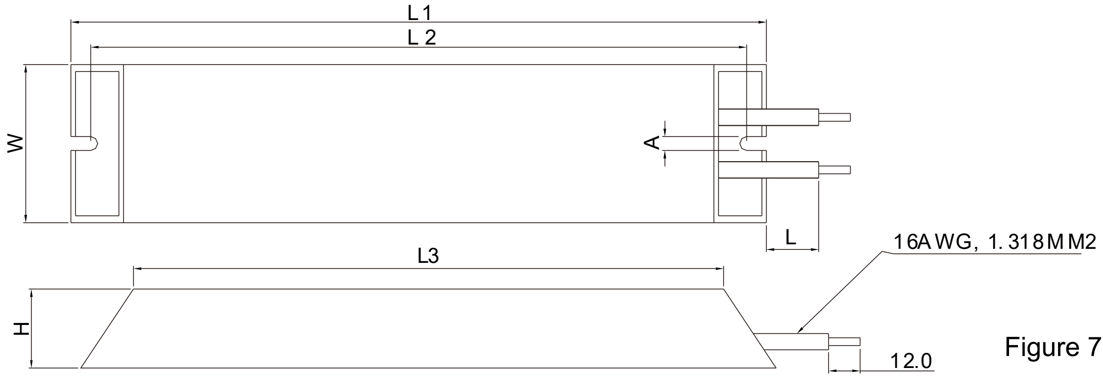


Figure 7-2

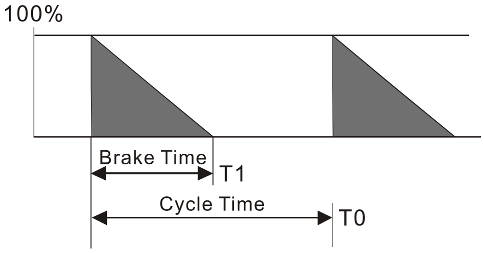
Unit: mm

MODEL	L1	L2	L3	W	H	A	L
BR080W200	140±2	125±2	100±1	40±0.5	20±0.5	5.3±0.5	200±20
BR080W750							
BR200W091	165±2	150±2	125±1	60±0.5	30±0.5		
BR200W360							
BR300W070	215±2	200±2	175±1				
BR300W250							
BR400W040	265±2	250±2	225±1				
BR400W150							

Table 7-6

2. Select the resistance value, power and brake usage (ED %) according to Delta rules.

   Definition for Brake Usage ED%



ED% = T1 / T0 x 100(%)

Explanation:
Brake usage ED (%) is the amount of time needed for the brake unit and brake resistor to dissipate heat generated by braking. When the brake resistor heats up, the resistance increases with temperature, and braking torque decreases accordingly.

Figure 7-3

For safety, install a thermal overload relay (O.L) between the brake unit and the brake resistor in conjunction with the magnetic contactor (MC) before the drive for additional protection. The thermal overload relay protects the brake resistor from damage due to frequent or continuous braking. Under such circumstances, turn off the power to prevent damage to the brake resistor, brake unit and drive. NOTE: Never use it to disconnect the brake resistor.

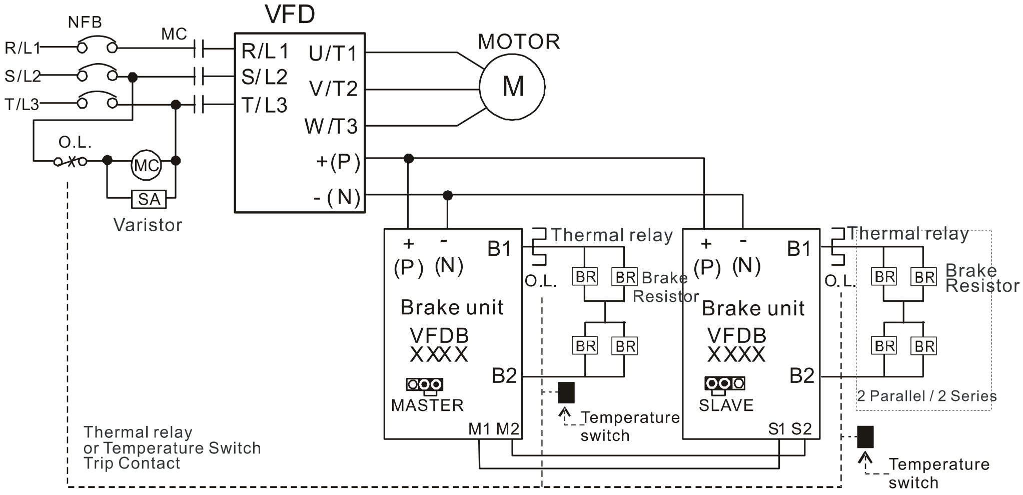


Figure 7-4

- When AC Drive is equipped with a DC reactor, please read user manual for the correct wiring for the brake unit input circuit +(P).
- DO NOT connect input circuit -(N) to the neutral point of the power system.

3. Any damage to the drive or other equipment caused by using brake resistors and brake modules that are not provided by Delta voids the warranty.
4. Consider environmental safety factors when installing the brake resistors. If you use the minimum resistance value, consult local dealers for the power calculation.
5. When using more than two brake units, the equivalent resistor value of the parallel brake unit cannot be less than the value in the column "Min. Resistor Value (Ω)". Read the wiring information in the brake unit instruction sheet thoroughly prior to operation. Visit the following links to get the instruction sheets for the wiring in the brake unit:
   - VFDB2015 / 2022 / 4030 / 4045 / 5055 Braking Modules Instruction Sheet
     http://www.deltaww.com/filecenter/Products/download/06/060101/Option/DELTA_IA-MDS_VFDB_I_EN_20070719.pdf
   - VFDB4110 / 4160 / 4185 Braking Modules Instruction Sheet
     http://www.deltaww.com/filecenter/Products/download/06/060101/Option/DELTA_IA-MDS_VFDB4110-4160-4185_I_EN_20101011.pdf
   - VFDB6055 / 6110 / 6160 / 6200 Braking Modules Instruction Sheet
     http://www.deltaww.com/filecenter/Products/download/06/060101/Option/DELTA_IA-MDS_VFDB6055-6110-6160-6200_I_TSE_20121030.pdf
6. The selection tables are for normal usage. If the AC motor drive requires frequent braking, increase the Watts by two to three times.
7. Thermal Overload Relay (TOR), for 230V / 460V / 690V models:
   Thermal overload relay selection is based on its overload capacity. A standard braking capacity of the CP2000 is 10% ED (Tripping time = 10 s). As shown in the figure below, a 460V, 110 kw CP2000 requires the thermal relay to take 260% overload capacity for 10 seconds (hot starting) and the braking current is 126 A. In this case, select a thermal overload relay rated at 50 A. The property of each thermal relay may vary among different manufacturers. Carefully read the specification before using it.

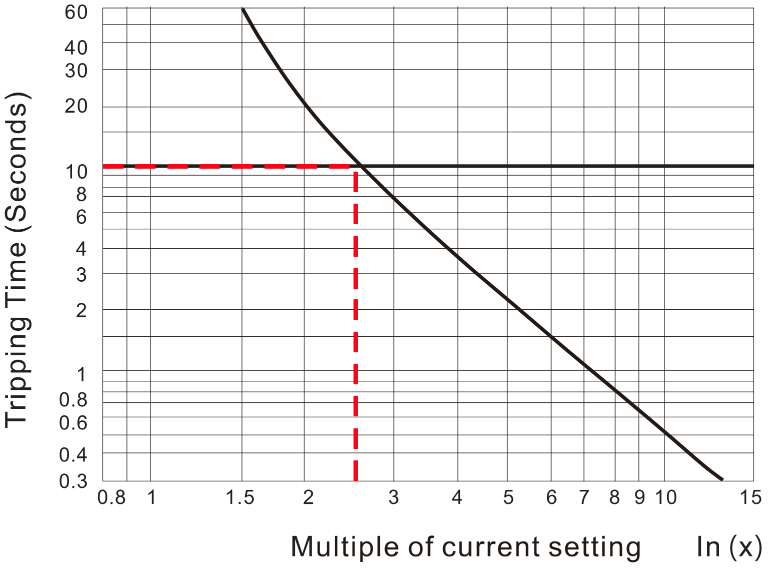

60
40
30
20
10
8
6
4
3
2
1
0.8
0.6
0.4
0.3
Tripping Time (Seconds)
0.8
1
1.5
2
3
4
5
6
7
8
9
10
15
Multiple of current setting
In (x)

Figure 7-5

7-2 Magnetic Contactor / Air Circuit Breaker and Non-fuse Circuit Breaker

Magnetic Contactor (MC) and Air Circuit Breaker (ACB)

It is recommended the surrounding temperature for MC should be ≥ 60°C and that for ACB should be ≥ 50°C. In the meanwhile, consider temperature derating for components with ON/OFF switch in accordance with the ambient temperature of the on-site distribution panel.

230V Model

Frame	Model	Light Duty Output Current [A]	Light Duty Input Current [A]	MC/ACB Selection [A]
A	VFD007CP23A-21	5	6.4	11
	VFD015CP23A-21	7.5	9.6	18
	VFD022CP23A-21	10	15	22
	VFD037CP23A-21	15	22	40
	VFD055CP23A-21	21	25	40
B	VFD075CP23A-21	31	34	55
	VFD110CP23A-21	46	51	85
	VFD150CP23A-21	61	67	105
C	VFD185CP23A-21	75	83	130
	VFD220CP23A-21	90	99	150
	VFD300CP23A-21	105	116	185
D	VFD370CP23A-00/21	146	146	225
	VFD450CP23A-00/21	180	180	265
E	VFD550CP23A-00/21	215	215	330
	VFD750CP23A-00/21	276	276	400
	VFD900CP23A-00/21	322	322	500

Table 7-7

460V Model

Frame	Model	Light Duty Output Current [A]	Light Duty Input Current [A]	MC/ACB Selection [A]
A	VFD007CP43A-21	3.0	4.3	7
	VFD015CP43B-21	4.2	6.0	9
	VFD022CP43B-21	5.5	8.1	12
	VFD037CP43B-21	8.5	12.4	22
	VFD040CP43A-21	10.5	16	32
	VFD055CP43B-21	13	20	32
	VFD075CP43B-21	18	22	40
B	VFD110CP43B-21	24	26	40
	VFD150CP43B-21	32	35	55
	VFD185CP43B-21	38	42	65
C	VFD220CP43A-21	45	50	75
	VFD300CP43B-21	60	66	105
	VFD370CP43B-21	73	80	130

Frame	Model	Light Duty Output Current [A]	Light Duty Input Current [A]	MC/ACB Selection [A]
D0	VFD450CP43S-21	91	91	150
	VFD550CP43S-21	110	110	185
D	VFD750CP43B-00/21	150	150	265
	VFD900CP43A-00/21	180	180	265
E	VFD1100CP43A-00/21	220	220	330
	VFD1320CP43B-00/21	260	260	400
F	VFD1600CP43A-00/21	310	310	500
	VFD1850CP43B-00/21	370	370	630
G	VFD2000CP43A-00/21	395	395	800
	VFD2200CP43A-00/21	460	460	800
	VFD2500CP43A-00/21	481	481	800
	VFD2800CP43A-00/21	530	530	800
H	VFD3150CP43A-00/C-00/C-21	616	616	1000
	VFD3550CP43A-00/C-00/C-21	683	683	1000
	VFD4000CP43A-00/C-00/C-21	770	770	1250
	VFD5000CP43A-00/C-00/C-21	930	930	1600
	VFD5600CP43A-00/C-21	1094	1094	2000
	VFD6300CP43A-00/C-21	1212	1212	2000

Table7-8

575V Model

Frame	Model	Light Duty Output Current [A]	Light Duty Input Current [A]	MC/ACB Selection [A]
A	VFD015CP53A-21	3	3.8	9
	VFD022CP53A-21	4.3	5.4	12
	VFD037CP53A-21	6.7	10.4	18
B	VFD055CP53A-21	9.9	14.9	32
	VFD075CP53A-21	12.1	16.9	32
	VFD110CP53A-21	18.7	21.3	40
	VFD150CP53A-21	24.2	26.3	50

Table 7-9

690V Model

Frame	Model	Light Duty Output Current [A]	Light Duty Input Current [A]	MC/ACB Selection [A]
C	VFD185CP63A-21	24	29	50
	VFD220CP63A-21	30	36	65
	VFD300CP63A-21	36	43	75
	VFD370CP63A-21	45	54	100
D	VFD450CP63A-00/A-21	54	65	130
	VFD550CP63A-00/A-21	67	81	150
E	VFD750CP63A-00/A-21	86	84	150
	VFD900CP63A-00/A-21	104	102	185
	VFD1100CP63A-00/A-21	125	122	225

Frame	Model	Light Duty Output Current [A]	Light Duty Input Current [A]	MC/ACB Selection [A]
E	VFD1320CP63A-00/A-21	150	147	265
F	VFD1600CP63A-00/A-21	180	178	330
	VFD2000CP63A-00/A-21	220	217	400
G	VFD2500CP63A-00/A-21	290	292	630
	VFD3150CP63A-00/A-21	350	353	630
H	VFD4000CP63A-00/A-21	430	454	800
	VFD4500CP63A-00/A-21	465	469	800
	VFD5600CP63A-00/A-21	590	595	1000
	VFD6300CP63A-00/A-21	675	681	1250

Table 7-10

Non-fuse Circuit Breaker

Comply with the UL standard: Per UL 508, paragraph 45.8.4, part a,

The rated current of the non-fuse circuit breaker should be 1.6–2.6 times (575V / 690V models: 2–4 times) the drive's rated input current.

230V / Three-phase	
Model	Breaker Rated Input Recommended Current [A]
VFD007CP23A-21	15
VFD015CP23A-21	20
VFD022CP23A-21	30
VFD037CP23A-21	40
VFD055CP23A-21	50
VFD075CP23A-21	60
VFD110CP23A-21	100
VFD150CP23A-21	125
VFD185CP23A-21	150
VFD220CP23A-21	200
VFD300CP23A-21	225
VFD370CP23A-00/23A-21	250
VFD450CP23A-00/23A-21	300
VFD550CP23A-00/23A-21	400
VFD750CP23A-00/23A-21	450
VFD900CP23A-00/23A-21	600

Table 7-11

460V / Three-phase	
Model	Breaker Rated Input Recommended Current [A]
VFD007CP43A-21/4EA-21	10
VFD015CP43B-21/4EB-21	10
VFD022CP43B-21/4EB-21	15
VFD040CP43A-21/4EA-21	25
VFD037CP43B-21/4EB-21	30
VFD055CP43B-21/4EB-21	40
VFD075CP43B-21/4EB-21	40
VFD110CP43B-21/4EB-21	50
VFD150CP43B-21/4EB-21	60
VFD185CP43B-21/4EB-21	75
VFD220CP43A-21/4EA-21	100
VFD300CP43B-21/4EB-21	125
VFD370CP43B-21/4EB-21	150
VFD450CP43S-00/43S-21	175
VFD550CP43S-00/43S-21	250
VFD750CP43B-00/43B-21	300
VFD900CP43A-00/43A-21	300
VFD1100CP43A-00/43A-21	400
VFD1320CP43B-00/43B-21	500
VFD1600CP43A-00/43A-21	600
VFD1850CP43B-00/43B-21	600
VFD2000CP43A-0043A/-21	800
VFD2200CP43A-00/43A-21	800
VFD2500CP43A-00/43A-21	1000
VFD2800CP43A-00/43A-21	1000
VFD3150CP43A-00/43C-00/43C-21	1200
VFD3550CP43A-00/43C-00/43C-21	1350
VFD4000CP43A-00/43C-00/43C-21	1500
VFD5000CP43A-00/43C-00/43C-21	2000
VFD5600CP43A-00/43C-21	2000
VFD6300CP43A-00/43C-21	2000

Table 7-12

575V / Three-phase	
Model	Breaker Rated Input Recommended Current [A]
VFD015CP53A-21	7
VFD022CP53A-21	10
VFD037CP53A-21	15
VFD055CP53A-21	25
VFD075CP53A-21	32
VFD110CP53A-21	50
VFD150CP53A-21	63

Table 7-13

690V / Three-phase	
Model	Breaker Rated Input Recommended Current [A]
VFD185CP63A-21	60
VFD220CP63A-21	70
VFD300CP63A-21	80
VFD370CP63A-21	100
VFD450CP63A-00/-21	100
VFD550CP63A-00/-21	125
VFD750CP63A-00/-21	175
VFD900CP63A-00/-21	200
VFD1100CP63A-00/-21	250
VFD1320CP63A-00/-21	300
VFD1600CP63A-00/-21	350
VFD2000CP63A-00/-21	400
VFD2500CP63A-00/-21	450
VFD3150CP63A-00/-21	500
VFD4000CP63A-00/-21	700
VFD4500CP63A-00/-21	800
VFD5600CP63A-00/-21	1250
VFD6300CP63A-00/-21	1400

Table 7-14

7-3 Fuse Specification Chart

☑ Fuse specifications lower than the table below are allowed.

☑ For installation in the United States, branch circuit protection must be provided in accordance with the National Electrical Code (NEC) and any applicable local codes. Use UL classified fuses to fulfill this requirement.

☑ For installation in Canada, branch circuit protection must be provided in accordance with Canadian Electrical Code and any applicable provincial codes. Use UL classified fuses to fulfill this requirement.

230V Model	Input Current I [A]		Line Fuse	
	Normal Duty	Light Duty	I [A]	Bussmann P/N
VFD007CP23A-21	3.9	6.4	15	JJN-15
VFD015CP23A-21	6.4	9.6	20	JJN-20
VFD022CP23A-21	12	15	30	JJN-30
VFD037CP23A-21	16	22	40	JJN-40
VFD055CP23A-21	20	25	50	JJN-50
VFD075CP23A-21	28	35	60	JJN-60
VFD110CP23A-21	36	50	100	JJN-100
VFD150CP23A-21	52	65	125	JJN-125
VFD185CP23A-21	72	83	150	JJN-150
VFD220CP23A-21	83	100	200	JJN-200
VFD300CP23A-21	99	116	225	JJN-225
VFD370CP23A-00/23A-21	124	146	250	JJN-250
VFD450CP23A-00/23A-21	143	180	300	JJN-300
VFD550CP23A-00/23A-21	171	215	400	JJN-400
VFD750CP23A-00/23A-21	206	276	450	JJN-450
VFD900CP23A-00/23A-21	245	322	600	JJN-600

Table 7-15

460V Model	Input Current I [A]		Line Fuse	
	Normal Duty	Light Duty	I [A]	Bussmann P/N
VFD007CP43A-21/4EA-21	3.5	4.3	10	JJS-10
VFD015CP43B-21/4EB-21	4.3	6.0	10	JJS-10
VFD022CP43B-21/4EB-21	5.9	8.1	15	JJS-15
VFD040CP43A-21/4EA-21	8.7	12.4	25	JJS-20
VFD037CP43B-21/4EB-21	14	16	30	JJS-20
VFD055CP43B-21/4EB-21	15.5	20	40	JJS-30
VFD075CP43B-21/4EB-21	17	22	40	JJS-40
VFD110CP43B-21/4EB-21	20	26	50	JJS-50
VFD150CP43B-21/4EB-21	26	35	60	JJS-60
VFD185CP43B-21/4EB-21	35	42	75	JJS-75
VFD220CP43A-21/4EA-21	40	50	100	JJS-100
VFD300CP43B-21/4EB-21	47	66	125	JJS-125
VFD370CP43B-21/4EB-21	63	80	150	JJS-150
VFD450CP43S-00/43S-21	74	91	175	JJS-175
VFD550CP43S-00/43S-21	101	110	250	JJS-250
VFD750CP43B-00/43B-21	114	150	300	JJS-300
VFD900CP43A-00/43-21	157	180	300	JJS-300
VFD1100CP43A-00/43A-21	167	220	400	JJS-400
VFD1320CP43B-00/43B-21	207	260	500	JJS-500
VFD1600CP43A-00/43A-21	240	310	600	JJS-600
VFD1850CP43B-00/43B-21	300	370	600	JJS-600
VFD2000CP43A-00/43A-21	300	395	800	JJS-800
VFD2200CP43A-00/43A-21	380	460	800	JJS-800
VFD2500CP43A-00/43A-21	390	481	1000	KTU-1000
VFD2800CP43A-00/43A-21	400	530	1000	KTU-1000
VFD3150CP43A-00/43C-00/43C-21	494	616	1200	KTU-1200
VFD3550CP43A-00/43C-00/43C-21	555	683	1350	KTU-1350
VFD4000CP43A-00/43C-00/43C-21	625	770	1500	KTU-1500
VFD5000CP43A-00/43C-00/43C-21 *	866	930	1600	170M6019
VFD5600CP43A-00/43C-21	930	1094	2000	170M6021
VFD6300CP43A-00/43C-21	1094	1212	2000	170C6021

*VFD5000CP43A-00/43C-00/43C-21 models are not UL certified.

Table 7-16

575V Model	Input Current I [A]		Line Fuse		
	Normal Duty	Light Duty	I [A]	Bussmann P/N	Vendor
VFD015CP53A-21	3.1	3.8	7	KLKD007.T	Littelfuse
VFD022CP53A-21	4.5	5.4	10	KLKD010.T	Littelfuse
VFD037CP53A-21	7.2	10.2	15	KLKD015.T	Littelfuse
VFD055CP53A-21	12.3	14.9	25	25ET	Bussmann
VFD075CP53A-21	15	16.9	32	32ET	Bussmann
VFD110CP53A-21	18	21.3	50	50FE	Bussmann
VFD150CP53A-21	22.8	26.3	63	63FE	Bussmann

Table 7-17

690V Model	Input Current I [A]		Line Fuse	
	Normal Duty	Light Duty	I [A]	Bussmann P/N
VFD185CP63A-21	24	29	60	JJS-60
VFD220CP63A-21	29	36	70	JJS-70
VFD300CP63A-21	36	43	80	JJS-80
VFD370CP63A-21	43	54	100	JJS-100
VFD450CP63A-00/-21	54	65	100	JJS-100
VFD550CP63A-00/-21	65	81	125	JJS-125
VFD750CP63A-00/-21	66	84	175	JJS-175
VFD900CP63A-00/-21	84	102	200	JJS-200
VFD1100CP63A-00/-21	102	122	250	JJS-250
VFD1320CP63A-00/-21	122	147	300	JJS-300
VFD1600CP63A-00/-21	148	178	350	JJS-350
VFD2000CP63A-00/-21	178	217	400	JJS-400
VFD2500CP63A-00/-21	222	292	450	170M4063
VFD3150CP63A-00/-21	292	353	500	170M6058
VFD4000CP63A-00/-21	353	454	700	170M6061
VFD4500CP63A-00/-21	388	469	800	170M6062
VFD5600CP63A-00/-21	504	595	1250	170M6066
VFD6300CP63A-00/-21	681	681	1400	170M6067

Table 7-18

7-4 AC / DC Reactor

AC Input Reactor

Installing an AC reactor on the input side of an AC motor drive can increase line impedance, improve the power factor, reduce input current, increase system capacity, and reduce interference generated from the motor drive. It also reduces momentary voltage surges or abnormal current spikes from the mains power, further protecting the drive. For example, when the main power capacity is higher than 500 kVA, or when using a phase-compensation capacitor, momentary voltage and current spikes may damage the AC motor drive's internal circuit. An AC reactor on the input side of the AC motor drive protects it by suppressing surges.

Installation

Install an AC input reactor in series between the main power and the three input phases R S T, as shown in the figure below:

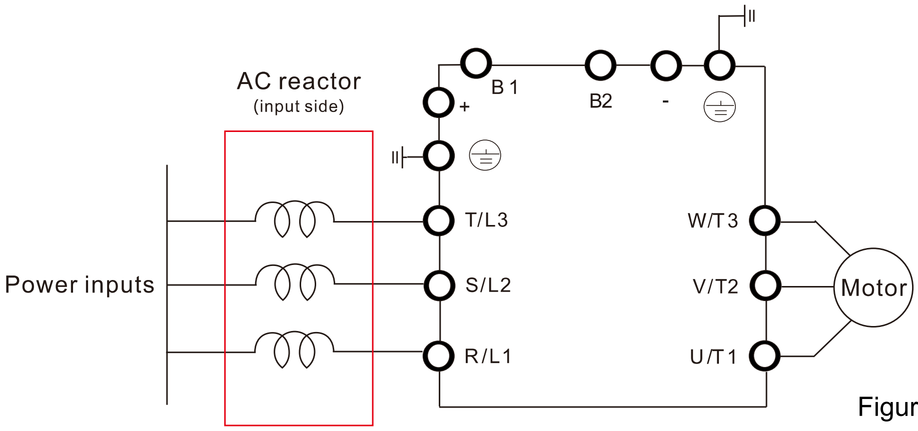


Figure 7-6

Wiring of AC input reactor

Following table shows the standard AC reactors specification of Delta CP2000

200V–230V, 50 / 60 Hz, Light Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP23A-21	0.75	1	5	6	2.536	4.227	No	DR005A0254	21
VFD015CP23A-21	1.5	2	7.5	9	1.585	2.642	No	DR008A0159	37
VFD022CP23A-21	2.2	3	10	12	1.152	1.92	No	DR011A0115	38
VFD037CP23A-21	3.7	5	15	18	0.746	1.243	No	DR017AP746	40
VFD055CP23A-21	5.5	7.5	21	25.2	0.507	0.845	No	DR025AP507	61
VFD075CP23A-21	7.5	10	31	37.2	0.38	0.633	No	DR033AP320	60
VFD110CP23A-21	11	15	46	55.2	0.26	0.433	No	DR049AP215	70
VFD150CP23A-21	15	20	61	73.2	0.196	0.327	No	DR065AP162	83
VFD185CP23A-21	18.5	25	75	90	0.169	0.282	No	DR075AP170	150
VFD220CP23A-21	22	30	90	108	0.141	0.235	No	DR090AP141	120
VFD300CP23A-21	30	40	105	126	0.12	0.2	No	DR105AP106	150
VFD370CP23A-00 VFD370CP23A-21	37	50	146	175.2	0.087	0.145	Yes	DR146AP087	110
VFD450CP23A-00 VFD450CP23A-21	45	60	180	216	0.07	0.117	Yes	DR180AP070	120
VFD550CP23A-00 VFD550CP23A-21	55	75	215	258	0.059	0.098	Yes	DR215AP059	150

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD750CP23A-00 VFD750CP23A-21	75	100	276	331.2	0.049	0.082	Yes	DR276AP049	200
VFD900CP23A-00 VFD900CP23A-21	90	125	322	386.4	0.037	0.062	Yes	DR346AP037	240
Note: The above heat dissipation is calculated based on AC reactor's rated current, the actual dissipation varies with the operation current.									

Table 7-19

200V–230V, 50 / 60 Hz, Normal Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP23A-21	0.75	1	4.6	7.36	2.536	4.227	No	DR005A0254	21
VFD015CP23A-21	1.5	2	5	8	2.536	4.227	No	DR005A0254	21
VFD022CP23A-21	2.2	3	8	12.8	1.585	2.642	No	DR008A0159	37
VFD037CP23A-21	3.7	5	11	17.6	1.152	1.92	No	DR011A0115	38
VFD055CP23A-21	5.5	7.5	17	27.2	0.746	1.243	No	DR017AP746	40
VFD075CP23A-21	7.5	10	25	40	0.507	0.845	No	DR025AP507	61
VFD110CP23A-21	11	15	33	52.8	0.38	0.633	No	DR033AP320	60
VFD150CP23A-21	15	20	49	78.4	0.26	0.433	No	DR049AP215	70
VFD185CP23A-21	18.5	25	65	104	0.196	0.327	No	DR065AP162	83
VFD220CP23A-21	22	30	75	120	0.169	0.282	No	DR075AP170	150
VFD300CP23A-21	30	40	90	144	0.141	0.235	No	DR090AP141	120
VFD370CP23A-00 VFD370CP23A-21	37	50	120	192	0.12	0.2	Yes	DR105AP106	150
VFD450CP23A-00 VFD450CP23A-21	45	60	146	233.6	0.087	0.145	Yes	DR146AP087	110
VFD550CP23A-00 VFD550CP23A-21	55	75	180	288	0.07	0.117	Yes	DR180AP070	120
VFD750CP23A-00 VFD750CP23A-21	75	100	215	344	0.059	0.098	Yes	DR215AP059	150
VFD900CP23A-00 VFD900CP23A-21	90	125	255	408	0.049	0.082	Yes	DR276AP049	200
Note: The above heat dissipation is calculated based on AC reactor's rated current, the actual dissipation varies with the operation current.									

Table 7-20

380V–460V, 50 / 60 Hz, Light Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP43A-21 VFD007CP4EA-21	0.75	1	3	3.6	8.102	13.503	No	DR003A0810	20
VFD015CP43B-21 VFD015CP4EB-21	1.5	2	4.2	5.04	6.077	10.128	No	DR004A0607	21
VFD022CP43B-21 VFD022CP4EB-21	2.2	3	5.5	6.6	4.05	6.75	No	DR006A0405	31
VFD037CP43B-21 VFD037CP4EB-21	3.7	5	8.5	10.2	2.7	4.5	No	DR009A0270	40
VFD040CP43A-21 VFD040CP4EA-21	4	5	10.5	12.6	2.315	3.858	No	DR010A0231	50

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD055CP43B-21 VFD055CP4EB-21	5.5	7.5	13	15.6	2.025	3.375	No	DR012A0202	50
VFD075CP43B-21 VFD075CP4EB-21	7.5	10	18	21.6	1.35	2.25	No	DR018A0117	54
VFD110CP43B-21 VFD110CP4EB-21	11	15	24	28.8	1.01	1.683	No	DR024AP881	60
VFD150CP43B-21 VFD150CP4EB-21	15	20	32	38.4	0.76	1.267	No	DR032AP660	80
VFD185CP43B-21 VFD185CP4EB-21	18.5	25	38	45.6	0.639	1.065	No	DR038AP639	85
VFD220CP43A-21 VFD220CP4EA-21	22	30	45	54	0.541	0.902	No	DR045AP541	95
VFD300CP43B-21 VFD300CP4EB-21	30	40	60	72	0.405	0.675	No	DR060AP405	100
VFD370CP43B-21 VFD370CP4EB-21	37	50	73	87.6	0.334	0.557	No	DR073AP334	115
VFD450CP43S-00 VFD450CP43S-21	45	60	91	109.2	0.267	0.445	Yes	DR091AP267	130
VFD550CP43S-00 VFD550CP43S-21	55	75	110	132	0.221	0.368	Yes	DR110AP221	150
VFD750CP43B-00 VFD750CP43B-21	75	100	150	180	0.162	0.27	Yes	DR150AP162	170
VFD900CP43A-00 VFD900CP43A-21	90	125	180	216	0.135	0.225	Yes	DR180AP135	190
VFD1100CP43A-00 VFD1100CP43A-21	110	150	220	264	0.11	0.183	Yes	DR220AP110	230
VFD1320CP43B-00 VFD1320CP43B-21	132	175	260	312	0.098	0.163	Yes	DR260AP098	280
VFD1600CP43A-00 VFD1600CP43A-21	160	215	310	372	0.078	0.13	Yes	DR310AP078	300
VFD1850CP43B-00 VFD1850CP43B-21	185	250	370	444	0.066	0.11	Yes	DR370AP066	340
VFD2000CP43A-00 VFD2000CP43A-21	200	270	395	474	0.061	0.1	Yes	DR460AP054*1	400
VFD2200CP43A-00 VFD2200CP43A-21	220	300	460	552	0.054	0.09	Yes	DR460AP054	400
VFD2500CP43A-00 VFD2500CP43A-21	250	340	481	578	0.052	0.086	Yes	DR550AP044*1	430
VFD2800CP43A-00 VFD2800CP43A-21	280	375	530	636	0.044	0.073	Yes	DR550AP044	430
VFD3150CP43A-00 VFD3150CP43C-00 VFD3150CP43C-21	315	420	616	739.2	0.039	0.065	Yes	DR616AP039	450
VFD3550CP43A-00 VFD3550CP43C-00 VFD3550CP43C-21	355	475	683	819.6	0.036	0.06	Yes	DR683AP036	480
VFD4000CP43A-00 VFD4000CP43C-00 VFD4000CP43C-21	400	530	770	924	0.028	0.047	Yes	DR866AP028	610

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD5000CP43A-00 VFD5000CP43C-00 VFD5000CP43C-21	500	930	912	1094.4	0.028	0.043	Yes	DR866AP028	610
VFD5600CP43A-00 VFD5600CP43C-21	560	750	1094	1318.2	0.022	0.037	Yes	Contact Delta	
VFD6300CP43A-00 VFD6300CP43C-21	630	850	1212	1454.4	0.020	0.033	Yes		
*Note 1: The inductance value for the above applications of Delta's reactors will be closer, but less than 3%. Note 2: The above heat dissipation is calculated based on AC reactor's rated current; the actual dissipation varies with the operation current.									

Table 7-21

380V–460V, 50 / 60 Hz, Normal Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP43A-21 VFD007CP4EA-21	0.75	1	2.8	4.48	9.058	15.097	No	DR003A0810*[1]	20
VFD015CP43B-21 VFD015CP4EB-21	1.5	2	3	4.8	8.102	13.503	No	DR003A0810	20
VFD022CP43B-21 VFD022CP4EB-21	2.2	3	4	6.4	6.077	10.128	No	DR004A0607	21
VFD037CP43B-21 VFD037CP4EB-21	3.7	5	6	9.6	4.05	6.75	No	DR006A0405	31
VFD040CP43A-21 VFD040CP4EA-21	4	5	9	14.4	2.7	4.5	No	DR009A0270	40
VFD055CP43B-21 VFD055CP4EB-21	5.5	7.5	10.5	16.8	2.315	3.858	No	DR010A0231	50
VFD075CP43B-21 VFD075CP4EB-21	7.5	10	12	19.2	2.025	3.375	No	DR012A0202	50
VFD110CP43B-21 VFD110CP4EB-21	11	15	18	28.8	1.35	2.25	No	DR018A0117	54
VFD150CP43B-21 VFD150CP4EB-21	15	20	24	38.4	1.01	1.683	No	DR024AP881	60
VFD185CP43B-21 VFD185CP4EB-21	18.5	25	32	51.2	0.76	1.267	No	DR032AP660	80
VFD220CP43A-21 VFD220CP4EA-21	22	30	38	60.8	0.639	1.065	No	DR038AP639	85
VFD300CP43B-21 VFD300CP4EB-21	30	40	45	72	0.541	0.902	No	DR045AP541	95
VFD370CP43B-21 VFD370CP4EB-21	37	50	60	96	0.405	0.675	No	DR060AP405	100
VFD450CP43S-00 VFD450CP43S-21	45	60	73	116.8	0.334	0.557	Yes	DR073AP334	115
VFD550CP43S-00 VFD550CP43S-21	55	75	91	145.6	0.267	0.445	Yes	DR091AP267	130
VFD750CP43B-00 VFD750CP43B-21	75	100	110	176	0.221	0.368	Yes	DR110AP221	150
VFD900CP43A-00 VFD900CP43A-21	90	125	150	240	0.162	0.27	Yes	DR150AP162	170

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Input AC Reactor Delta Part #	Heat Dissipation (W)
VFD1100CP43A-00 VFD1100CP43A-21	110	150	180	288	0.135	0.225	Yes	DR180AP135	190
VFD1320CP43B-00 VFD1320CP43B-21	132	175	220	352	0.11	0.183	Yes	DR220AP110	230
VFD1600CP43A-00 VFD1600CP43A-21	160	215	260	416	0.098	0.163	Yes	DR260AP098	280
VFD1850CP43B-00 VFD1850CP43B-21	185	250	310	496	0.078	0.13	Yes	DR310AP078	300
VFD2000CP43A-00 VFD2000CP43A-21	200	270	335	536	0.072	0.12	Yes	DR370AP066[*1]	340
VFD2200CP43A-00 VFD2200CP43A-21	220	300	370	592	0.066	0.11	Yes	DR370AP066	340
VFD2500CP43A-00 VFD2500CP43A-21	250	340	415	664	0.058	0.10	Yes	DR460AP054[*1]	400
VFD2800CP43A-00 VFD2800CP43A-21	280	375	460	736	0.054	0.09	Yes	DR460AP054	400
VFD3150CP43A-00 VFD3150CP43C-00 VFD3150CP43C-21	315	420	550	880	0.044	0.073	Yes	DR550AP044	430
VFD3550CP43A-00 VFD3550CP43C-00 VFD3550CP43C-21	355	475	616	985.6	0.039	0.065	Yes	DR616AP039	450
VFD4000CP43A-00 VFD4000CP43C-00 VFD4000CP43C-21	400	530	683	1092.8	0.036	0.06	Yes	DR683AP036	480
VFD5000CP43A-00 VFD5000CP43C-00 VFD5000CP43C-21	500	930	866	1385.6	0.028	0.047	Yes	DR866AP028	610
VFD5600CP43A-00 VFD5600CP43C-21	560	750	930	1488	0.026	0.043	Yes	Contact Delta	
VFD6300CP43A-00 VFD6300CP43C-21	630	850	1094	1750.4	0.022	0.037	Yes		

*Note 1: The inductance value for the above applications of Delta's reactors will be closer, but less than 3%.

Note 2: The above heat dissipation is calculated based on AC reactor's rated current; the actual dissipation varies with the operation current.

Table 7-22

575 V, 50 / 60 Hz, Three-phase

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)	3% Reactor (mH)		5% Reactor (mH)	
			Normal Duty	Light Duty		Normal Duty	Light Duty	Normal Duty	Light Duty
VFD015CP53A-21	1.5	2	2.5	3	4.2	10.567	8.806	17.612	14.677
VFD022CP53A-21	2.2	3	3.6	4.3	5.9	7.338	6.144	12.230	10.239
VFD037CP53A-21	3.7	5	5.5	6.7	9.1	4.803	3.943	8.005	6.572
VFD055CP53A-21	5.5	7.5	8.2	9.9	13.7	3.222	2.668	5.369	4.447
VFD075CP53A-21	7.5	10	10	12.1	16.5	2.642	2.183	4.403	3.639
VFD110CP53A-21	11	15	15.5	18.7	25.7	1.704	1.413	2.841	2.355
VFD150CP53A-21	15	20	20	24.2	33.3	1.321	1.092	2.201	1.819

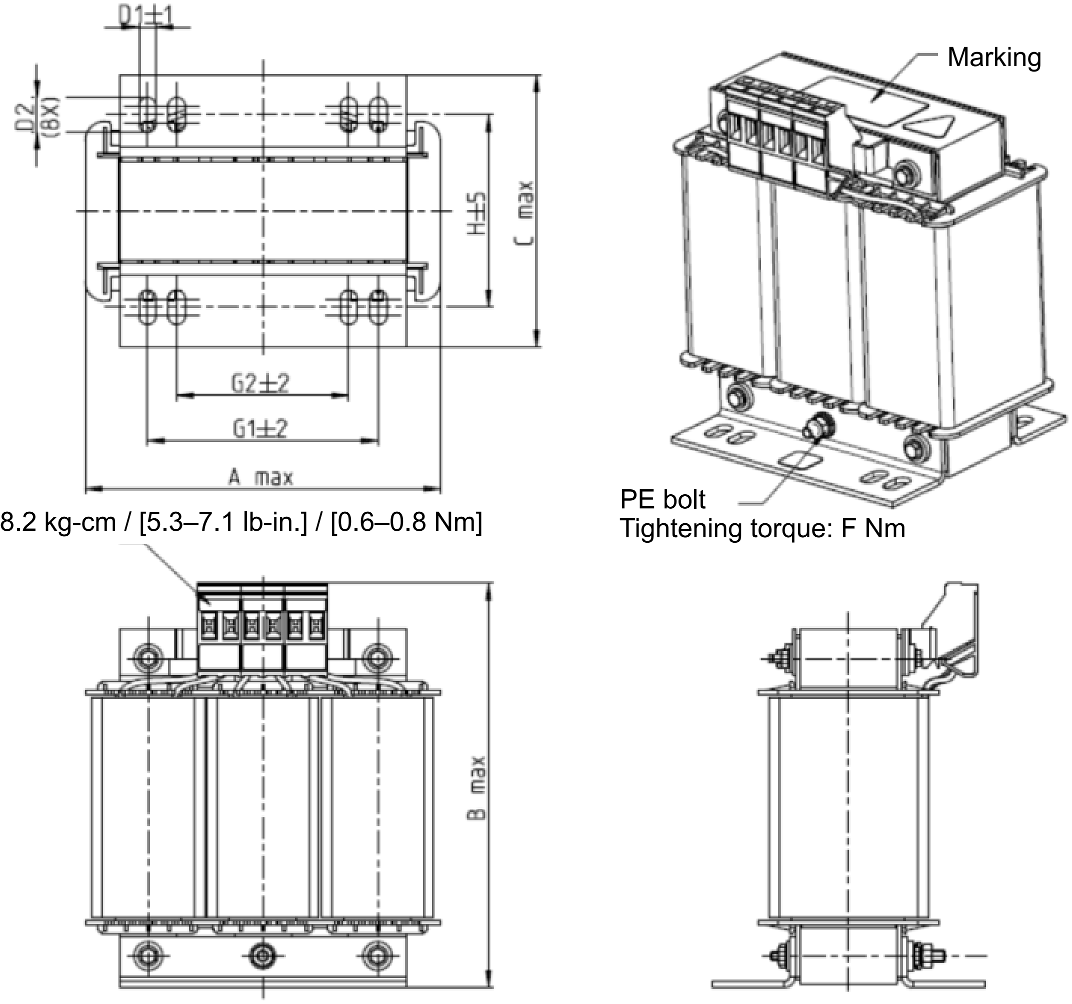
Table 7-23

690V, 50 / 60 Hz, Three-phase

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)		3% Impedance (mH)		5% Impedance (mH)	
			Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty
VFD185CP63A-21	18.5	25	20	24	30.0	28.8	1.902	1.585	3.170	2.642
VFD220CP63A-21	22	30	24	30	36.0	36.0	1.585	1.268	2.642	2.113
VFD300CP63A-21	30	40	30	36	45.0	43.2	1.268	1.057	2.113	1.761
VFD370CP63A-21	37	50	36	45	54.0	54.0	1.057	0.845	1.761	1.409
VFD450CP63A-00/-21	45	60	45	54	67.5	64.8	0.845	0.704	1.409	1.174
VFD550CP63A-00/-21	55	75	54	67	81.0	80.4	0.704	0.568	1.174	0.946
VFD750CP63A-00/-21	75	100	67	86	100.5	103.2	0.568	0.442	0.946	0.737
VFD900CP63A-00/-21	90	125	86	104	129.0	124.8	0.442	0.366	0.737	0.610
VFD1100CP63A-00/-21	110	150	104	125	156.0	150.0	0.366	0.304	0.610	0.507
VFD1320CP63A-00/-21	132	175	125	150	187.5	180.0	0.304	0.254	0.507	0.423
VFD1600CP63A-00/-21	160	215	150	180	225.0	216.0	0.254	0.211	0.423	0.352
VFD2000CP63A-00/-21	200	270	180	220	270.0	264.0	0.211	0.173	0.352	0.288
VFD2500CP63A-00/-21	250	335	220	290	330.0	348.0	0.173	0.131	0.288	0.219
VFD3150CP63A-00/-21	315	425	290	350	435.0	420.0	0.131	0.109	0.219	0.181
VFD4000CP63A-00/-21	400	530	350	430	525.0	516.0	0.109	0.088	0.181	0.147
VFD4500CP63A-00/-21	450	600	385	465	577.5	558.0	0.099	0.082	0.165	0.136
VFD5600CP63A-00/-21	560	745	465	590	697.5	708.0	0.082	0.064	0.136	0.107
VFD6300CP63A-00/-21	630	850	675	675	1012.5	810.0	0.056	0.056	0.094	0.094

Table 7-24

AC input reactor dimension and specification:



Tightening torque: 6.1–8.2 kg-cm / [5.3–7.1 lb-in.] / [0.6–0.8 Nm]

Tightening torque: F Nm

Figure 7-7

Unit: mm

Input AC reactor Delta part #	A	B	C	D1*D2	E	G1	G2	PE D
DR005A0254	100	115	65	6*9	45	60	40	M4
DR008A0159	100	115	65	6*9	45	60	40	M4
DR011A0115	130	135	95	6*12	60	80.5	60	M4
DR017AP746	130	135	100	6*12	65	80.5	60	M4

Table 7-25

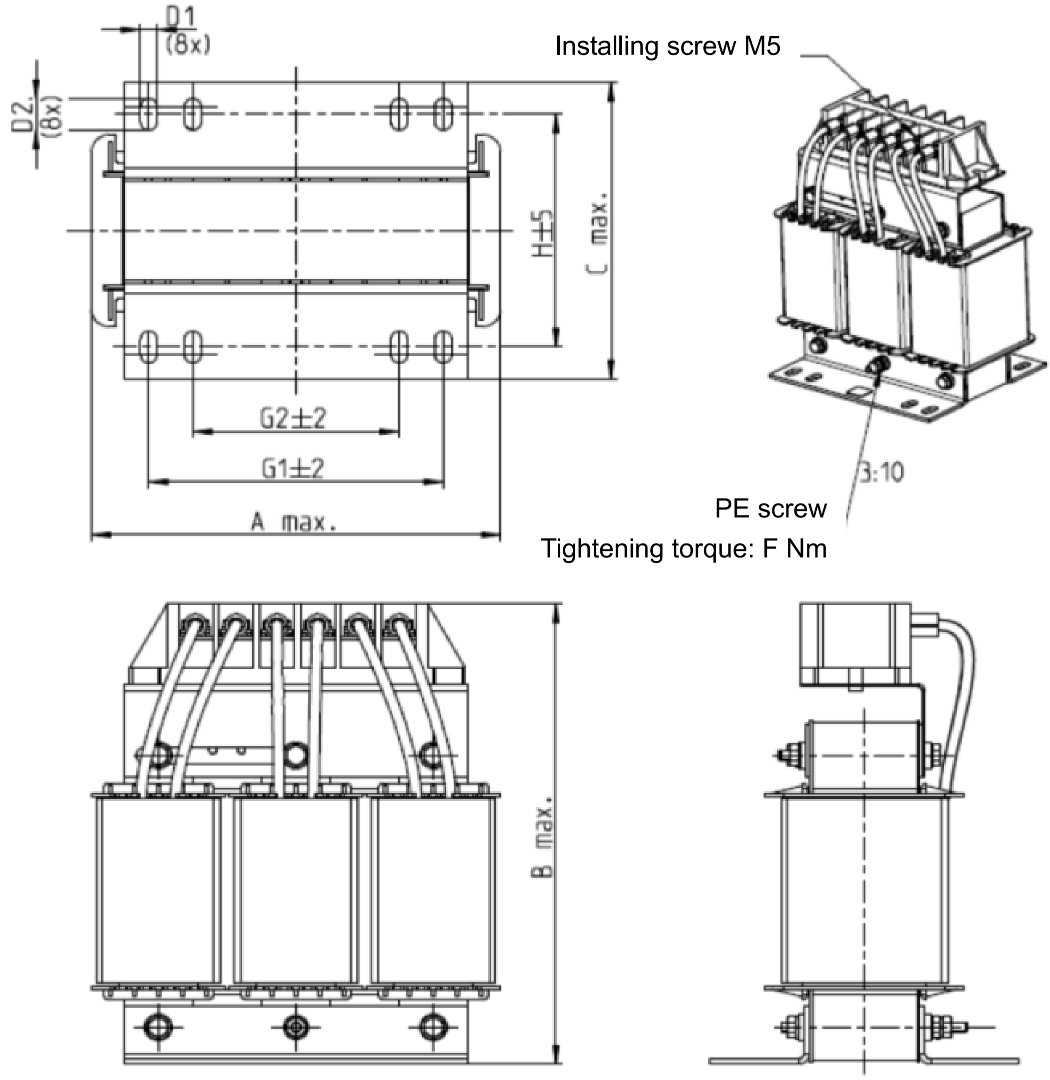
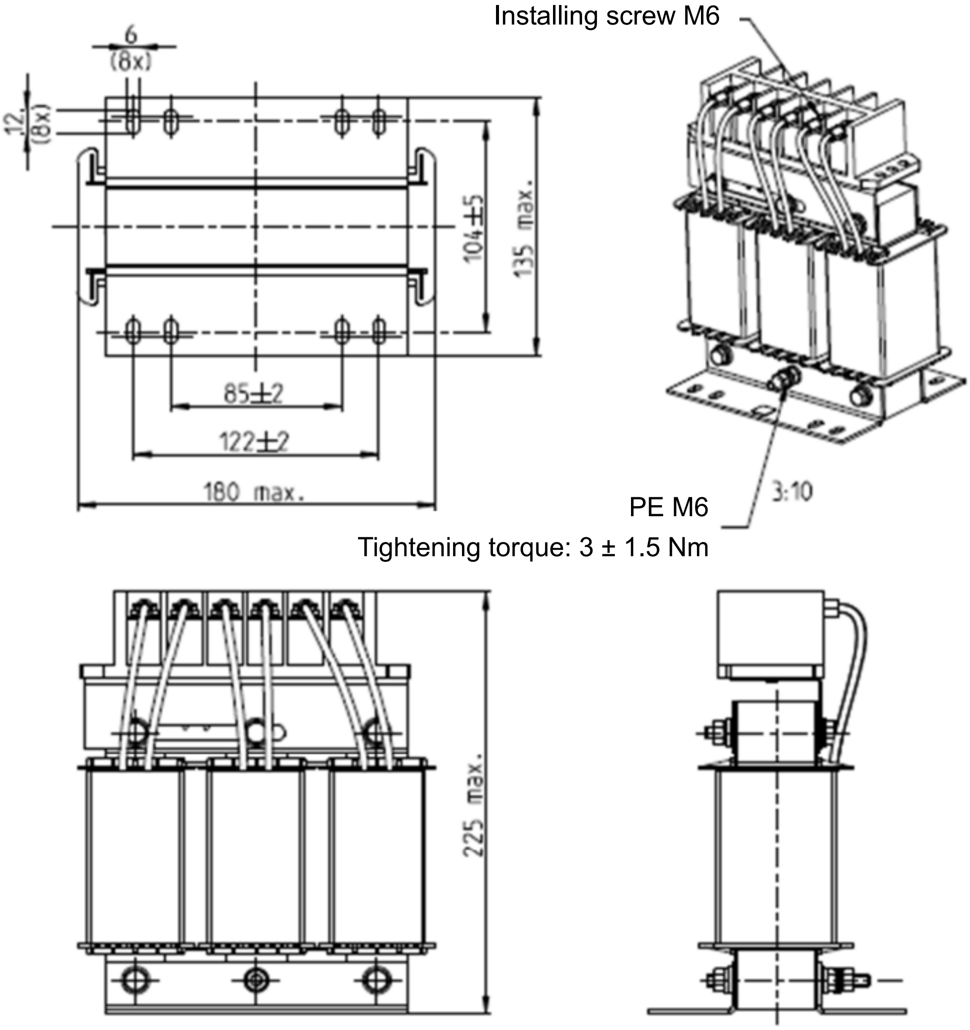


Figure 7-8

Unit: mm

Input AC reactor Delta part #	A	B	C	D1*D2	H	G1	G2	PE D
DR025AP215	130	195	100	6*12	65	80.5	60	M4
DR033AP163	130	195	100	6*12	65	80.5	60	M4
DR049AP163	160	200	125	6*12	90	107	75	M4

Table 7-26



Installing screw M6

PE M6

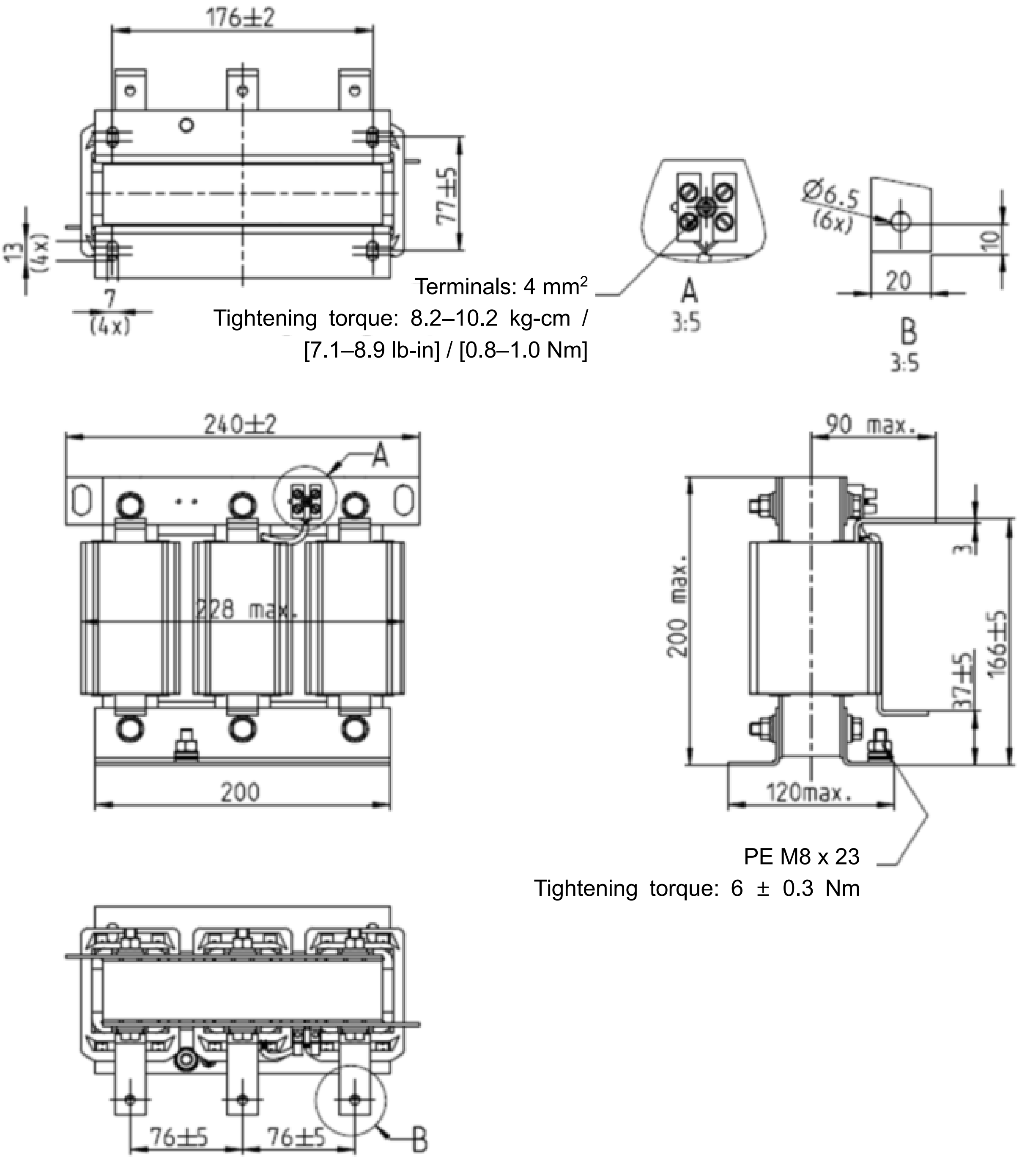
Tightening torque: 3 ± 1.5 Nm

Figure 7-9

Unit: mm

Input AC reactor Delta part #	Dimensions
DR065AP162	Refer to the diagram above

Table 7-27



Terminals: 4 mm^2
Tightening torque: 8.2–10.2 kg-cm / [7.1–8.9 lb-in] / [0.8–1.0 Nm]

PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-10

Unit: mm

Input AC reactor Delta part #	Dimensions
DR075AP170	Refer to the diagram above

Table 7-28

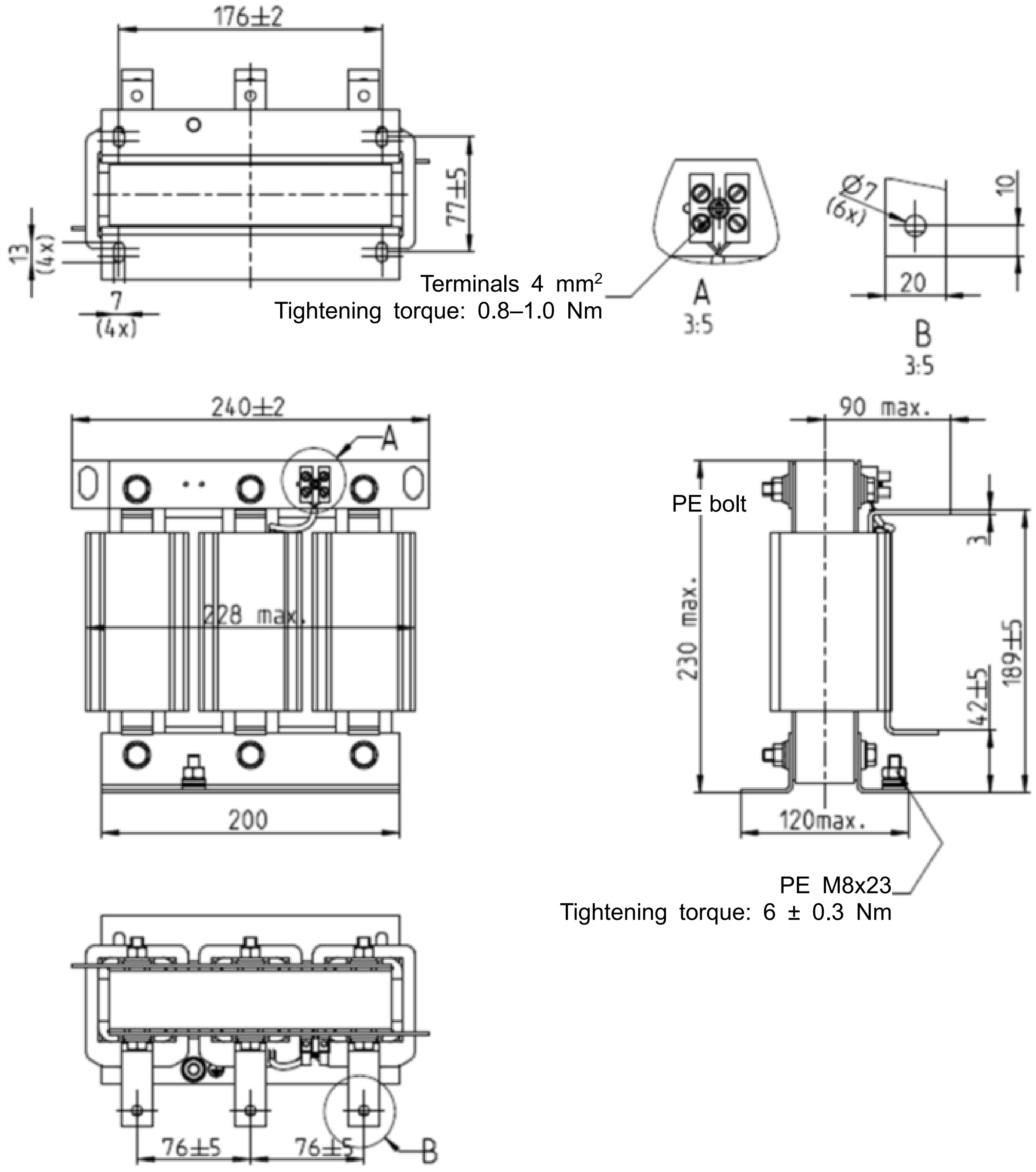
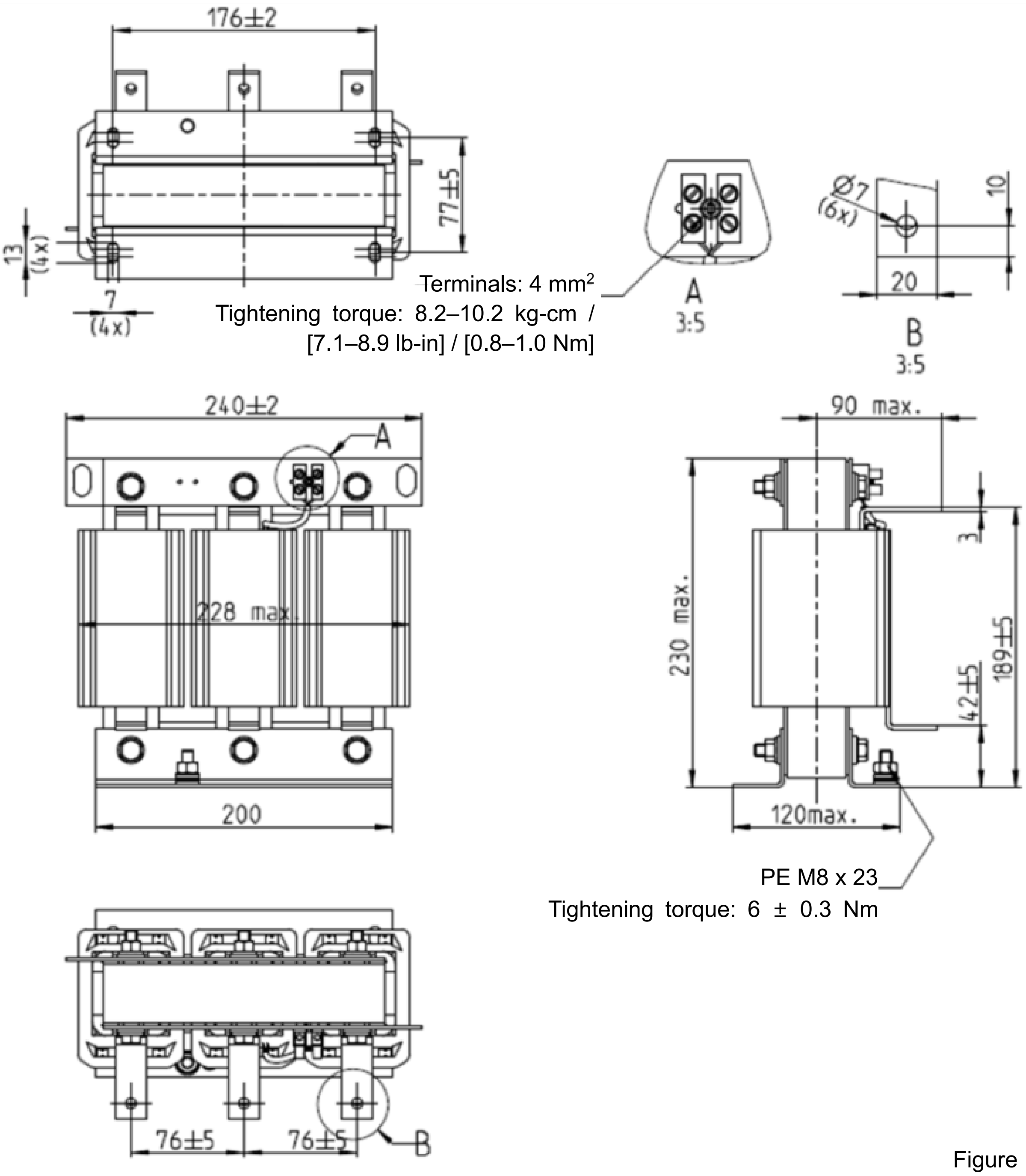


Figure 7-11

Unit: mm

Input AC reactor Delta part #	Dimensions
DR090AP141	Refer to the diagram above

Table 7-29



Terminals: 4 mm^2
Tightening torque: 8.2–10.2 kg-cm / [7.1–8.9 lb-in] / [0.8–1.0 Nm]

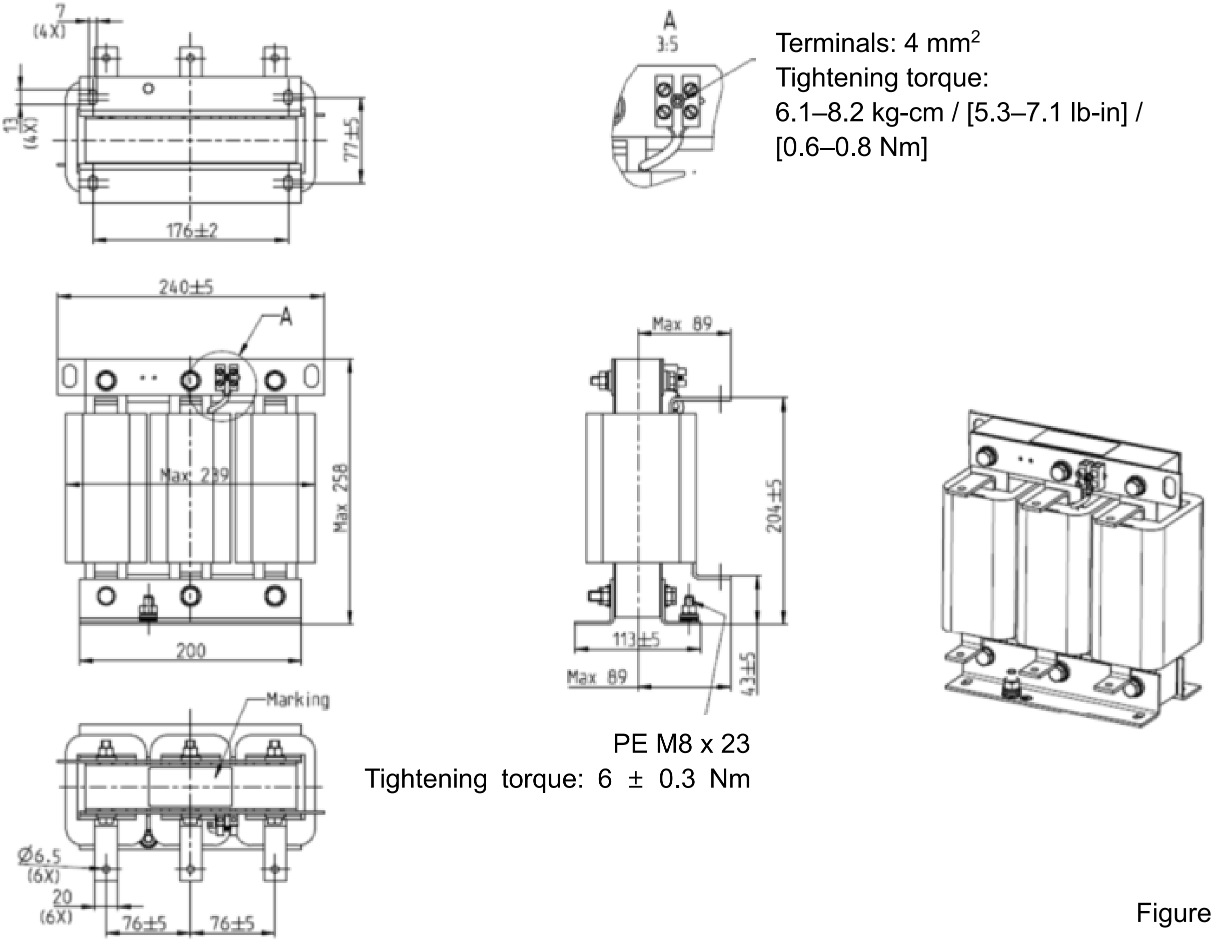
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-12

Unit: mm

Input AC reactor Delta part #	Dimensions
DR105AP106	Refer to the diagram above

Table 7-30



Terminals: 4 mm^2
Tightening torque:
6.1–8.2 kg-cm / [5.3–7.1 lb-in] /
[0.6–0.8 Nm]

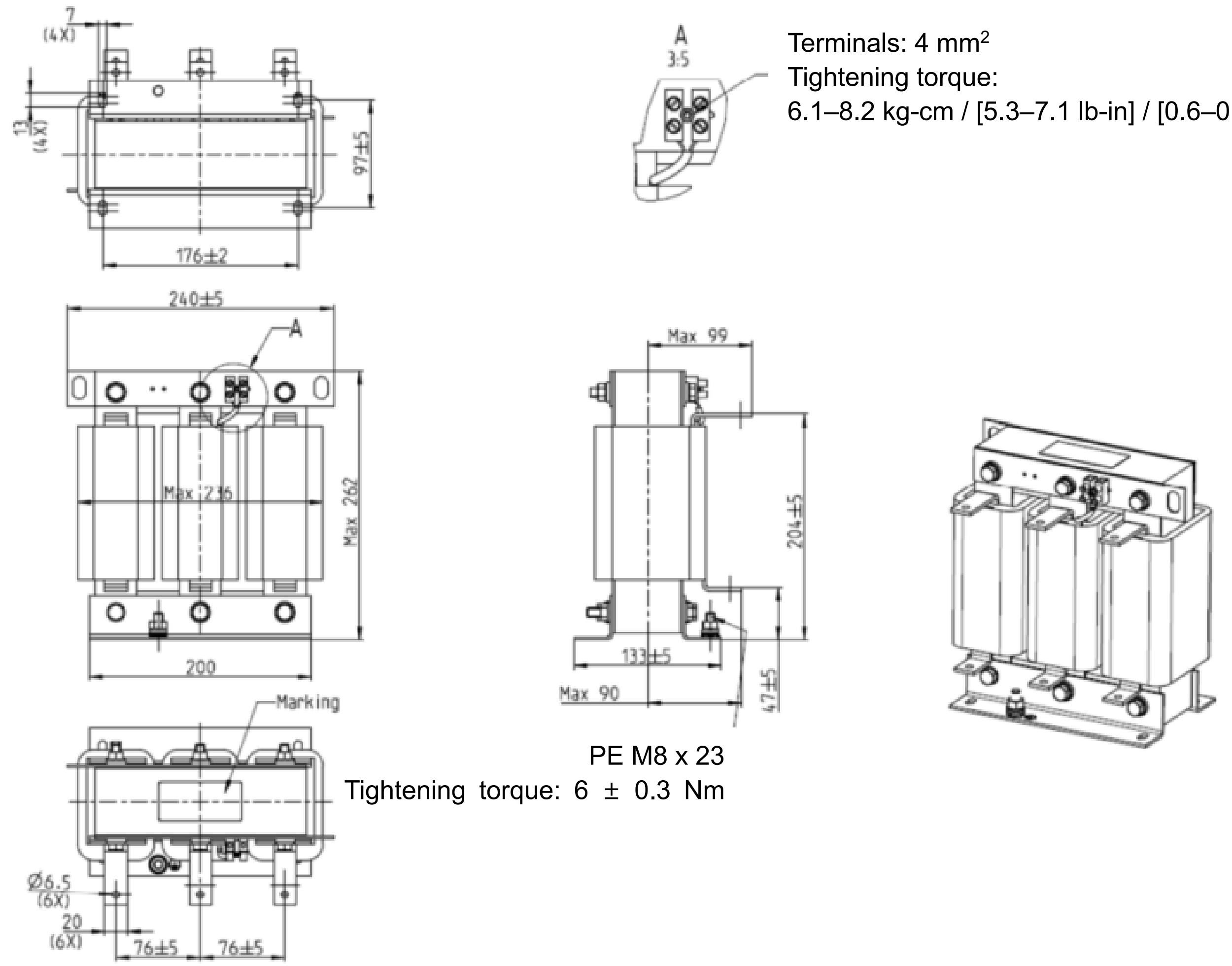
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-13

Unit: mm

Input AC reactor Delta part #	Dimensions
DR146AP087	Refer to the diagram above

Table 7-31



Terminals: 4 mm^2
Tightening torque:
6.1–8.2 kg-cm / [5.3–7.1 lb-in] / [0.6–0.8 Nm]

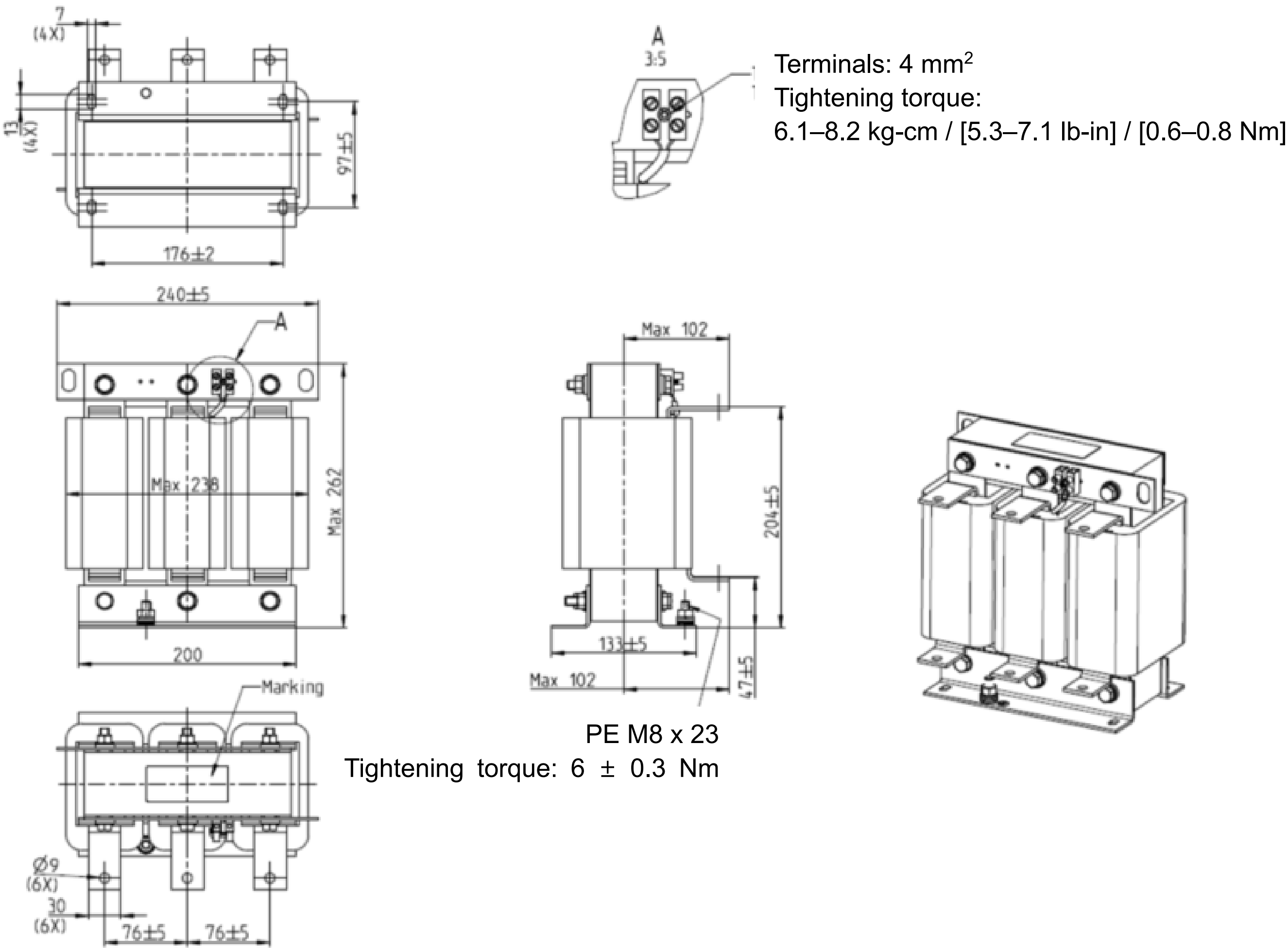
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-14

Unit: mm

Input AC reactor Delta part #	Dimensions
DR180AP070	Refer to the diagram above

Table 7-32



Terminals: 4 mm^2
Tightening torque:
6.1–8.2 kg-cm / [5.3–7.1 lb-in] / [0.6–0.8 Nm]

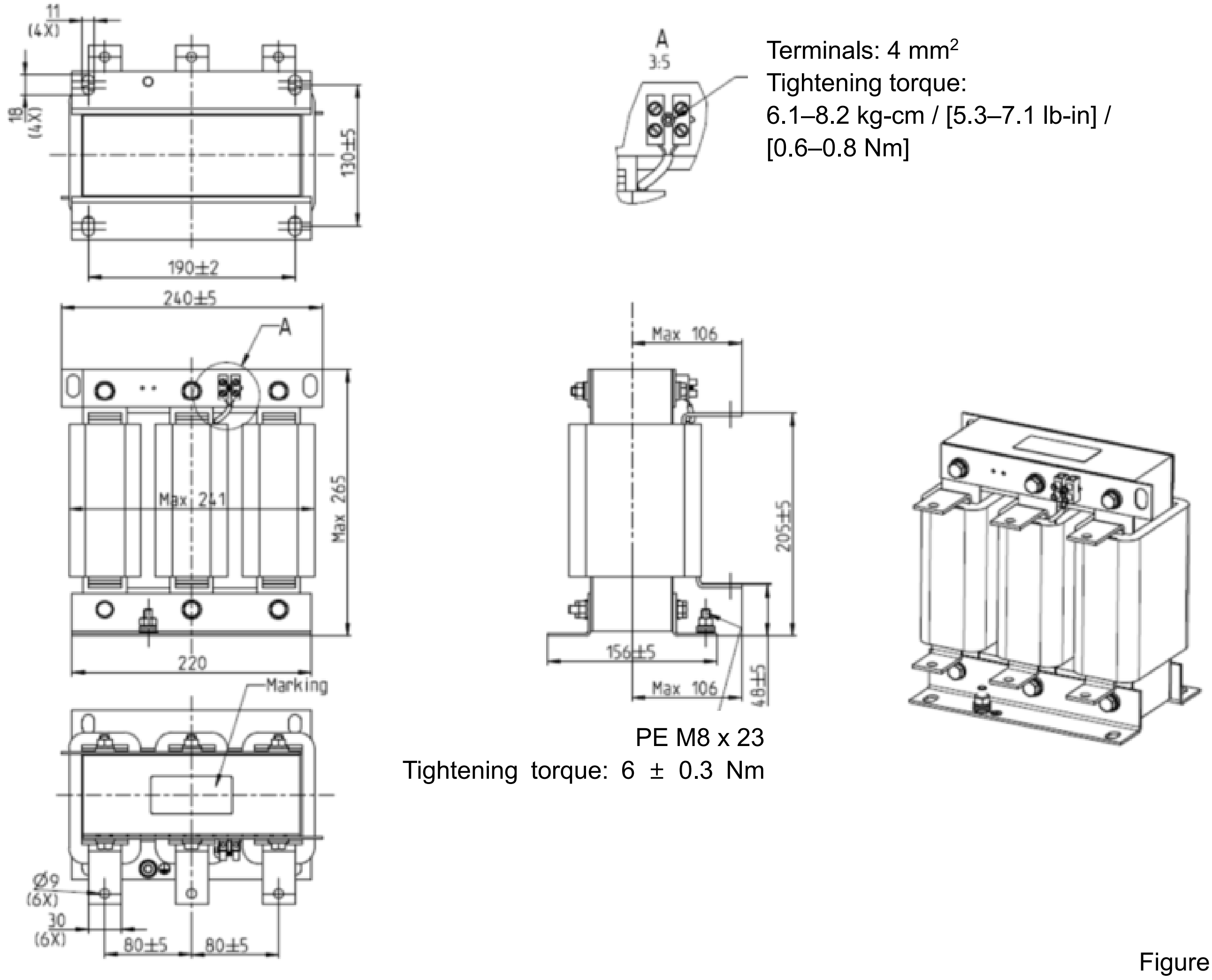
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-15

Unit: mm

Input AC reactor Delta part #	Dimensions
DR215AP059	Refer to the diagram above

Table 7-33



Terminals: 4 mm^2
Tightening torque:
6.1–8.2 kg-cm / [5.3–7.1 lb-in] /
[0.6–0.8 Nm]

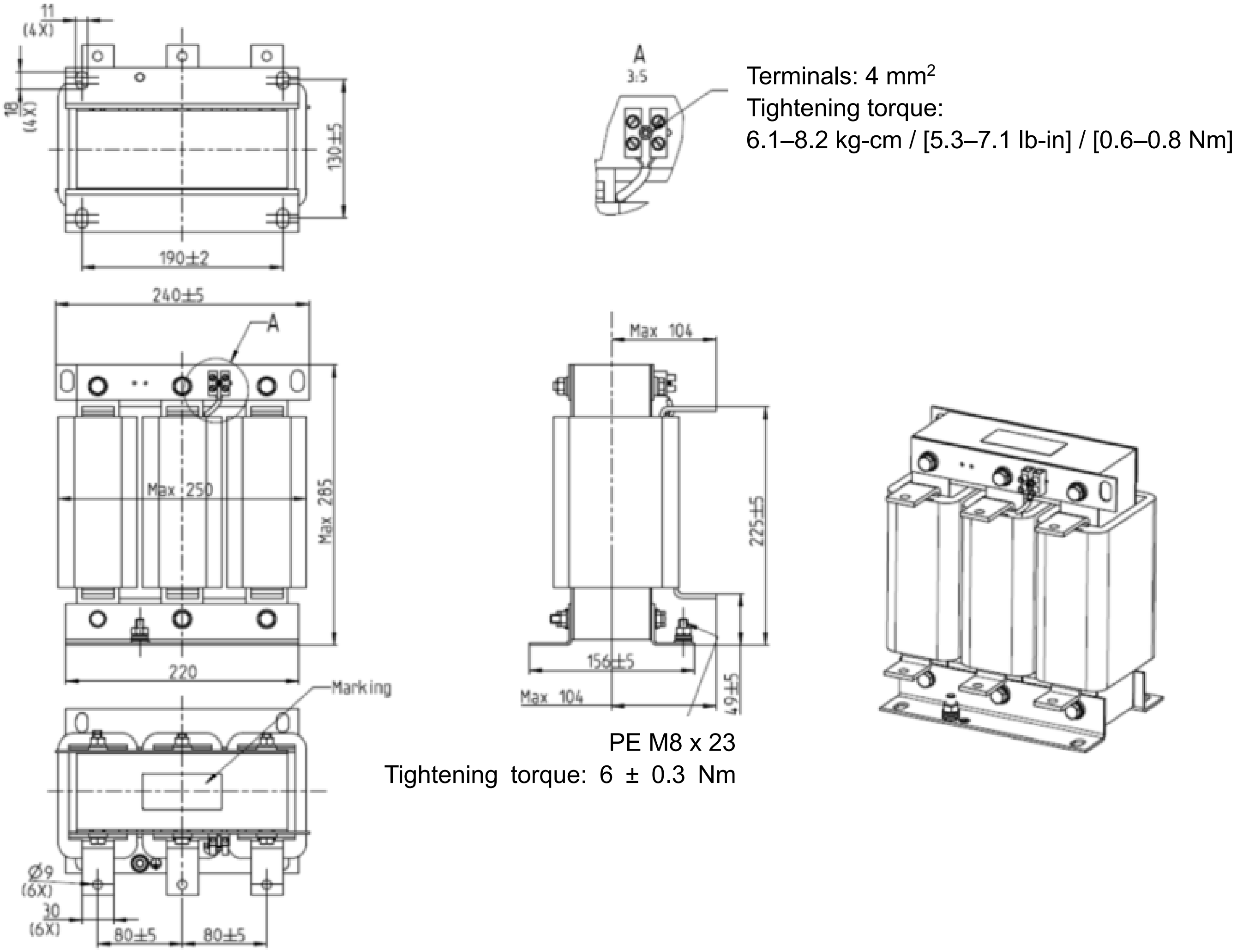
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-16

Unit: mm

Input AC reactor Delta part #	Dimensions
DR215AP059	Refer to the diagram above

Table 7-34



Terminals: 4 mm^2
Tightening torque:
6.1–8.2 kg-cm / [5.3–7.1 lb-in] / [0.6–0.8 Nm]

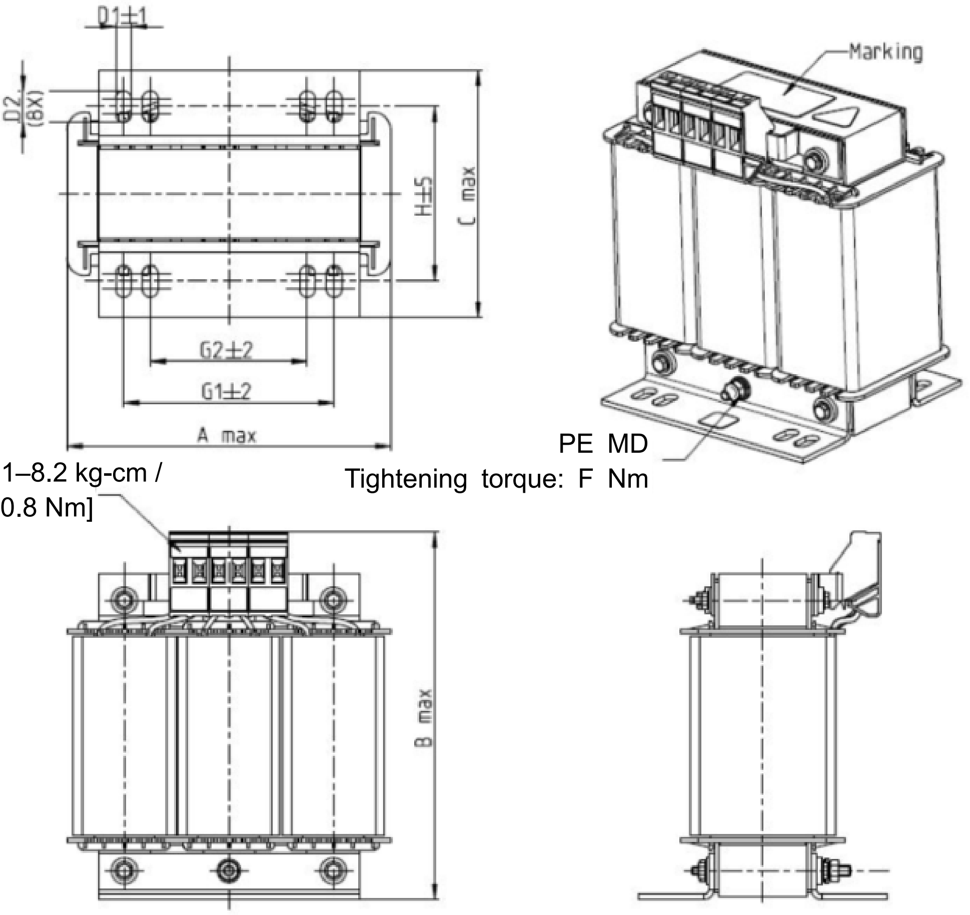
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-17

Unit: mm

Input AC reactor Delta part #	Dimensions
DR346AP037	Refer to the diagram above

Table 7-35



PE MD
Tightening torque: F Nm

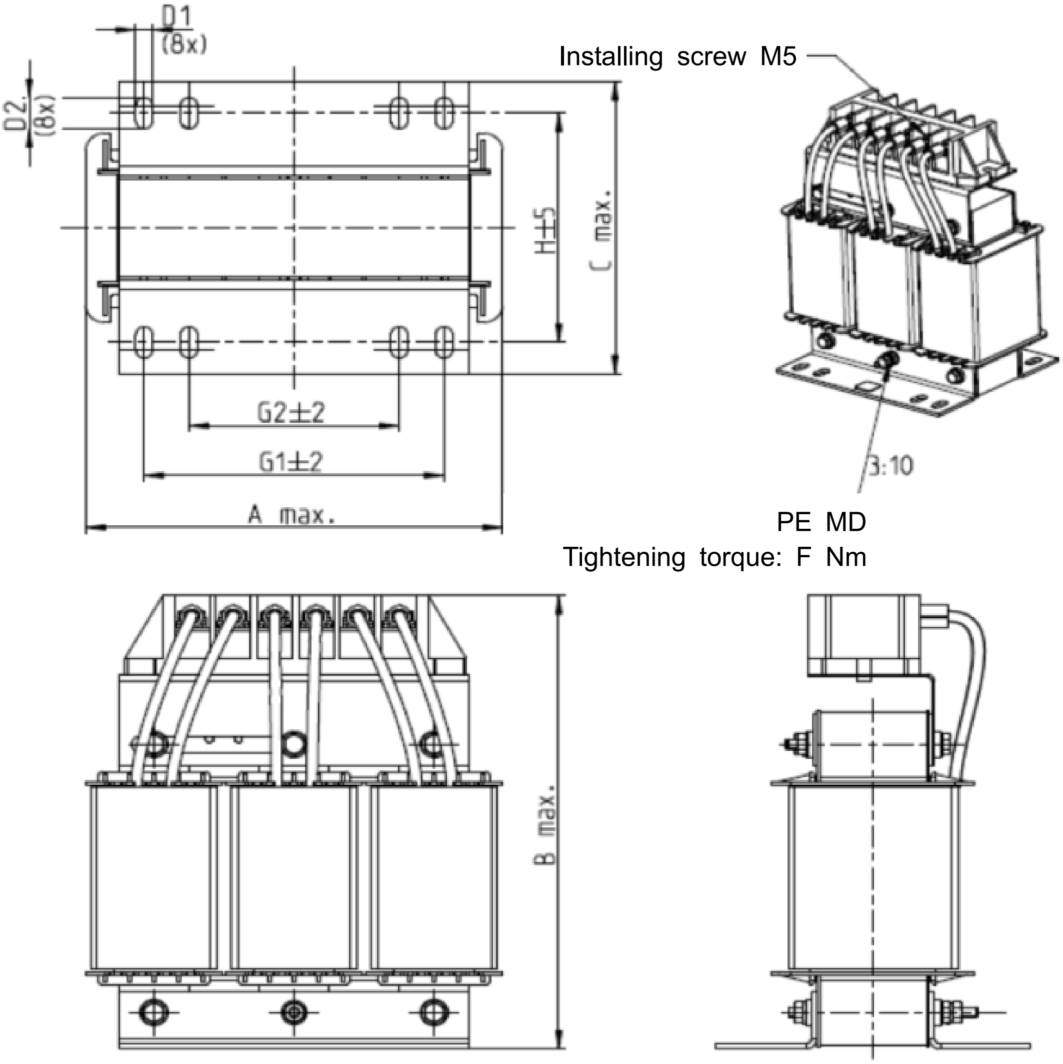
Tightening torque: 6.1–8.2 kg-cm /
[5.3–7.1 lb-in] / [0.6–0.8 Nm]

Figure 7-18

Unit: mm

Input AC reactor Delta part #	A	B	C	D1*D2	H	G1	G2	PE D
DR003A0810	100	125	65	6*9	43	60	40	M4
DR004A0607	100	125	65	6*9	43	60	40	M4
DR006A0405	130	15	95	6*12	60	80.5	60	M4
DR009A0270	160	160	105	6*12	75	107	75	M4
DR010A0231	160	160	115	6*12	90	107	75	M4
DR012A0202	160	160	115	6*12	90	107	75	M4
DR018A0117	160	160	115	6*12	90	107	75	M4

Table 7-36



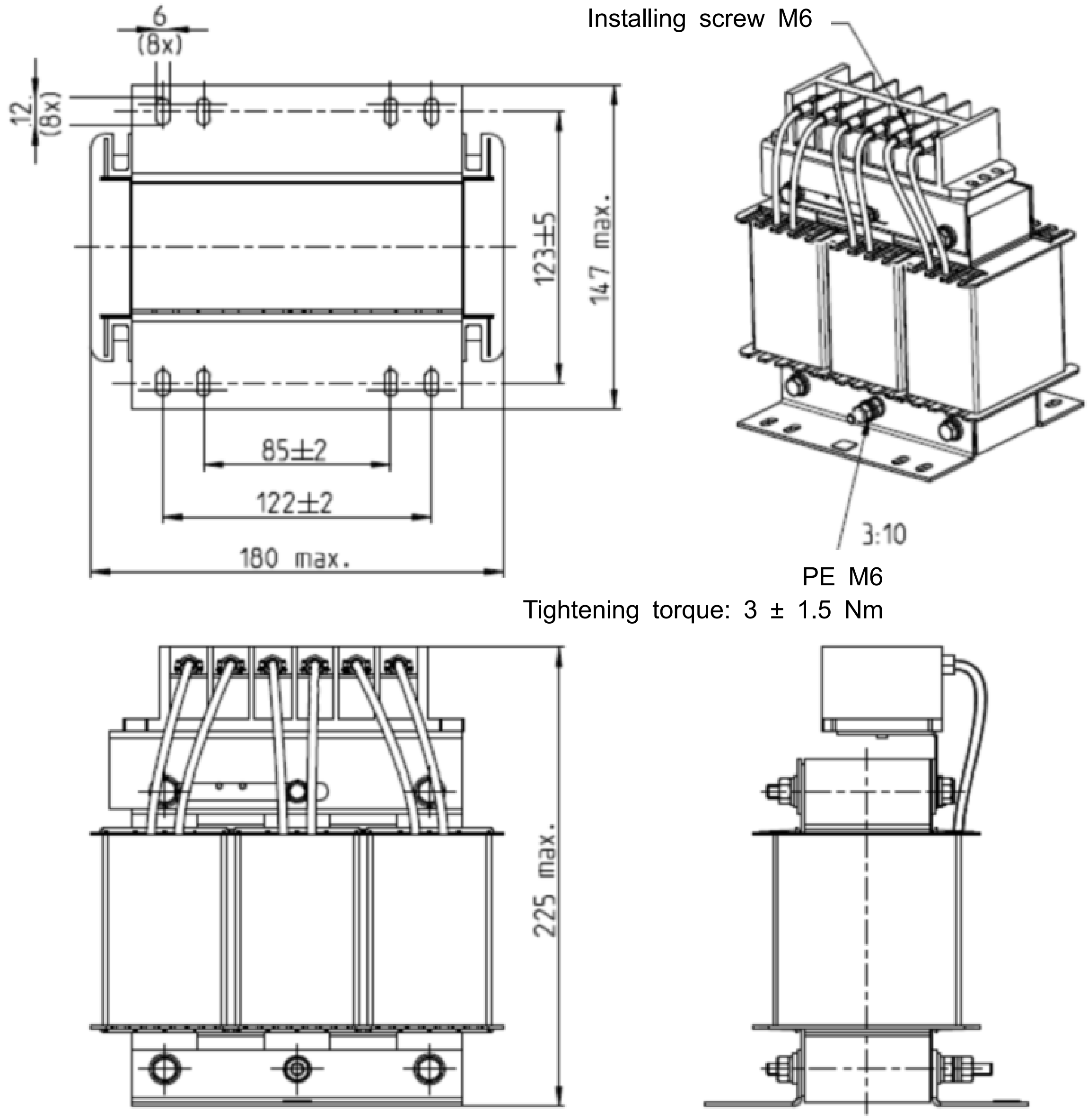
Installing screw M5

PE MD
Tightening torque: F Nm

Figure 7-19
Unit: mm

Input AC reactor Delta part #	A	B	C	D1*D2	H	G1	G2	PE D
DR024AP881	160	175	115	6*12	90	107	75	M4
DR032AP660	195	200	145	6*12	115	122	85	M6
DR038AP639	190	200	145	6*12	115	122	85	M6
DR045AP541	190	200	145	6*12	115	122	85	M6

Table 7-37



Installing screw M6

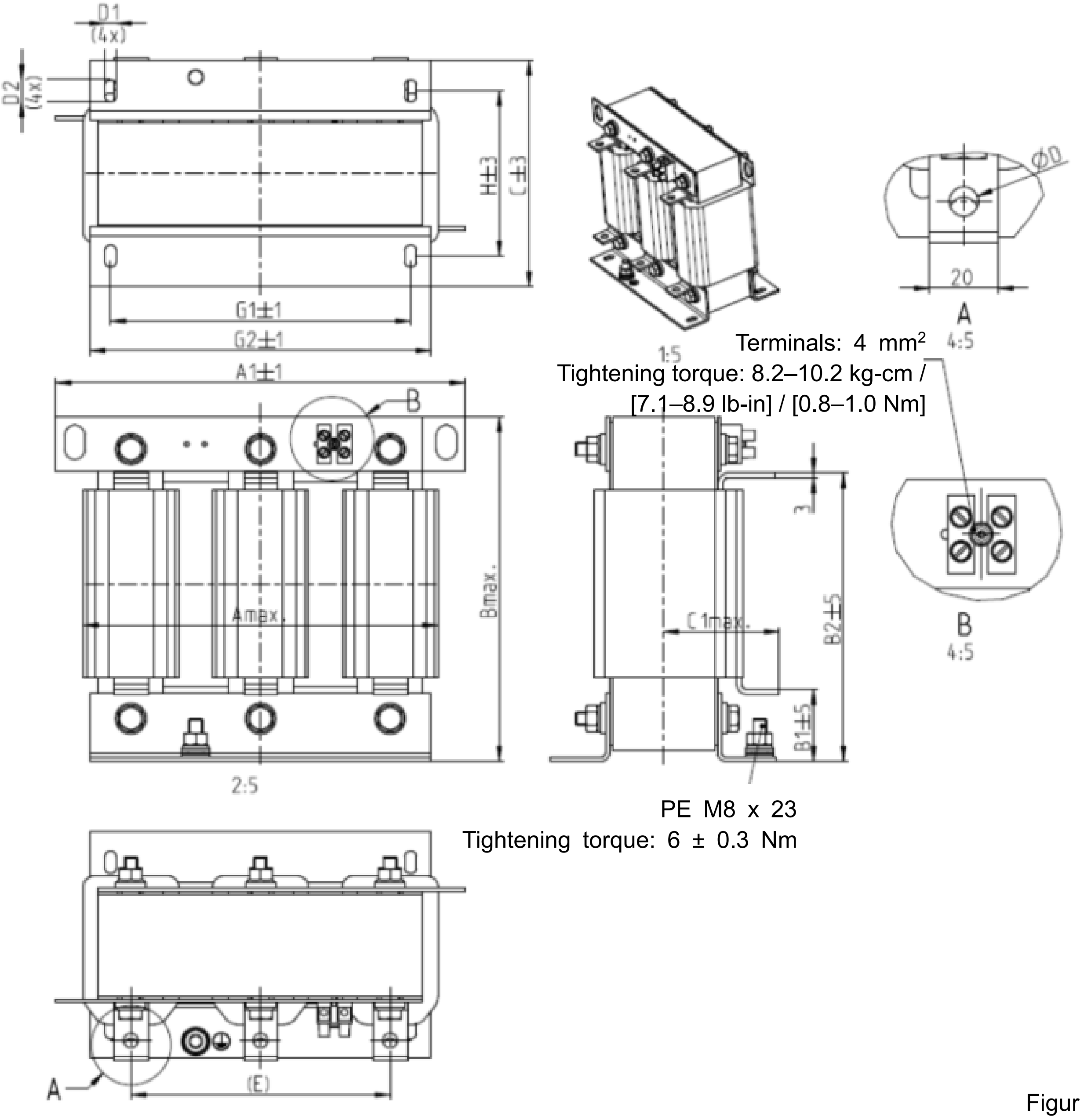
PE M6
Tightening torque: 3 ± 1.5 Nm

Figure 7-20

Unit: mm

Input AC reactor Delta part #	Dimensions
DR060AP405	Refer to the diagram above

Table 7-38



Terminals: 4 mm^2
Tightening torque: 8.2–10.2 kg-cm /
[7.1–8.9 lb-in] / [0.8–1.0 Nm]

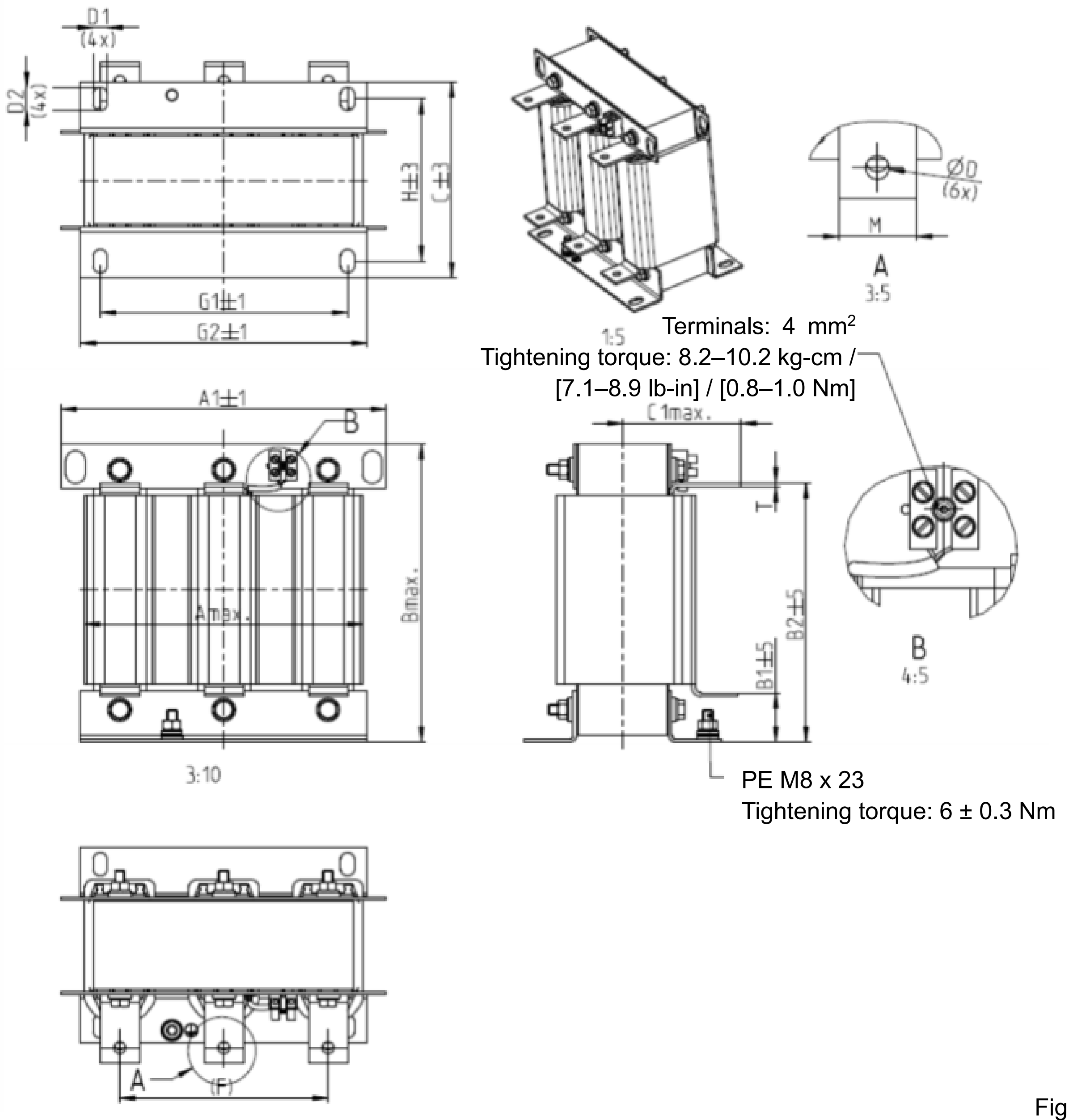
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-21

Unit: mm

Input AC reactor Delta part #	A	A1	B	B1	B2	C	D	D1*D2	E	C1	G1	G2	H
DR073AP334	228	240	215	40	170	133	8.5	7*13	152	75	176	200	97
DR091AP267	228	240	245	40	195	133	8.8	7*13	152	90	176	200	97
DR110AP221	228	240	245	40	195	138	8.5	7*13	152	75	176	200	102

Table 7-39



Terminals: 4 mm^2
Tightening torque: 8.2–10.2 kg-cm /
[7.1–8.9 lb-in] / [0.8–1.0 Nm]

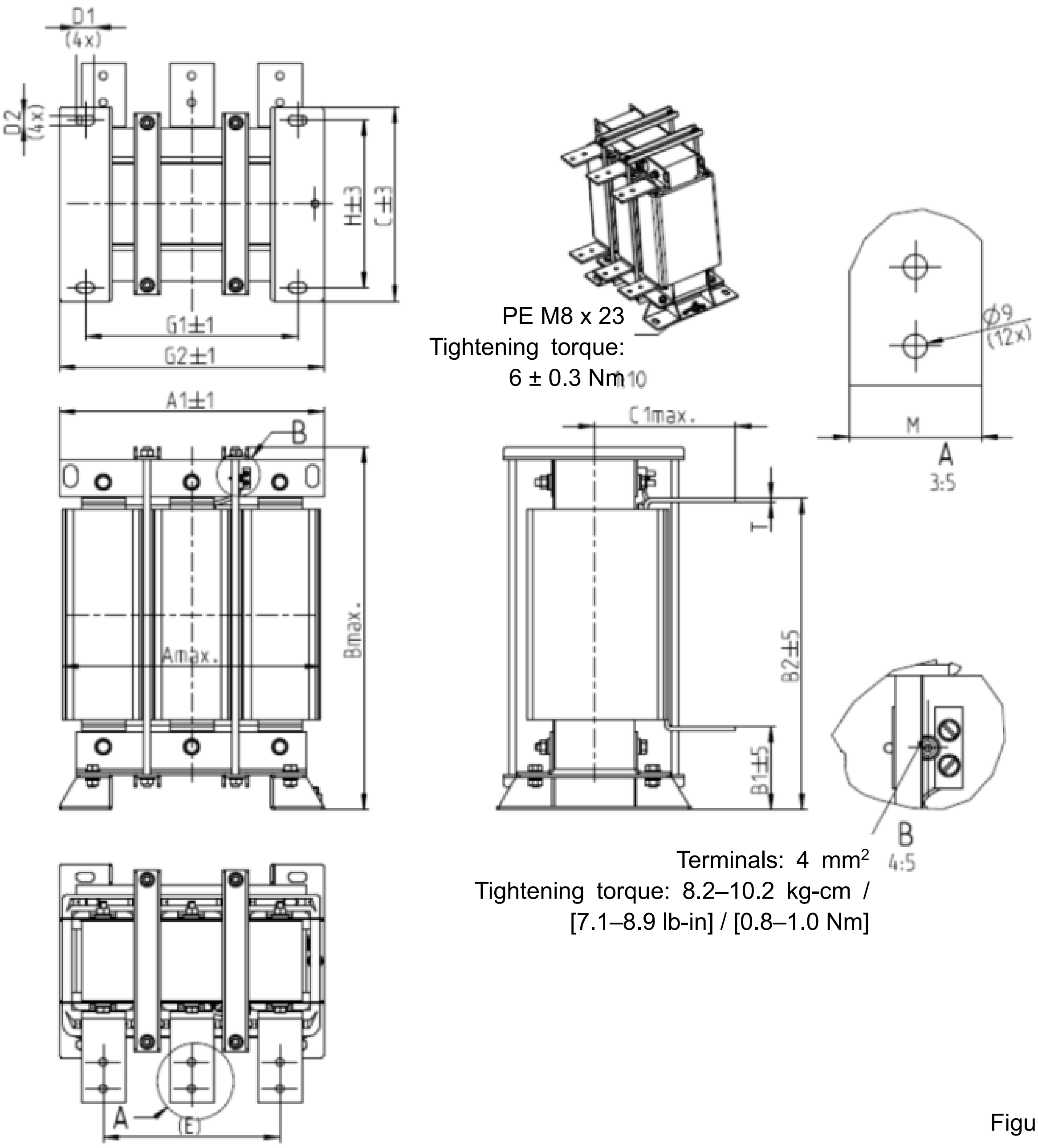
PE M8 x 23
Tightening torque: 6 ± 0.3 Nm

Figure 7-22

Unit: mm

Input AC reactor Delta part #	A	A1	B	B1	B2	C	C1	D	D1*D2	F	G1	G2	H	M*T
DR150AP162	240	250	245	40	200	151	105	9	11*18	160	190	220	125	20*3
DR180AP135	240	250	245	40	200	151	105	9	11*18	160	190	220	125	20*3
DR220AP110	264	270	275	50	230	151	105	9	10*18	176	200	230	106	30*3
DR260AP098	264	270	285	50	240	151	105	9	10*18	176	200	230	106	30*3
DR310AP078	300	300	345	55	295	153	105	9	10*18	200	224	260	113	30*3
DR370AP066	300	300	345	55	295	158	120	9	10*18	200	224	260	118	50*4

Table 7-40



PE M8 x 23
Tightening torque:
6 ± 0.3 Nm

Terminals: 4 mm^2
Tightening torque: 8.2–10.2 kg-cm /
[7.1–8.9 lb-in] / [0.8–1.0 Nm]

Figure 7-23

Unit: mm

Input AC reactor Delta part #	A	A1	B	B1	B2	C	C1	D1*D2	E	G1	G2	H	M*T
DR460AP054	300	300	425	95	355	220	170	11*21	200	240	300	190	50*4
DR550AP044	300	300	445	95	375	220	170	11*21	200	240	300	190	50*4
DR616AP039	360	360	465	105	385	252	190	11*21	240	246	316	220	50*5
DR683AP036	360	360	465	105	385	252	195	11*21	240	246	316	220	50*5
DR866AP028	360	360	520	105	435	272	200	11*21	240	246	316	240	60*6

Table 7-41

DC Reactor

A DC reactor can also increase line impedance, improve the power factor, reduce input current, increase system power, and reduce interference generated from the motor drive. A DC reactor stabilizes the DC bus voltage. Compared with an AC input reactor, a DC reactor is in smaller size, lower price, and lower voltage drop (lower power dissipation)

Installation

Install a DC reactor between terminals +2/DC+ and +1/DC+. Remove the jumper, as shown in the figure below, before installing a DC reactor.

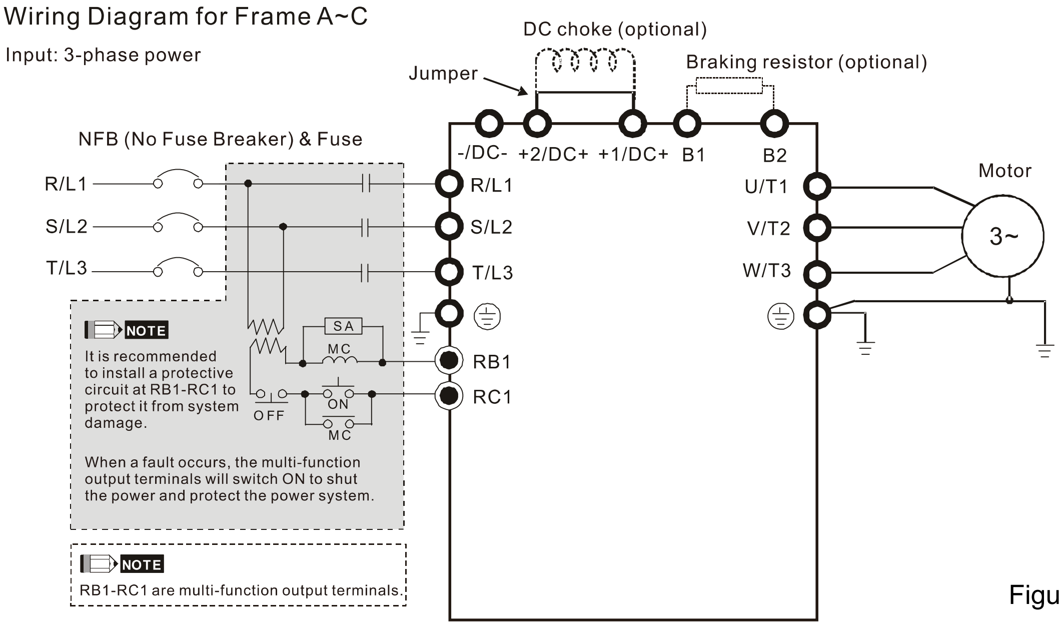

Wiring Diagram for Frame A~C
Input: 3-phase power
DC choke (optional)
Braking resistor (optional)
Jumper
NFB (No Fuse Breaker) & Fuse
-/DC-
+2/DC+
+1/DC+
B1
B2
R/L1
S/L2
T/L3
R/L1
S/L2
T/L3
U/T1
V/T2
W/T3
Motor
3~
SA
MC
OFF
ON
MC
RB1
RC1
NOTE
It is recommended to install a protective circuit at RB1-RC1 to protect it from system damage.
When a fault occurs, the multi-function output terminals will switch ON to shut the power and protect the power system.
NOTE
RB1-RC1 are multi-function output terminals.

Figure 7-24

Wiring of DC reactor

Specifications of DC reactors (standard item)

The following table shows the specifications of DC reactors (standard items) for Delta CP2000 series products.

200V–230V, 50 / 60 Hz

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)		DC Reactor (mH)		DC Reactor Delta Part #	
			Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty
VFD007CP23A-21	0.75	1	4.6	5	7.36	6	6.366	5.857	DR005D0585*	DR005D0585
VFD015CP23A-21	1.5	2	5	7.5	8	9	5.857	3.66	DR005D0585	DR008D0366
VFD022CP23A-21	2.2	3	8	10	12.8	12	3.66	2.662	DR008D0366	DR011D0266
VFD037CP23A-21	3.7	5	11	15	17.6	18	2.662	1.722	DR011D0266	DR017D0172
VFD055CP23A-21	5.5	7.5	17	21	27.2	25.2	1.722	1.172	DR017D0172	DR025D0117
VFD075CP23A-21	7.5	10	25	31	40	37.2	1.172	0.851	DR025D0117	DR033DP851
VFD110CP23A-21	11	15	33	46	52.8	55.2	0.851	0.574	DR033DP851	DR049DP574
VFD150CP23A-21	15	20	49	61	78.4	73.2	0.574	0.432	DR049DP574	DR065DP432
VFD185CP23A-21	18.5	25	65	75	104	90	0.432	0.391	DR065DP432	DR075DP391
VFD220CP23A-21	22	30	75	90	120	108	0.391	0.325	DR075DP391	DR090DP325
VFD300CP23A-21	30	40	90	105	144	126	0.325	0.244	DR090DP325	Contact Delta
*Note 1: Use with DR005D0585, but the inductance value will be 3% short.										

Table 7-42

380V–460V, 50 / 60 Hz

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)		DC Reactor (mH)		DC Reactor Delta Part #	
			Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty
VFD007CP43A-21/4EA-21	0.75	1	2.8	3	4.48	3.6	20.918	18.709	DR003D1870*	DR003D1870
VFD015CP43B-21/4EB-21	1.5	2	3	4.2	4.8	5.04	18.709	14.031	DR003D1870	DR004D1403
VFD022CP43B-21/4EB-21	2.2	3	4	5.5	6.4	6.6	14.031	9.355	DR004D1403	DR006D0935
VFD037CP43B-21/4EB-21	3.7	5	6	8.5	9.6	10.2	9.355	6.236	DR006D0935	DR009D0623
VFD040CP43A-21/4EA-21	4	5	9	10.5	14.4	12.6	6.236	5.345	DR009D0623	DR010D0534
VFD055CP43B-21/4EB-21	5.5	7.5	10.5	13	16.8	15.6	5.345	4.677	DR010D0534	DR012D0467
VFD075CP43B-21/4EB-21	7.5	10	12	18	19.2	21.6	4.677	3.119	DR012D0467	DR018D0311
VFD110CP43B-21/4EB-21	11	15	18	24	28.8	28.8	3.119	2.338	DR018D0311	DR024D0233
VFD150CP43B-21/4EB-21	15	20	24	32	38.4	38.4	2.338	1.754	DR024D0233	DR032D0175
VFD185CP43B-21/4EB-21	18.5	25	32	38	51.2	45.6	1.754	1.477	DR032D0175	DR038D0147
VFD220CP43A-21/4EA-21	22	30	38	45	60.8	54	1.477	1.247	DR038D0147	DR045D0124
VFD300CP43B-21/4EB-21	30	40	45	60	72	72	1.247	0.935	DR045D0124	DR060DP935
VFD370CP43B-21/4EB-21	37	50	60	73	96	87.6	0.935	0.768	DR060DP935	Contact Delta

*Note 1: Use with DR003D1870, but the inductance value will be 3% short.

Table 7-43

575 V, 50 / 60 Hz, Three-phase

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)	DC Reactor (mH)	
			Normal Duty	Light Duty		Normal Duty	Light Duty
VFD015CP53A-21	1.5	2	2.5	3	4.2	29.284	24.404
VFD022CP53A-21	2.2	3	3.6	4.3	5.9	20.336	17.027
VFD037CP53A-21	3.7	5	5.5	6.7	9.1	13.310	10.927
VFD055CP53A-21	5.5	7.5	8.2	9.9	13.7	8.929	7.394
VFD075CP53A-21	7.5	10	10	12.1	16.5	7.322	6.050
VFD110CP53A-21	11	15	15.5	18.7	25.7	4.722	3.916
VFD150CP53A-21	15	20	20	24.2	33.3	3.661	3.026

Table 7-44

690V, 50 / 60 Hz, Three-phase

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)		DC Reactor (mH)	
			Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty
VFD185CP63A-21	18.5	25	20	24	30.0	28.8	4.392	3.660
VFD220CP63A-21	22	30	24	30	36.0	36.0	3.660	2.928
VFD300CP63A-21	30	40	30	36	45.0	43.2	2.928	2.441
VFD370CP63A-21	37	50	36	45	54.0	54.0	2.441	1.951
VFD450CP63A-00/-21	45	60	45	54	67.5	64.8	1.951	1.626
VFD550CP63A-00/-21	55	75	54	67	81.0	80.4	1.626	1.312
VFD750CP63A-00/-21	75	100	67	86	100.5	103.2	1.312	1.021
VFD900CP63A-00/-21	90	125	86	104	129.0	124.8	1.021	0.845
VFD1100CP63A-00/-21	110	150	104	125	156.0	150.0	0.845	0.702
VFD1320CP63A-00/-21	132	175	125	150	187.5	180.0	0.702	0.587
VFD1600CP63A-00/-21	160	215	150	180	225.0	216.0	0.587	0.487

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)		DC Reactor (mH)	
			Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty
VFD2000CP63A-00/-21	200	270	180	220	270.0	264.0	0.487	0.400
VFD2500CP63A-00/-21	250	335	220	290	330.0	348.0	0.400	0.303
VFD3150CP63A-00/-21	315	425	290	350	435.0	420.0	0.303	0.252
VFD4000CP63A-00/-21	400	530	350	430	525.0	516.0	0.252	0.203
VFD4500CP63A-00/-21	450	600	385	465	577.5	558.0	0.229	0.189
VFD5600CP63A-00/-21	560	745	465	590	697.5	708.0	0.189	0.148
VFD6300CP63A-00/-21	630	850	675	675	1012.5	810.0	0.129	0.129

Table 7-45

DC reactor dimension and specification:

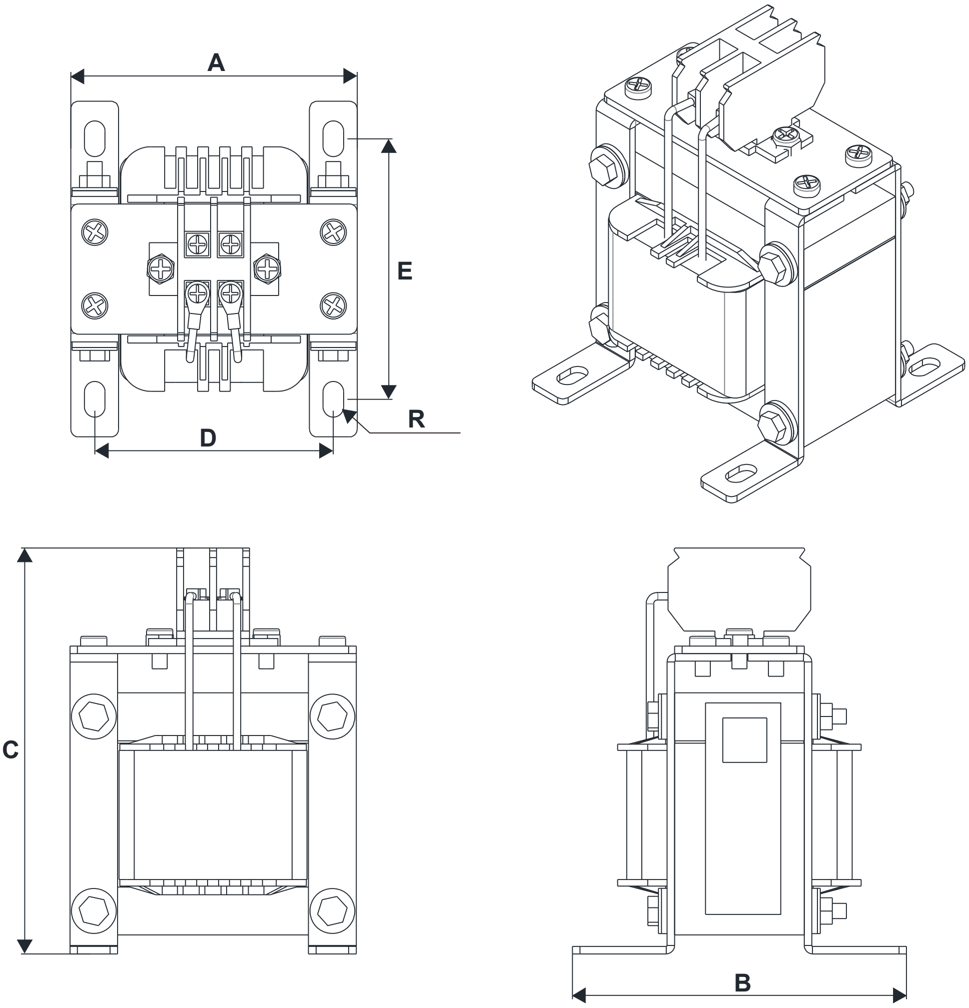


Figure 7-25

DC reactor Delta part #	A [mm)	B [mm]	C [mm]	D [mm]	E [mm]	Dimensions [mm]
DR005D0585	79	78	112	64 ± 2	56 ± 2	9.5*5.5
DR008D0366	79	78	112	64 ± 2	56 ± 2	9.5*5.5
DR011D0266	79	92	112	64 ± 2	69.5 ± 2	9.5*5.5
DR017D0172	79	112	112	64 ± 2	89.5 ± 2	9.5*5.5
DR025D0117	99	105	128	79 ± 2	82.5 ± 2	9.5*5.5
DR033DP851	117	110	156	95 ± 2	87 ± 2	10*6.5
DR049DP574	117	120	157	95 ± 2	97 ± 2	10*6.5
DR065DP432	117	140	157	95 ± 2	116.5 ± 2	10*6.5
DR075DP391	136	135	178	111 ± 2	112 ± 2	10*6.5
DR090DP325	136	135	179	111 ± 2	112 ± 2	10*6.5
DR003D1870	79	78	112	64 ± 2	56 ± 2	9.5*5.5
DR004D1403	79	92	112	64 ± 2	69.5 ± 2	9.5*5.5
DR006D0935	79	92	112	64 ± 2	69.5 ± 2	9.5*5.5
DR009D0623	79	112	112	64 ± 2	89.5 ± 2	9.5*5.5
DR010D0534	99	93	128	79 ± 2	70 ± 2	9.5*5.5
DR012D0467	99	105	128	79 ± 2	82.5 ± 2	9.5*5.5
DR018D0311	117	110	144	95 ± 2	87 ± 2	10*6.5
DR024D0233	117	120	144	95 ± 2	97 ± 2	10*6.5
DR032D0175	117	140	157	95 ± 2	116.5 ± 2	10*6.5
DR038D0147	136	135	172	111 ± 2	112 ± 2	10*6.5
DR045D0124	136	135	173	111 ± 2	112 ± 2	10*6.5
DR060DP935	136	150	173	111 ± 2	127 ± 2	10*6.5

Table 7-46

The table below shows the THDi specification when using Delta's drives to work with AC/DC reactors:

Current Harmonic	Models without Built-in DC Reactor				Models with Built-in DC Reactor		
	No AC/DC Reactor	3% Input AC Reactor	5% Input AC Reactor	4% DC Reactor	No Input AC Reactor	3% Input AC Reactor	5% Input AC Reactor
5th	73.3%	38.5%	30.8%	25.5%	31.16%	27.01%	25.5%
7th	52.74%	15.3%	9.4%	18.6%	23.18%	9.54%	8.75%
11th	7.28%	7.1%	6.13%	7.14%	8.6%	4.5%	4.2%
13th	0.4%	3.75%	3.15%	0.48%	7.9%	0.22%	0.17%
THDi	91%	43.6%	34.33%	38.2%	42.28%	30.5%	28.4%
Note	The THDi specification listed here may be slightly different from the actual THDi, depending on the installation and environmental conditions (wires, motors).						

Table 7-47

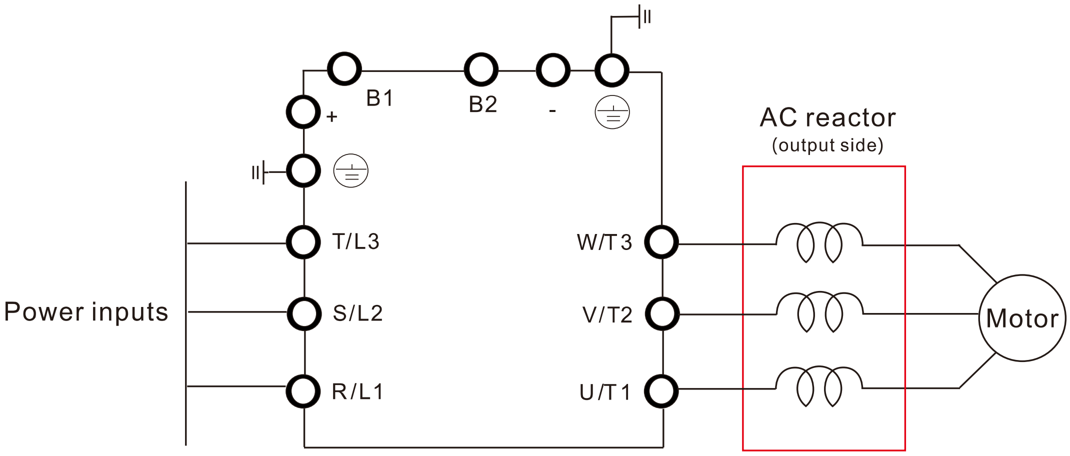
AC Output Reactor

When using drives in long wiring output application, ground fault (GFF), over-current (oc) and motor over-voltage (ov) often occur. GFF and OC cause errors due to the drive's self-protective mechanism; over-voltage damages motor insulation.

The excessive length of the output wires makes the grounded stray capacitance too large, increase the three-phase output common mode current, and the reflected wave of the long wires makes the motor dv / dt and the motor terminal voltage too high. Thus, installing a reactor on the drive's output side can increase the high-frequency impedance to reduce the dv / dt and terminal voltage to protect the motor.

Installation

Install an AC output reactor in series between the three output phases U V W and the motor, as shown in the figure below:



Wiring of AC output reactor Figure 7-26

Specifications of AC output reactors (standard item)

Following tables show the standard AC output reactors specification of Delta CP2000:

200V–230V, 50 / 60 Hz, Light Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Output AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP23A-21	0.75	1	5	6	2.536	4.227	No	DR005L0254	15
VFD015CP23A-21	1.5	2	7.5	9	1.585	2.642	No	DR008L0159	30
VFD022CP23A-21	2.2	3	10	12	1.152	1.92	No	DR011L0115	33
VFD037CP23A-21	3.7	5	15	18	0.746	1.243	No	DR017LP746	34
VFD055CP23A-21	5.5	7.5	21	25.2	0.507	0.845	No	DR025LP507	50
VFD075CP23A-21	7.5	10	31	37.2	0.38	0.633	No	DR033LP320	50
VFD110CP23A-21	11	15	46	55.2	0.26	0.433	No	DR049LP215	62
VFD150CP23A-21	15	20	61	73.2	0.196	0.327	No	DR065LP162	70
VFD185CP23A-21	18.5	25	75	90	0.169	0.282	No	DR075LP170	80
VFD220CP23A-21	22	30	90	108	0.141	0.235	No	DR090LP141	80
VFD300CP23A-21	30	40	105	126	0.12	0.2	No	DR105LP106	95
VFD370CP23A-00 VFD370CP23A-21	37	50	146	175.2	0.087	0.145	Yes	DR146LP087	110
VFD450CP23A-00 VFD450CP23A-21	45	60	180	216	0.07	0.117	Yes	DR180LP070	125
VFD550CP23A-00 VFD550CP23A-21	55	75	215	258	0.059	0.098	Yes	DR215LP059	150
VFD750CP23A-00 VFD750CP23A-21	75	100	276	331.2	0.049	0.082	Yes	DR276LP049	210
VFD900CP23A-00 VFD900CP23A-21	90	125	322	386.4	0.037	0.062	Yes	DR346LP037	220

Table 7-48

200V–230V, 50 / 60 Hz, Normal Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Output AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP23A-21	0.75	1	4.6	7.36	2.536	4.227	No	DR005L0254	15
VFD015CP23A-21	1.5	2	5	8	2.536	4.227	No	DR005L0254	15
VFD022CP23A-21	2.2	3	8	12.8	1.585	2.642	No	DR008L0159	30
VFD037CP23A-21	3.7	5	11	17.6	1.152	1.92	No	DR011L0115	33
VFD055CP23A-21	5.5	7.5	17	27.2	0.746	1.243	No	DR017LP746	34
VFD075CP23A-21	7.5	10	25	40	0.507	0.845	No	DR025LP507	50
VFD110CP23A-21	11	15	33	52.8	0.38	0.633	No	DR033LP320	50
VFD150CP23A-21	15	20	49	78.4	0.26	0.433	No	DR049LP215	62
VFD185CP23A-21	18.5	25	65	104	0.196	0.327	No	DR065LP162	70
VFD220CP23A-21	22	30	75	120	0.169	0.282	No	DR075LP170	80
VFD300CP23A-21	30	40	90	144	0.141	0.235	No	DR090LP141	80
VFD370CP23A-00 VFD370CP23A-21	37	50	120	192	0.12	0.2	Yes	DR105LP106	95
VFD450CP23A-00 VFD450CP23A-21	45	60	146	233.6	0.087	0.145	Yes	DR146LP087	110
VFD550CP23A-00 VFD550CP23A-21	55	75	180	288	0.07	0.117	Yes	DR180LP070	125
VFD750CP23A-00 VFD750CP23A-21	75	100	215	344	0.059	0.098	Yes	DR215LP059	150
VFD900CP23A-00 VFD900CP23A-21	90	125	255	408	0.049	0.082	Yes	DR276LP049	210

Table 7-49

380V–460V, 50 / 60 Hz, Light Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Output AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP43A-21 VFD007CP4EA-21	0.75	1	3	3.6	8.102	13.503	No	DR003L0810	13
VFD015CP43B-21 VFD015CP4EB-21	1.5	2	4.2	5.04	6.077	10.128	No	DR004L0607	18
VFD022CP43B-21 VFD022CP4EB-21	2.2	3	5.5	6.6	4.050	6.75	No	DR006L0405	22
VFD037CP43B-21 VFD037CP4EB-21	3.7	5	8.5	10.2	2.700	4.5	No	DR009L0270	35
VFD040CP43A-21 VFD040CP4EA-21	4	5	10.5	12.6	2.315	3.858	No	DR010L0231	40
VFD055CP43B-21 VFD055CP4EB-21	5.5	7.5	13	15.6	2.025	3.375	No	DR012L0202	45
VFD075CP43B-21 VFD075CP4EB-21	7.5	10	18	21.6	1.35	2.25	No	DR018L0117	48
VFD110CP43B-21 VFD110CP4EB-21	11	15	24	28.8	1.01	1.683	No	DR024LP881	52
VFD150CP43B-21 VFD150CP4EB-21	15	20	32	38.4	0.76	1.267	No	DR032LP660	66
VFD185CP43B-21 VFD185CP4EB-21	18.5	25	38	45.6	0.639	1.065	No	DR038LP639	70
VFD220CP43A-21 VFD220CP4EA-21	22	30	45	54	0.541	0.902	No	DR045LP541	85
VFD300CP43B-21 VFD300CP4EB-21	30	40	60	72	0.405	0.675	No	DR060LP405	85
VFD370CP43B-21 VFD370CP4EB-21	37	50	73	87.6	0.334	0.557	No	DR073LP334	110
VFD450CP43S-00 VFD450CP43S-21	45	60	91	109.2	0.267	0.445	Yes	DR091LP267	130
VFD550CP43S-00 VFD550CP43S-21	55	75	110	132	0.221	0.368	Yes	DR110LP221	150
VFD750CP43B-00 VFD750CP43B-21	75	100	150	180	0.162	0.27	Yes	DR150LP162	175
VFD900CP43A-00 VFD900CP43A-21	90	125	180	216	0.135	0.225	Yes	DR180LP135	195
VFD1100CP43A-00 VFD1100CP43A-21	110	150	220	264	0.110	0.183	Yes	DR220LP110	235
VFD1320CP43B-00 VFD1320CP43B-21	132	175	260	312	0.098	0.163	Yes	DR260LP098	285
VFD1600CP43A-00 VFD1600CP43A-21	160	215	310	372	0.078	0.13	Yes	DR310LP078	300
VFD1850CP43B-00 VFD1850CP43B-21	185	250	370	444	0.066	0.11	Yes	DR370LP066	345
VFD2000CP43A-00 VFD2000CP43A-21	200	270	395	474	0.061	0.1	Yes	DR370LP066[*1]	410
VFD2200CP43A-00 VFD2200CP43A-21	220	300	460	552	0.054	0.09	Yes	DR460LP054	410
VFD2500CP43A-00 VFD2500CP43A-21	250	340	481	578	0.052	0.086	Yes	DR460LP054[*1]	440

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Output AC Reactor Delta Part #	Heat Dissipation (W)
VFD2800CP43A-00 VFD2800CP43A-21	280	375	530	636	0.044	0.073	Yes	DR550LP044	440
VFD3150CP43A-00 VFD3150CP43C-00 VFD3150CP43C-21	315	420	616	739.2	0.039	0.065	Yes	DR616LP039	465
VFD3550CP43A-00 VFD3550CP43C-00 VFD3550CP43C-21	355	475	683	819.6	0.036	0.06	Yes	DR683LP036	495
VFD4000CP43A-00 VFD4000CP43C-00 VFD4000CP43C-21	400	530	770	924	0.028	0.047	Yes	DR866LP028	600
VFD5000CP43A-00 VFD5000CP43C-00 VFD5000CP43C-21	500	675	912	1094.4	0.028	0.047	Yes	DR866LP028	600
VFD5600CP43A-00 VFD5600CP43C-21	560	650	1094	1318.2	0.022	0.037	Yes	Contact Delta	
VFD6300CP43A-00 VFD6300CP43C-21	630	760	1212	1454.4	0.020	0.033	Yes		

*Note 1: The inductance value for the above applications of Delta's reactors will be closer, but less than 3%.

Note 2: The above heat dissipation is calculated based on AC reactor's rated current; the actual dissipation varies with the operation current.

Table 7-50

380V–460V, 50 / 60 Hz, Normal Duty

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Output AC Reactor Delta Part #	Heat Dissipation (W)
VFD007CP43A-21 VFD007CP4EA-21	0.75	1	2.8	4.48	9.058	15.097	No	DR003L0810^{*1}	13
VFD015CP43B-21 VFD015CP4EB-21	1.5	2	3	4.8	8.102	13.503	No	DR003L0810	13
VFD022CP43B-21 VFD022CP4EB-21	2.2	3	4	6.4	6.077	10.128	No	DR004L0607	18
VFD037CP43B-21 VFD037CP4EB-21	3.7	5	6	9.6	4.050	6.75	No	DR006L0405	22
VFD040CP43A-21 VFD040CP4EA-21	4	5	9	14.4	2.700	4.5	No	DR009L0270	35
VFD055CP43B-21 VFD055CP4EB-21	5.5	7.5	10.5	16.8	2.315	3.858	No	DR010L0231	40
VFD075CP43B-21 VFD075CP4EB-21	7.5	10	12	19.2	2.025	3.375	No	DR012L0202	45
VFD110CP43B-21 VFD110CP4EB-21	11	15	18	28.8	1.35	2.25	No	DR018L0117	48
VFD150CP43B-21 VFD150CP4EB-21	15	20	24	38.4	1.01	1.683	No	DR024LP881	52
VFD185CP43B-21 VFD185CP4EB-21	18.5	25	32	51.2	0.76	1.267	No	DR032LP660	66
VFD220CP43A-21 VFD220CP4EA-21	22	30	38	60.8	0.639	1.065	No	DR038LP639	70
VFD300CP43B-21 VFD300CP4EB-21	30	40	45	72	0.541	0.902	No	DR045LP541	85

Model	kW	HP	Rated Current (Arms)	Saturation Current (Arms)	3% Reactor (mH)	5% Reactor (mH)	Built-in DC Reactor	Output AC Reactor Delta Part #	Heat Dissipation (W)
VFD370CP43B-21 VFD370CP4EB-21	37	50	60	96	0.405	0.675	No	DR060LP405	85
VFD450CP43S-00 VFD450CP43S-21	45	60	73	116.8	0.334	0.557	Yes	DR073LP334	110
VFD550CP43S-00 VFD550CP43S-21	55	75	91	145.6	0.267	0.445	Yes	DR091LP267	130
VFD750CP43B-00 VFD750CP43B-21	75	100	110	176	0.221	0.368	Yes	DR110LP221	150
VFD900CP43A-00 VFD900CP43A-21	90	125	150	240	0.162	0.27	Yes	DR150LP162	175
VFD1100CP43A-00 VFD1100CP43A-21	110	150	180	288	0.135	0.225	Yes	DR180LP135	195
VFD1320CP43B-00 VFD1320CP43B-21	132	175	220	352	0.110	0.183	Yes	DR220LP110	235
VFD1600CP43A-00 VFD1600CP43A-21	160	215	260	416	0.098	0.163	Yes	DR260LP098	285
VFD1850CP43B-00 VFD1850CP43B-21	185	250	310	496	0.078	0.13	Yes	DR310LP078	300
VFD2000CP43A-00 VFD2000CP43A-21	200	270	335	536	0.072	0.12	Yes	DR370LP066[*1]	345
VFD2200CP43A-00 VFD2200CP43A-21	220	300	370	592	0.066	0.11	Yes	DR370LP066	345
VFD2500CP43A-00 VFD2500CP43A-21	250	340	415	664	0.058	0.10	Yes	DR460LP054[*1]	410
VFD2800CP43A-00 VFD2800CP43A-21	280	375	460	736	0.054	0.09	Yes	DR460LP054	410
VFD3150CP43A-00 VFD3150CP43C-00 VFD3150CP43C-21	315	420	550	880	0.044	0.073	Yes	DR550LP044	440
VFD3550CP43A-00 VFD3550CP43C-00 VFD3550CP43C-21	355	475	616	985.6	0.039	0.065	Yes	DR616LP039	465
VFD4000CP43A-00 VFD4000CP43C-00 VFD4000CP43C-21	400	530	683	1092.8	0.036	0.06	Yes	DR683LP036	495
VFD5000CP43A-00 VFD5000CP43C-00 VFD5000CP43C-21	500	675	866	1385.6	0.028	0.047	Yes	DR866LP028	600
VFD5600CP43A-00 VFD5600CP43C-21	560	650	930	1488	0.026	0.043	Yes	Contact Delta	
VFD6300CP43A-00 VFD6300CP43C-21	630	760	1094	1750.4	0.022	0.037	Yes		

*Note 1: The inductance value for the above applications of Delta's reactors will be closer, but less than 3%.

Note 2: The above heat dissipation is calculated based on AC reactor's rated current; the actual dissipation varies with the operation current.

Table 7-51

575V, 50 / 60 Hz, Three-phase

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)	3% Reactor (mH)		5% Reactor (mH)	
			Normal Duty	Light Duty		Normal Duty	Light Duty	Normal Duty	Light Duty
VFD015CP53A-21	1.5	2	2.5	3	4.2	10.567	8.806	17.612	14.677
VFD022CP53A-21	2.2	3	3.6	4.3	5.9	7.338	6.144	12.230	10.239
VFD037CP53A-21	3.7	5	5.5	6.7	9.1	4.803	3.943	8.005	6.572
VFD055CP53A-21	5.5	7.5	8.2	9.9	13.7	3.222	2.668	5.369	4.447
VFD075CP53A-21	7.5	10	10	12.1	16.5	2.642	2.183	4.403	3.639
VFD110CP53A-21	11	15	15.5	18.7	25.7	1.704	1.413	2.841	2.355
VFD150CP53A-21	15	20	20	24.2	33.3	1.321	1.092	2.201	1.819

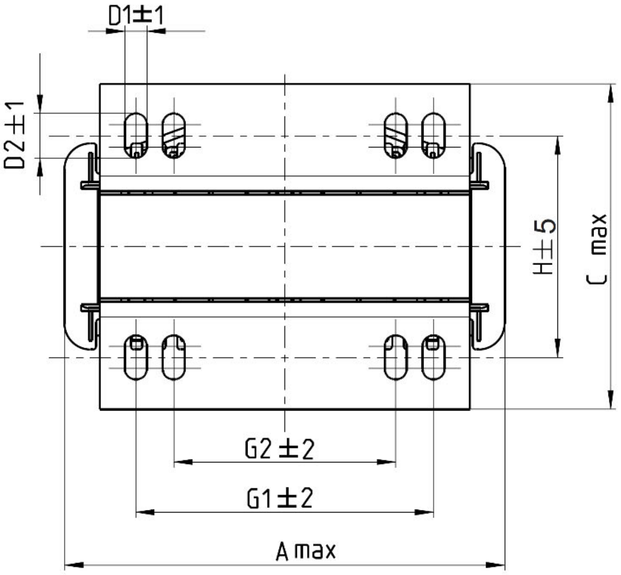
Table 7-52

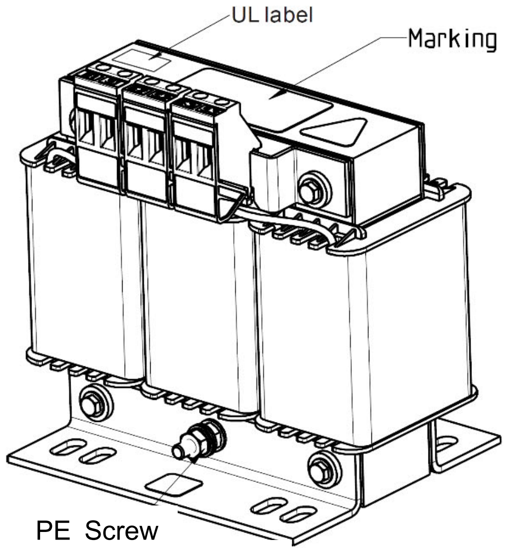
690V, 50 / 60 Hz, Three-phase

Model	kW	HP	Rated Current (Arms)		Saturation Current (Arms)		3% Reactor (mH)		5% Reactor (mH)	
			Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty	Normal Duty	Light Duty
VFD185CP63A-21	18.5	25	20	24	30.0	28.8	1.902	1.585	3.170	2.642
VFD220CP63A-21	22	30	24	30	36.0	36.0	1.585	1.268	2.642	2.113
VFD300CP63A-21	30	40	30	36	45.0	43.2	1.268	1.057	2.113	1.761
VFD370CP63A-21	37	50	36	45	54.0	54.0	1.057	0.845	1.761	1.409
VFD450CP63A-00/-21	45	60	45	54	67.5	64.8	0.845	0.704	1.409	1.174
VFD550CP63A-00/-21	55	75	54	67	81.0	80.4	0.704	0.568	1.174	0.946
VFD750CP63A-00/-21	75	100	67	86	100.5	103.2	0.568	0.442	0.946	0.737
VFD900CP63A-00/-21	90	125	86	104	129.0	124.8	0.442	0.366	0.737	0.610
VFD1100CP63A-00/-21	110	150	104	125	156.0	150.0	0.366	0.304	0.610	0.507
VFD1320CP63A-00/-21	132	175	125	150	187.5	180.0	0.304	0.254	0.507	0.423
VFD1600CP63A-00/-21	160	215	150	180	225.0	216.0	0.254	0.211	0.423	0.352
VFD2000CP63A-00/-21	200	270	180	220	270.0	264.0	0.211	0.173	0.352	0.288
VFD2500CP63A-00/-21	250	335	220	290	330.0	348.0	0.173	0.131	0.288	0.219
VFD3150CP63A-00/-21	315	425	290	350	435.0	420.0	0.131	0.109	0.219	0.181
VFD4000CP63A-00/-21	400	530	350	430	525.0	516.0	0.109	0.088	0.181	0.147
VFD4500CP63A-00/-21	450	600	385	465	577.5	558.0	0.099	0.082	0.165	0.136
VFD5600CP63A-00/-21	560	745	465	590	697.5	708.0	0.082	0.064	0.136	0.107
VFD6300CP63A-00/-21	630	850	675	675	1012.5	810.0	0.056	0.056	0.094	0.094

Table 7-53

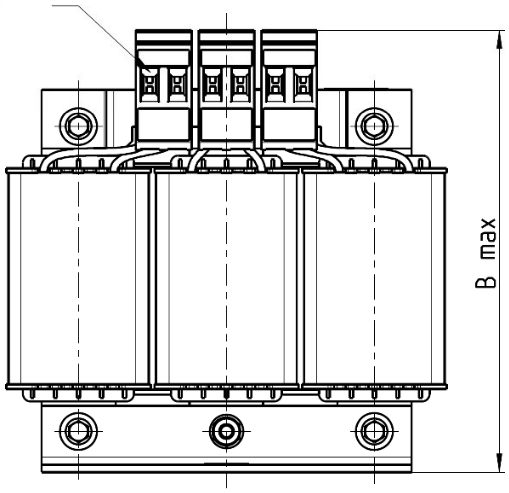
AC output reactor dimensions and specification:

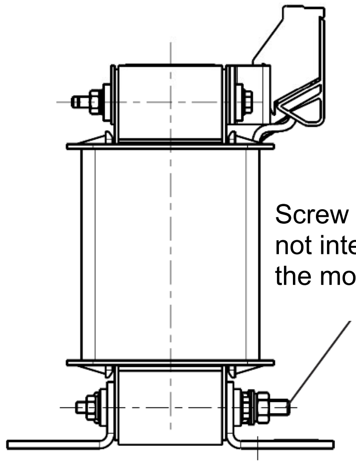




Torque: 6.1–8.2 kg-cm / [5.3–7.1 lb-in] / [0.6–0.8 Nm]

Torque: 10.2–12.3 kg-cm / [8.9–10.6 lb-in] / [1.0–1.2 Nm]





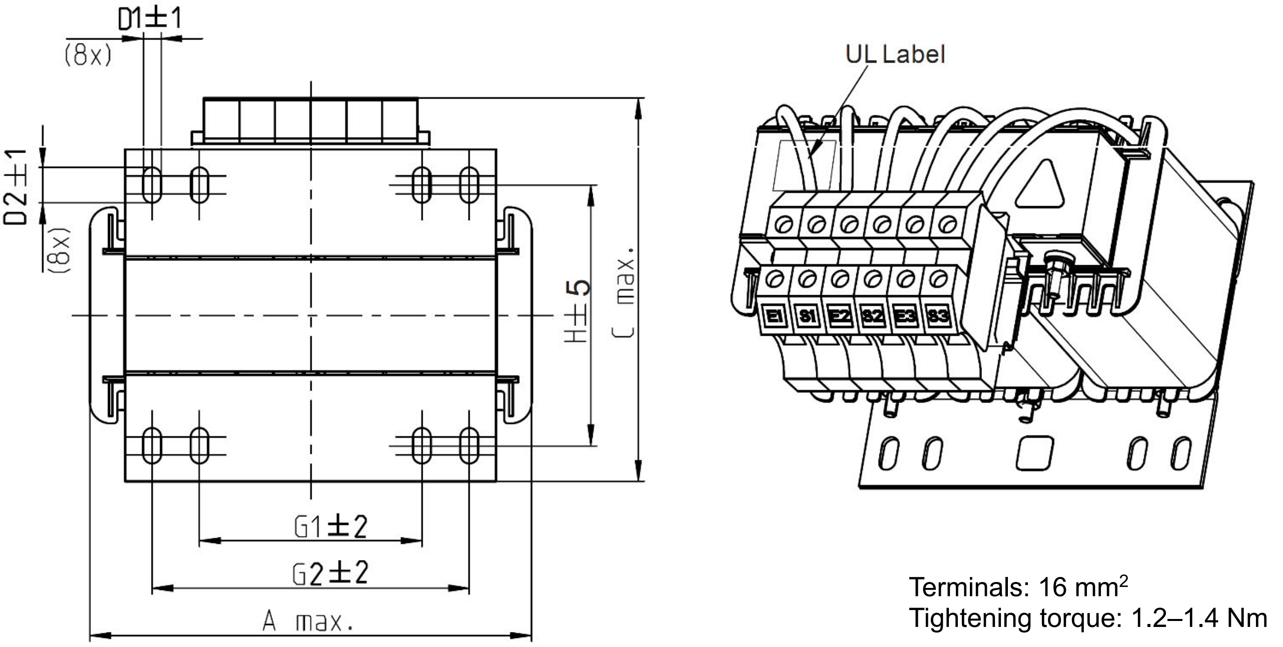
Screw length must not interfere with the mounting holes

Figure 7-27

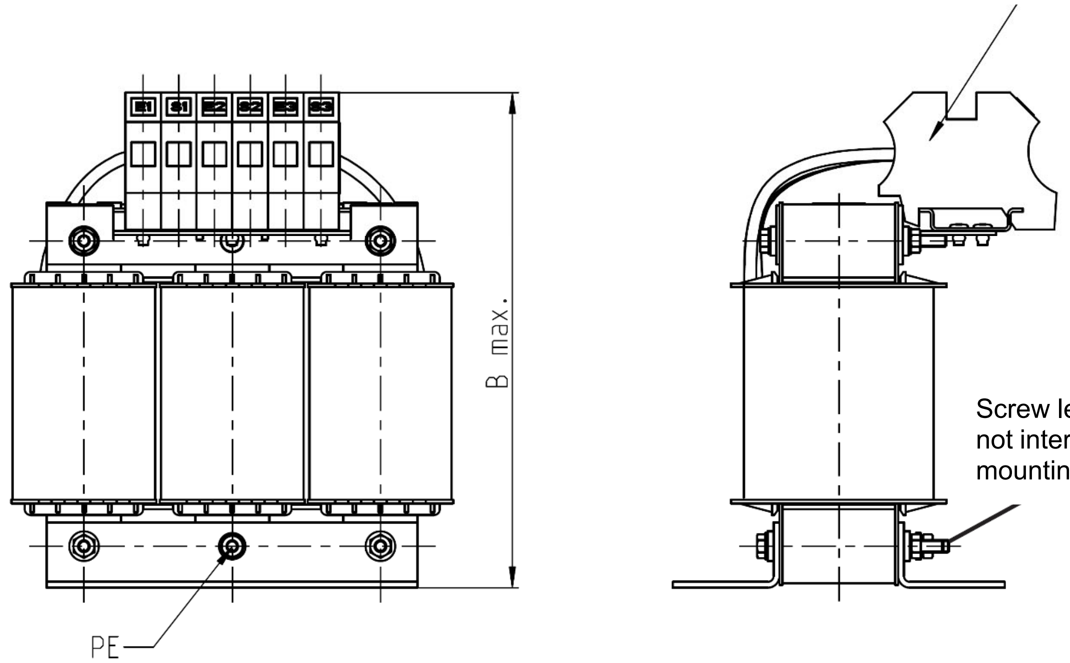
Unit: mm

Output AC Reactor Delta Part #	A	B	C	D1*D2	E	G1	G2	PE D
DR005L0254	96	110	70	6*9	42	60	40	M4
DR008L0159	120	135	96	6*12	60	80.5	60	M4
DR011L0115	120	135	96	6*12	60	80.5	60	M4
DR017LP746	120	135	105	6*12	65	80.5	60	M4
DR025LP507	150	160	120	6*12	88	107	75	M4
DR033LP320	150	160	120	6*12	88	107	75	M4

Table 7-54



Terminals: 16 mm^2
Tightening torque: 1.2–1.4 Nm



Screw length must not interfere with the mounting holes

Figure 7-28

Unit: mm

Output AC Reactor Delta Part #	A	B	C	D1*D2	H	G	G1	Q	M	PE D
DR049LP215	180	205	175	6*12	115	85	122	16	1.2–1.4	M4
DR065LP162	180	215	185	6*12	115	85	122	35	2.5–3.0	M4

Table 7-55

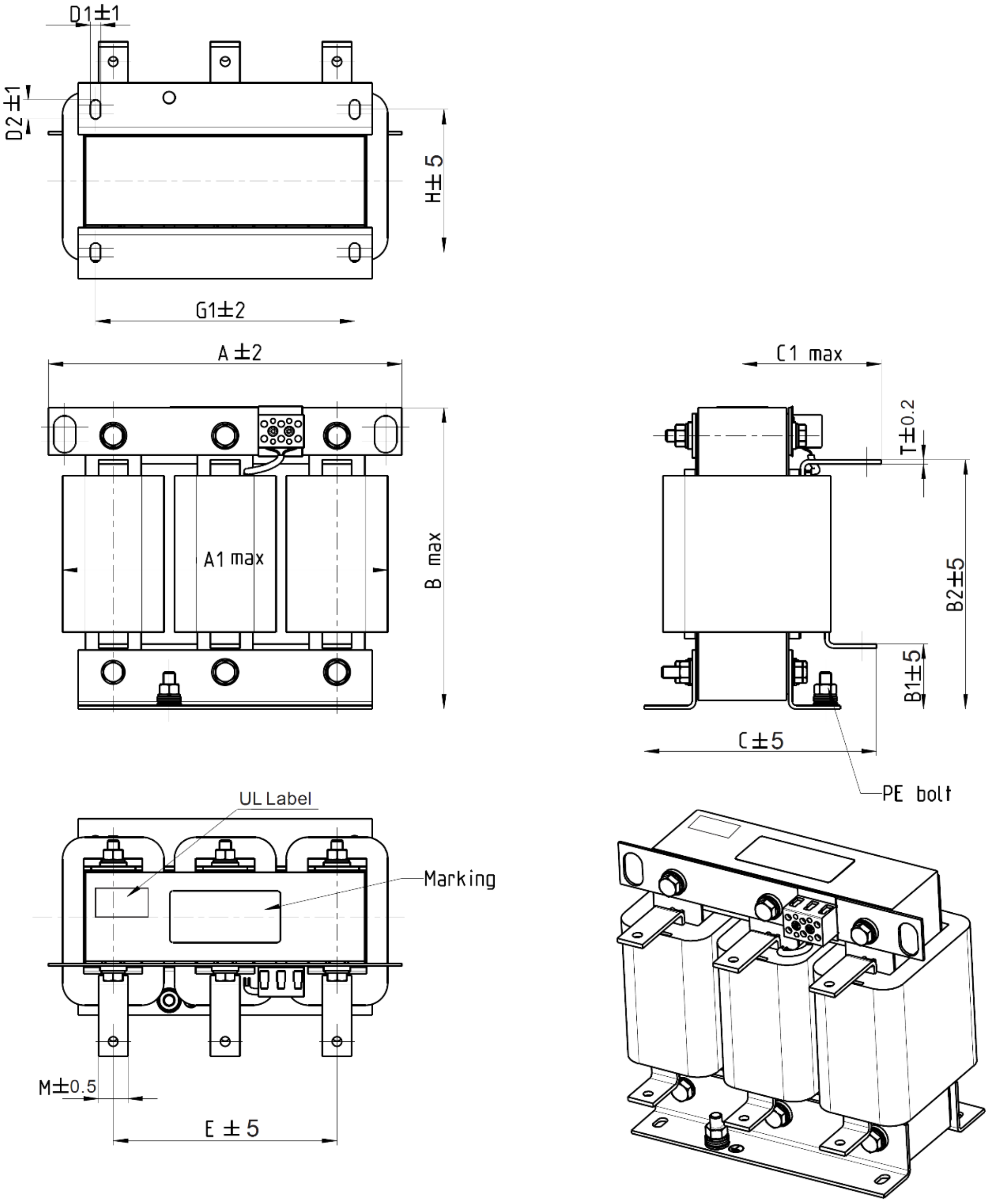


Figure 7-29
Unit: mm

Output AC Reactor Delta Part #	A	A1	B	B1	B2	C	C1	D1*D2	E	G1	H	M*T
DR075LP170	240	228	215	44	170	151	100	7*13	152	176	85	20*3
DR090LP141	240	228	215	44	170	151	100	7*13	152	176	85	20*3
DR105LP106	240	228	215	44	170	165	110	7*13	152	176	97	20*3
DR146LP087	240	228	240	45	202	165	110	7*13	152	176	97	30*3
DR180LP070	250	240	250	46	205	175	110	11*18	160	190	124	30*5
DR215LP059	250	240	275	51	226	180	120	11*18	160	190	124	30*5

Table 7-56

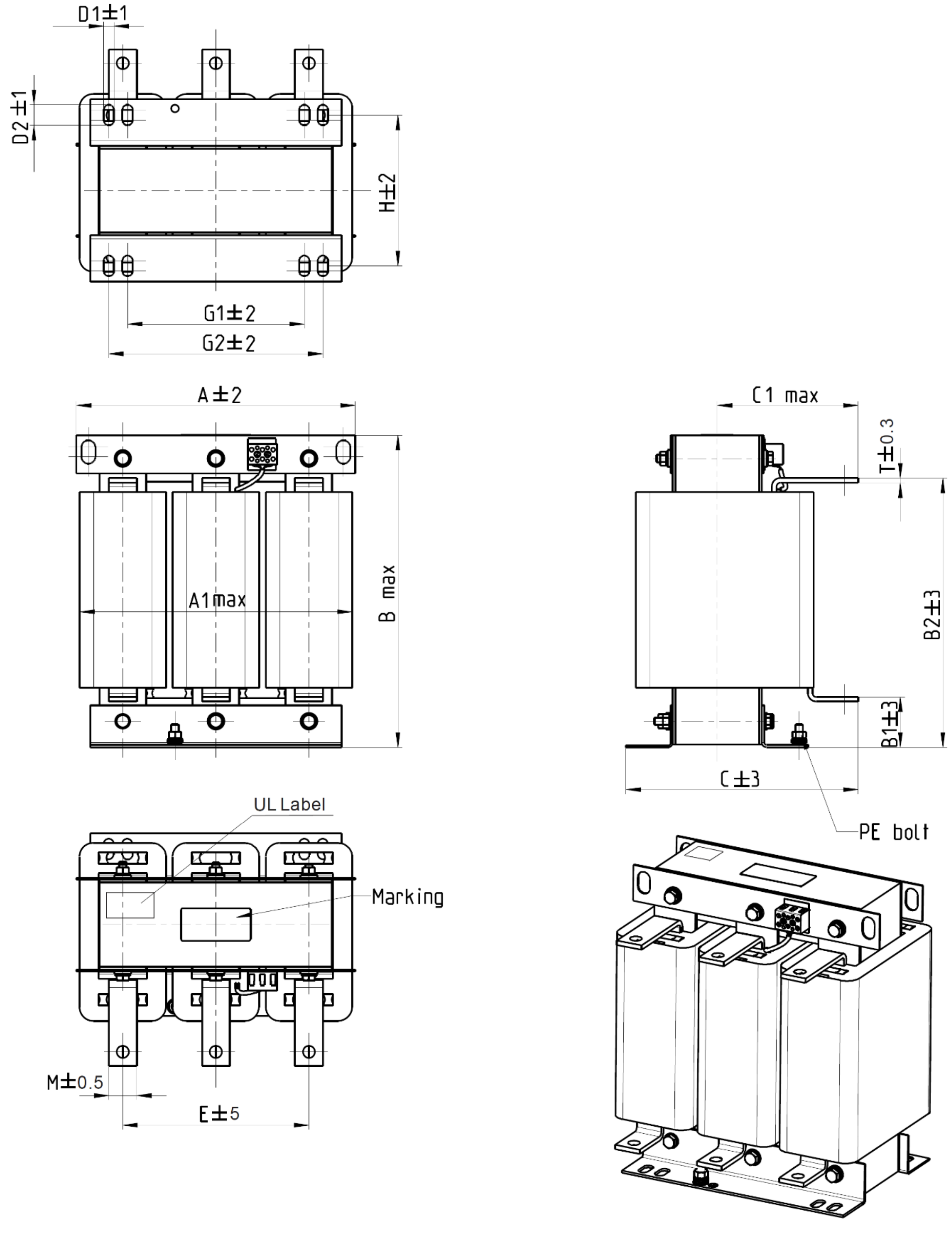
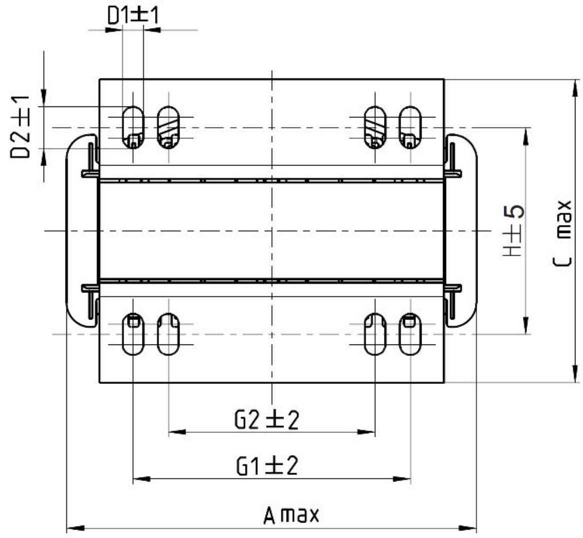


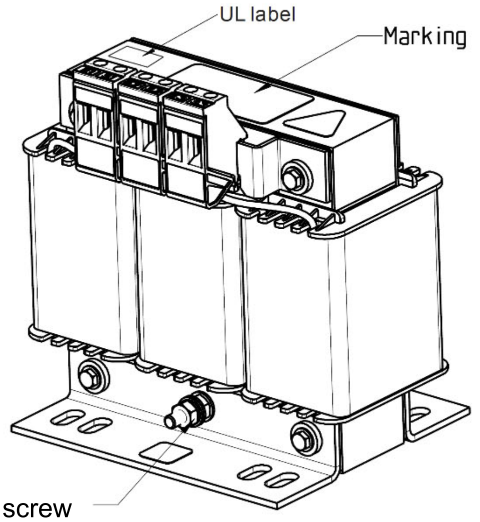
Figure 7-30

Unit: mm

Output AC Reactor Delta Part #	A	A1	B	B1	B2	C	C1	D1*D2	E	H	M*T
DR276LP049	270	260	320	50	265	200	140	10*18	176	106	30*5
DR346LP037	270	265	340	50	285	200	140	10*18	176	106	30*5

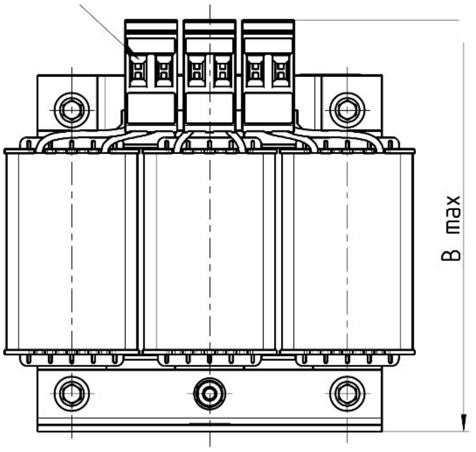
Table 7-57

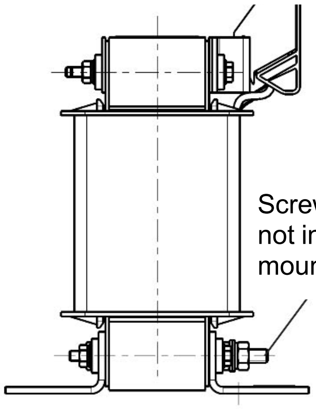




Torque: 6.1–8.2 kg-cm / [5.3–7.1 lb-in] / [0.6–0.8 Nm]

Torque: 10.2–12.3 kg-cm / [8.9–10.6 lb-in] / [1.0–1.2 Nm]





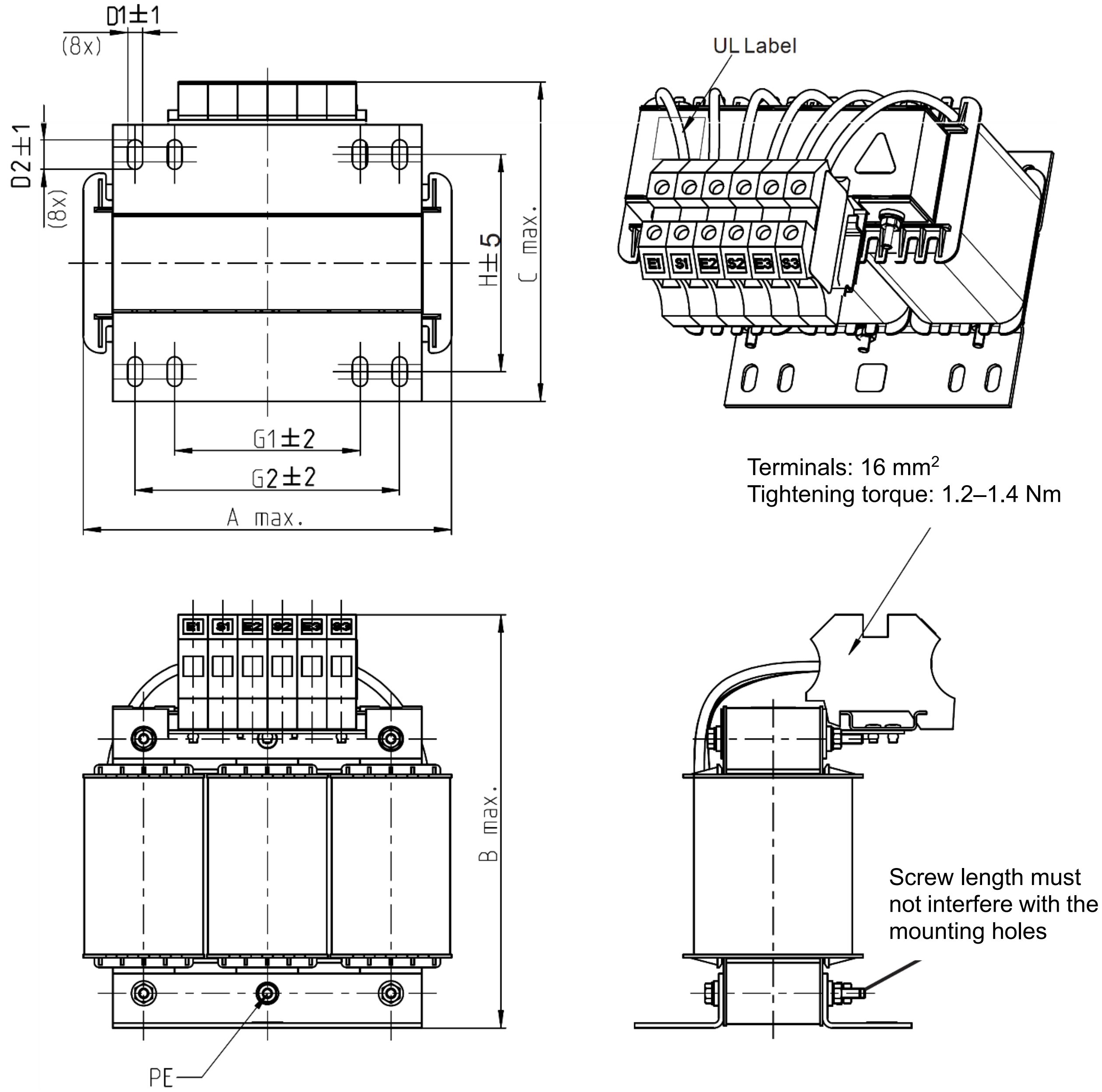
Screw length must not interfere with the mounting holes

Figure 7-31

Unit: mm

Output AC Reactor Delta Part #	A	B	C	D1*D2	H	G1	G2	PE D
DR003L0810	96	115	65	6*9	42	60	40	M4
DR004L0607	120	135	95	6*12	60	80.5	60	M4
DR006L0405	120	135	95	6*12	60	80.5	60	M4
DR009L0270	150	160	100	6*12	74	107	75	M4
DR010L0231	150	160	115	6*12	88	107	75	M4
DR012L0202	150	160	115	6*12	88	107	75	M4
DR018L0117	150	160	115	6*12	88	107	75	M4
DR024LP881	150	160	115	6*12	88	107	75	M4
DR032LP660	180	190	145	6*12	114	122	85	M6

Table 7-58



Terminals: 16 mm^2
Tightening torque: 1.2–1.4 Nm

Screw length must not interfere with the mounting holes

Figure 7-32

Unit: mm

Output AC Reactor Delta Part #	A	B	C	D1*D2	H	G1	G2	PE D
DR038LP639	180	205	170	6*12	115	85	122	M4
DR045LP541	235	245	155	7*13	85	/	176	M6

Table 7-59

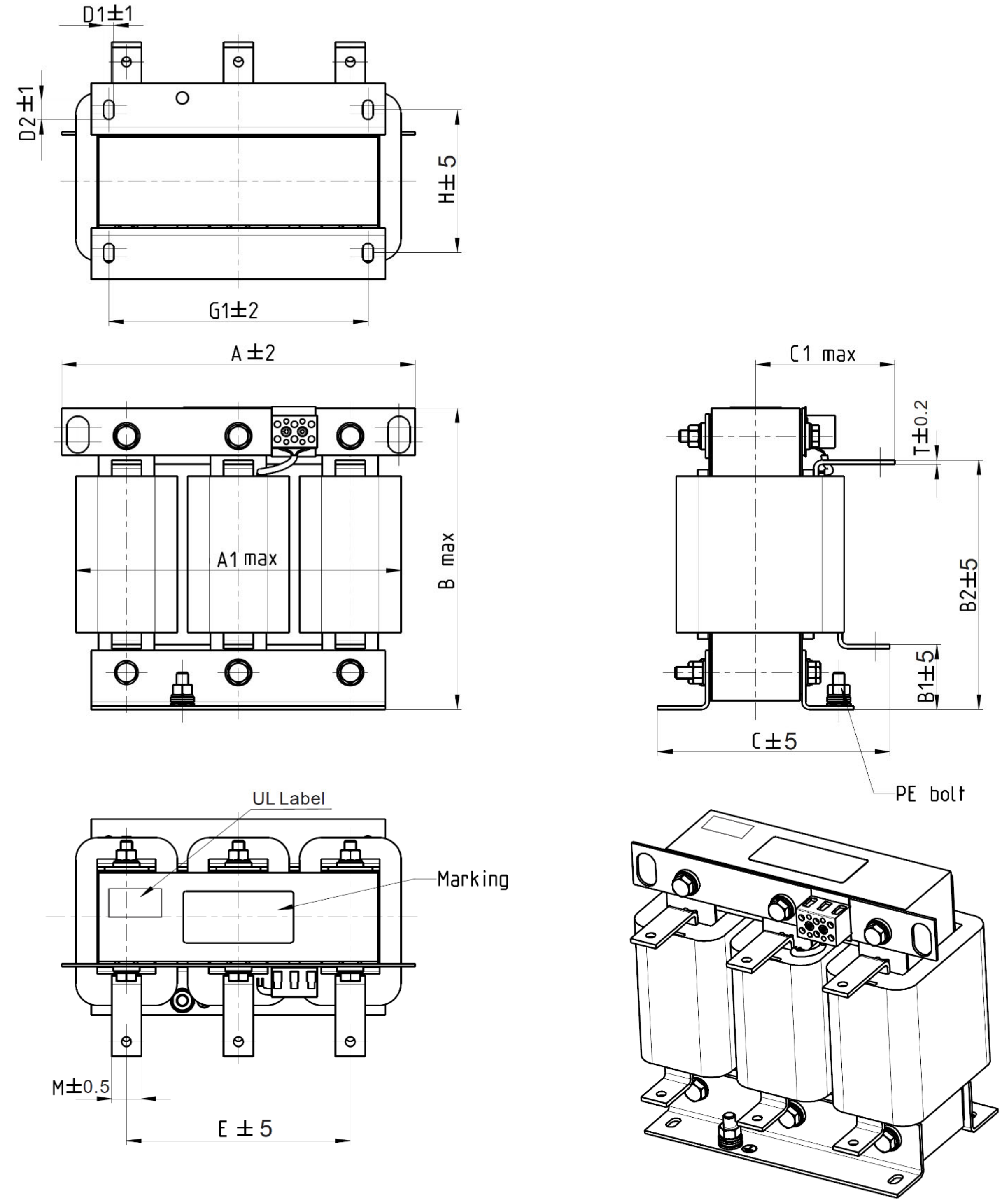


Figure 7-33

Unit: mm

Output AC Reactor Delta Part #	A	A1	B	B1	B2	C	C1	D1*D2	E	G1	H	M*T
DR060LP405	240	228	215	44	170	163	110	7*13	152	176	97	20*3
DR073LP334	250	235	235	44	186	174	115	11*18	160	190	124	20*3
DR091LP267	250	240	235	44	186	174	115	11*18	160	190	124	20*3
DR110LP221	270	260	245	50	192	175	115	10*18	176	200	106	20*3

Table 7-60

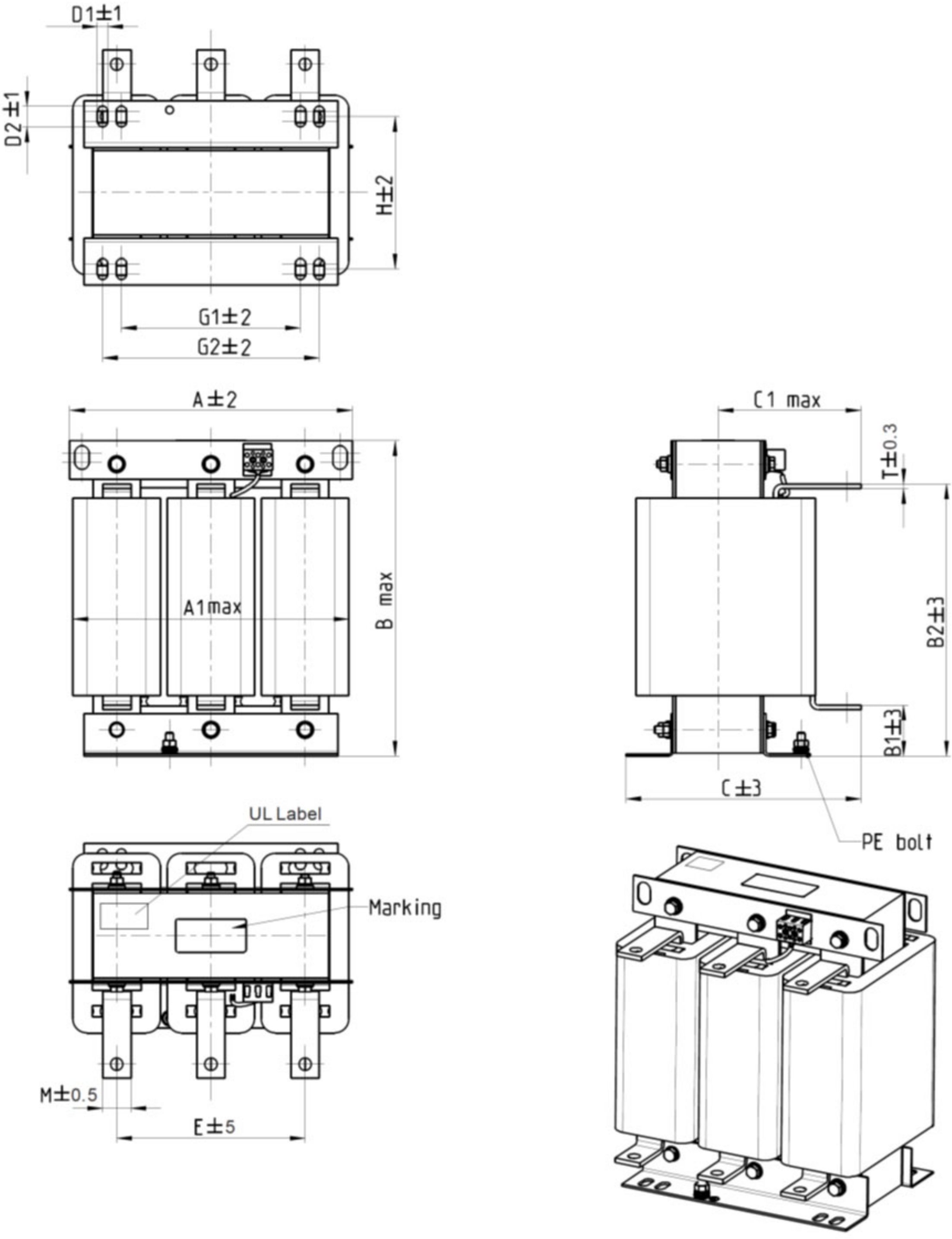


Figure 7-34

Unit: mm

Output AC Reactor Delta Part #	A	A1	B	B1	B2	C	C1	D1*D2	E	G1	G2	H	M*T
DR150LP162	270	264	265	51	208	192	125	10*18	176	200	/	118	30*3
DR180LP135	300	295	310	55	246	195	125	11*22	200	230	190	142	30*3
DR220LP110	300	298	310	57	248	210	140	11*22	200	230	190	142	30*5
DR260LP098	300	295	330	56	270	227	140	11*22	200	230	190	160	30*5
DR310LP078	300	298	350	54	288	233	145	11*22	200	230	190	160	30*5
DR370LP066	300	298	350	54	289	268	170	11*22	200	230	190	185	40*5

Table 7-61

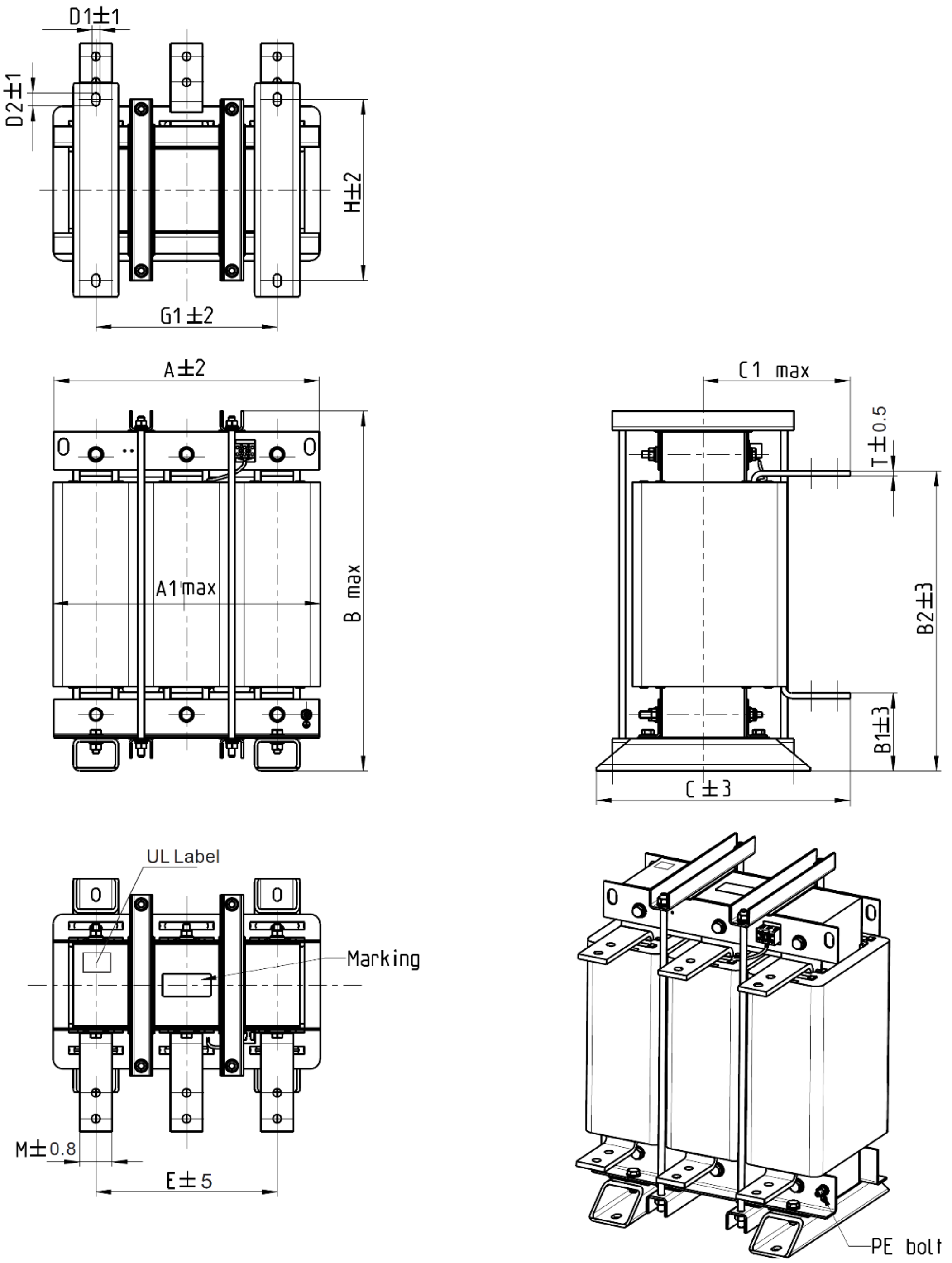


Figure 7-35

Unit: mm

Output AC Reactor Delta Part #	A	A1	B	B1	B2	C	C1	D1*D2	E	G1	H	M*T
DR460LP054	360	355	510	106	401	346	215	12*20	240	240	240	50*5
DR550LP044	360	355	510	106	401	358	220	12*20	240	240	250	50*5
DR616LP039	360	355	510	110	401	376	230	12*20	240	240	270	50*8
DR683LP036	360	355	510	110	401	396	240	12*20	240	240	290	50*8
DR866LP028	410	418	570	120	464	402	245	12*20	280	280	290	50*8

Table 7-62

Motor Cable Length

1. Consequence of leakage current on the motor

   If the cable length is too long, the stray capacitance between cables increases an may cause leakage current. In this case, it activates the over-current protection, increases leakage current, or may affect the current display. The worst case is that it may damage the AC motor drive. If more than one motor is connected to one AC motor drive, the total wiring length should be the sum of the wiring length from AC motor drive to each motor.

   For the 460V models AC motor drives, when you install an overload thermal relay between the drive and the motor to protect the motor from overheating, the connecting cable must be shorter than 50m, however, an overload thermal relay malfunction may still occur. To prevent the malfunction, install an output reactor (optional) to the drive or lower the carrier frequency setting (see Pr.00-17 Carrier Frequency).

2. Consequence of the surge voltage on the motor

   When a motor is driven by a PWM-type AC motor drive, the motor terminals experience surge voltages (dv/dt) due to power transistor conversion of AC motor drive. When the motor cable is very long (especially for the 460V models), surge voltages (dv/dt) may damage the motor insulation and bearing. To prevent this, follow these rules:

   a. Use a motor with enhanced insulation.
   b. Reduce the cable length between the AC motor drive and motor to suggested values.
   c. Connect an output reactor (optional) to the output terminals of the AC motor drive.

Refer to the following tables for the suggested motor shielded cable length. For drive models < 490V, use a motor with a rated voltage ≤ 500 V_{AC} and an insulation level ≥ 1.35 kV in accordance with IEC 60034-17.

230V Model	kW	HP	Rated Current (Arms)		Without an AC Output Reactor		With an AC Output Reactor	
			Normal Duty (ND)	Light Duty (LD)	Shielded Cable [meter]	Non-shielded Cable [meter]	Shielded Cable [meter]	Non-shielded Cable [meter]
VFD007CP23A-21	0.75	1	4.6	5	50	75	75	115
VFD015CP23A-21	1.5	2	5	7.5	50	75	75	115
VFD022CP23A-21	2.2	3	8	10	50	75	75	115
VFD037CP23A-21	3.7	5	11	15	50	75	75	115
VFD055CP23A-21	5.5	7.5	17	21	100	150	150	225
VFD075CP23A-21	7.5	10	25	31	100	150	150	225
VFD110CP23A-21	11	15	33	46	100	150	150	225
VFD150CP23A-21	15	20	49	61	100	150	150	225
VFD185CP23A-21	18.5	25	65	75	100	150	150	225
VFD220CP23A-21	22	30	75	90	100	150	150	225
VFD300CP23A-21	30	40	90	120	100	150	150	225
VFD370CP23A-00/-21	37	50	120	146	100	150	150	225
VFD450CP23A-00/-21	45	60	146	180	150	225	225	325
VFD550CP23A-00/-21	55	75	180	215	150	225	225	325
VFD750CP23A-00/-21	75	100	215	276	150	225	225	325
VFD900CP23A-00/-21	90	125	255	322	150	225	225	325

Table 7-63

460V Model	kW	HP	Rated Current (Arms)		Without an AC Output Reactor		With an AC Output Reactor	
			Normal Duty (ND)	Light Duty (LD)	Shielded Cable [meter]	Non-shielded Cable [meter]	Shielded Cable [meter]	Non-shielded Cable [meter]
VFD007CP43A-21/4EA-21	0.75	1	1.7	3	50	75	75	115
VFD015CP43B-21/4EB-21	1.5	2	3	4.2	50	75	75	115
VFD022CP43B-21/4EB-21	2.2	3	4	5.5	50	75	75	115
VFD037CP43B-21/4EB-21	3.7	5	6	8.5	50	75	75	115
VFD040CP43A-21/4EA-21	4	5	9	10.5	50	75	75	115
VFD055CP43B-21/4EB-21	5.5	7.5	10.5	13	50	75	75	115
VFD075CP43B-21/4EB-21	7.5	10	12	18	100	150	150	225
VFD110CP43B-21/4EB-21	11	15	18	24	100	150	150	225
VFD150CP43B-21/4EB-21	15	20	24	32	100	150	150	225
VFD185CP43B-21/4EB-21	18.5	25	32	38	100	150	150	225
VFD220CP43A-21/4EA-21	22	30	38	45	100	150	150	225
VFD300CP43B-21/4EB-21	30	40	45	60	100	150	150	225
VFD370CP43B-21/4EB-21	37	50	60	73	100	150	150	225
VFD450CP43S-00/43S-21	45	60	73	91	150	225	225	325
VFD550CP43S-00/43S-21	55	75	91	110	150	225	225	325
VFD750CP43B-00/43B-21	75	100	110	150	150	225	225	325
VFD900CP43A-00/43A-21	90	125	150	180	150	225	225	325
VFD1100CP43A-00/43A-21	110	150	180	220	150	225	225	325
VFD1320CP43B-00/43B-21	132	175	220	260	150	225	225	325
VFD1600CP43A-00/43A-21	160	215	260	310	150	225	225	325
VFD1850CP43B-00/43B-21	185	250	310	370	150	225	225	325
VFD2000CP43A-00/43A-21	200	270	335	395	150	225	225	325
VFD2200CP43A-00/43A-21	220	300	370	460	150	225	225	325
VFD2500CP43A-00/43A-21	250	340	415	481	150	225	225	325
VFD2800CP43A-00/43A-21	280	375	460	530	150	225	225	325
VFD3150CP43A-00/ VFD3150CP43C-00/-21	315	420	550	616	150	225	225	325
VFD3550CP43A-00/ VFD3550CP43C-00/-21	355	475	616	683	150	225	225	325
VFD4000CP43A-00/ VFD4000CP43C-00/-21	400	536	683	770	150	225	225	325
VFD5000CP43A-00/ VFD5000CP43C-00/-21	500	675	866	912	150	225	225	325
VFD5600CP43A-00/43C-21	560	650	930	1094	150	225	225	325
VFD6300CP43A-00/43C-21	630	750	1094	1212	150	225	225	325

Table 7-64

575V Model	kW	HP	Rated current (Arms) Normal Duty	Without an AC Output Reactor		With an AC Output Reactor	
				Shielded Cable [meter]	Non-shielded cable [meter]	Shielded Cable [meter]	Non-shielded cable [meter]
VFD015CP53A-21	0.75	1	2.5	35	30	45	20
VFD022CP53A-21	1.5	2	3.6	35	30	45	20
VFD037CP53A-21	2.2	3	5.5	35	30	45	20
VFD055CP53A-21	3.7	5	8.2	35	30	45	20
VFD075CP53A-21	5.5	7.5	10	35	30	45	20
VFD110CP53A-21	7.5	10	15.5	35	30	45	20
VFD150CP53A-21	11	15	20	35	30	45	20

Table 7-65

690V Model	kW	HP	Rated current (Arms) Normal Duty	Without an AC output reactor		With an AC output reactor	
				Shielded Cable [meter]	Non-shielded cable [meter]	Shielded Cable [meter]	Non-shielded cable [meter]
VFD185CP63A-21	18.5	25	20	20	35	30	45
VFD220CP63A-21	22	30	24	20	35	30	45
VFD300CP63A-21	30	40	30	20	35	45	60
VFD370CP63A-21	37	50	36	20	45	60	75
VFD450CP63A-00/21	45	60	45	20	45	60	75
VFD550CP63A-00/21	55	75	54	20	45	60	100
VFD750CP63A-00/21	75	100	67	20	45	60	100
VFD900CP63A-00/21	90	125	86	20	45	75	100
VFD1100CP63A-00/21	110	150	104	20	45	75	100
VFD1320CP63A-00/21	132	175	125	20	45	75	100
VFD1600CP63A-00/21	160	215	150	20	45	90	100
VFD2000CP63A-00/21	200	270	180	20	45	90	100
VFD2500CP63A-00/21	250	335	220	20	45	90	100
VFD3150CP63A-00/21	315	425	290	20	45	90	100
VFD4000CP63A-00/21	400	530	350	20	45	90	100
VFD4500CP63A-00/21	450	600	385	20	45	90	100
VFD5600CP63A-00/21	560	745	465	20	45	75	90
VFD6300CP63A-00/21	630	850	675	20	45	75	90

※ 690V output motor cable length needs to comply with IEC 60034-25.

Table 7-66

Requirements on insulation level of Curve B motor

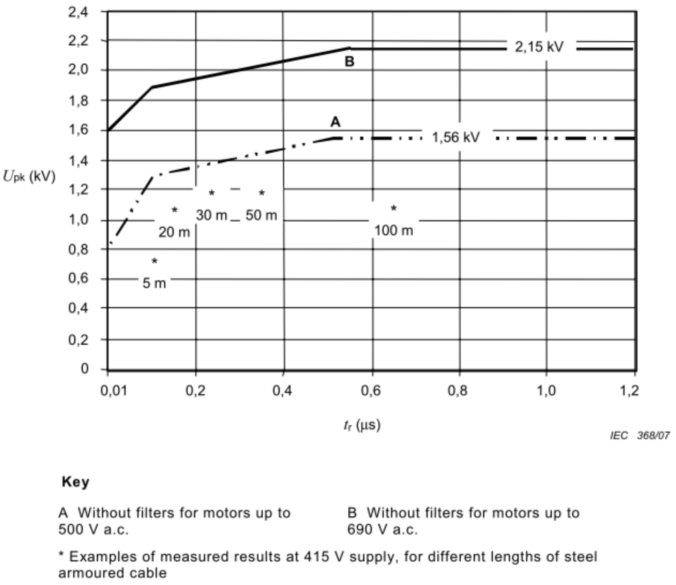


Figure 7-36

The t_r is defined as:

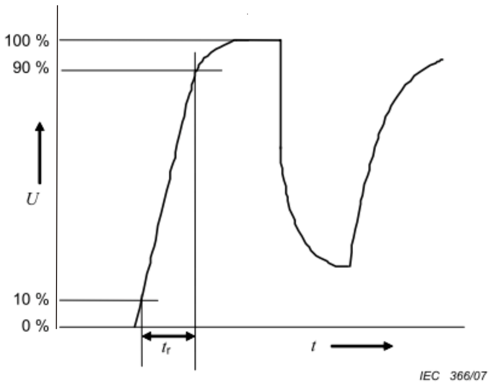


Figure 7-37

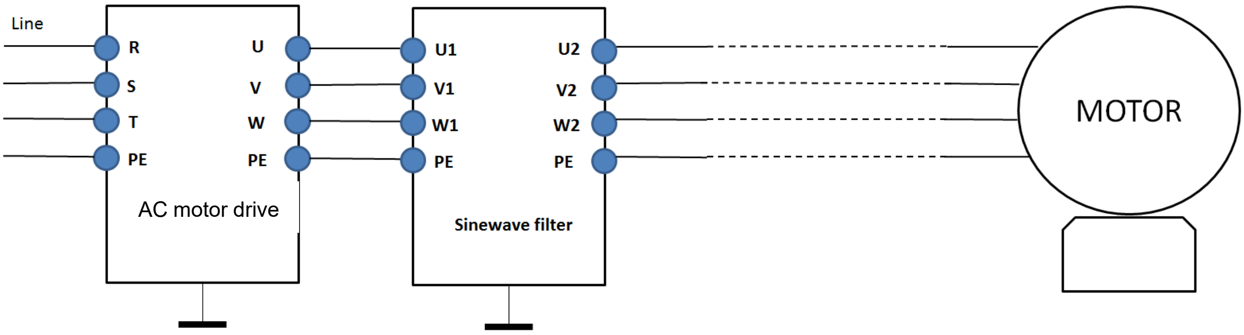
Sine-wave filter

When there is longer cable length connected between the motor drive and the motor, the damping leads to high frequency resonator, and makes impedance matching poor to enlarge the voltage reflection. This phenomenon will generate twice-input voltage in the motor side, which will easily make motor voltage overshoot to damage insulation.

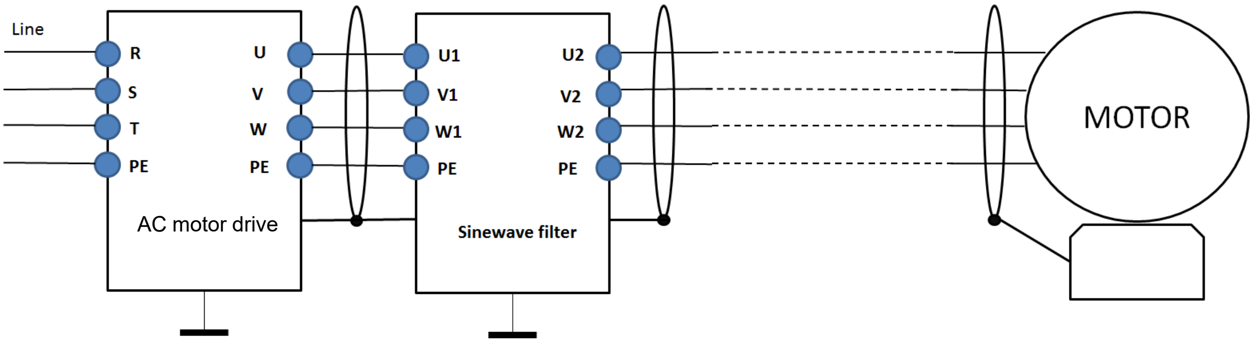
To prevent this, installing sine-wave filter can transform PWM output voltage to smooth and low-ripple sin wave, and motor cable length can be longer than 1000 meters.

Installation

Sine-wave filter is serially connected between motor drive UVW output side and motor, which is shown as below:



Wiring of non-shielded cable Figure 7-39



Wiring of shielded cable Figure 7-40

Following table shows the sine-wave filter specification of Delta CP2000

200V–230V, 50 / 60 Hz

230V Model	kW	HP	Rated Current (Arms)		Suggested Sine-wave Filter Part #	Output Cable Length (Shielded or Non-shielded)
			Normal Duty	Light Duty		
VFD007CP23A-21	0.75	1	4.6	5	B84143V0006R227	1000
VFD015CP23A21	1.5	2	5	7.5	B84143V0011R227	1000
VFD022CP23A-21	2.2	3	8	10	B84143V0011R227	1000
VFD037CP23A-21	3.7	5	11	15	B84143V0025R227	1000
VFD055CP23A-21	5.5	7.5	17	21	B84143V0025R227	1000
VFD075CP23A-21	7.5	10	25	31	B84143V0033R227	1000
VFD110CP23A-21	11	15	33	46	B84143V0050R227	1000
VFD150CP23A-21	15	20	49	61	B84143V0066R227	1000
VFD185CP23A-21	18.5	25	65	75	B84143V0075R227	1000
VFD220CP23A-21	22	30	75	90	B84143V0095R227	1000
VFD300CP23A-21	30	40	90	105	B84143V0132R227	1000
VFD370CP23A-00/-21	37	50	120	146	B84143V0180R227	1000
VFD450CP23A-00/-21	45	60	146	180	B84143V0180R227	1000
VFD550CP23A-00/-21	55	75	180	215	B84143V0250R227	1000
VFD750CP23A-00/-21	75	100	215	276	B84143V0320R227	1000
VFD900CP23A-00/-21	90	125	255	322	Non-available	1000

Table 7-67

380V–460V, 50 / 60 Hz

460V Model	kW	HP	Rated Current (Arms)		Suggested Sine-wave Filter Part #	Output Cable Length (Shielded or Non-shielded)
			Normal Duty	Light Duty		
VFD007CP43A-021/4EA-21	0.75	1	2.8	3	B84143V0004R227	1000
VFD015CP43B-21/4EB-21	1.5	2	3	4.2	B84143V0006R227	1000
VFD022CP43B-21/4EB-21	2.2	3	4	5.5	B84143V0006R227	1000
VFD037CP43B-21/4EB-21	3.7	5	6	8.5	B84143V0011R227	1000
VFD040CP43A-21/4EA-21	4	5	9	10.5	B84143V0011R227	1000
VFD055CP43B-21/4EB-21	5.5	7.5	10.5	13	B84143V0016R227	1000
VFD075CP43B-21/4EB-21	7.5	10	12	18	B84143V0025R227	1000
VFD110CP43B-21/4EB-21	11	15	18	24	B84143V0025R227	1000
VFD150CP43B-21/4EB-21	15	20	24	32	B84143V0033R227	1000
VFD185CP43B-21/4EB-21	18.5	25	32	38	B84143V0050R227	1000
VFD220CP43A-21/4EA-21	22	30	38	45	B84143V0050R227	1000
VFD300CP43B-21/4EB-21	30	40	45	60	B84143V0066R227	1000
VFD370CP43B-21/4EB-21	37	50	60	73	B84143V0075R227	1000
VFD450CP43S-00/43S-21	45	60	73	91	B84143V0095R227	1000
VFD550CP43S-00/43S-21	55	75	91	110	B84143V0132R227	1000
VFD750CP43B-00/43B-21	75	100	110	150	B84143V0180R227	1000
VFD900CP43A-00/43A-21	90	125	150	180	B84143V0180R227	1000

460V Model	kW	HP	Rated Current (Arms)		Suggested Sine-wave Filter Part #	Output Cable Length (Shielded or Non-shielded)
			Normal Duty	Light Duty		
VFD1100CP43A-00/43A-21	110	150	180	220	B84143V0250R227	1000
VFD1320CP43B-00/43B-21	132	175	220	260	B84143V0320R227	1000
VFD1600CP43A-00/43A-21	160	215	260	310	B84143V0320R227	1000
VFD1850CP43B-00/43B-21	185	250	310	370	Non-available	
VFD2000CP43A-00/43A-21	200	270	335	395	Non-available	
VFD2200CP43A-00/43A-21	220	300	370	460	Non-available	
VFD2500CP43A-00/43A-21	250	340	415	481	Non-available	
VFD2800CP43A-00/43A-21	280	375	460	530	Non-available	
VFD3150CP43A-00/ VFD3150CP43C-00/-21	315	420	550	616	Non-available	
VFD3550CP43A-00/ VFD3550CP43C-00/-21	355	475	616	683	Non-available	
VFD4000CP43A-00/ VFD4000CP43C-00/-21	400	536	683	770	Non-available	
VFD5000CP43A-00/ VFD5000CP43C-00/-21	500	675	866	912	Non-available	
VFD5600CP43A-00/43C-21	560	650	930	1294	Non-available	
VFD6300CP43A-00/43C-21	630	750	1094	1212	Non-available	

Table 7-68

Sine-wave output filters	Click on this URL for more information http://en.tdk.eu/inf/30/db/emc_2014/B84143V_R227.pdf
B84143V0004R227	I_R:4A, Sine-wave output filters for 3-phase systems
B84143V0006R227	I_R:6A, Sine-wave output filters for 3-phase systems
B84143V0011R227	I_R:11A, Sine-wave output filters for 3-phase systems
B84143V0016R227	I_R:16A, Sine-wave output filters for 3-phase systems
B84143V0025R227	I_R:25A, Sine-wave output filters for 3-phase systems
B84143V0033R227	I_R:33A, Sine-wave output filters for 3-phase systems
B84143V0050R227	I_R:50A, Sine-wave output filters for 3-phase systems
B84143V0066R227	I_R:66A, Sine-wave output filters for 3-phase systems
B84143V0075R227	I_R:75A, Sine-wave output filters for 3-phase systems
B84143V0095R227	I_R:95A, Sine-wave output filters for 3-phase systems
B84143V0132R227	I_R:132A, Sine-wave output filters for 3-phase systems
B84143V0180R227	I_R:180A, Sine-wave output filters for 3-phase systems
B84143V0250R227	I_R:250A, Sine-wave output filters for 3-phase systems
B84143V0320R227	I_R:320A, Sine-wave output filters for 3-phase systems

Table 7-69

7-5 Zero Phase Reactors

Reactor model (Note)	Recommended Wire Size		Wiring Method	Qty	Corresponding motor drives

RF008X00A
or
RF008X00N
	≤ 8 AWG	≤ 8.37 mm^2	Diagram A	1	VFD007CP23A-21; VFD007CP43A/4EA-21;
					VFD015CP23A-21; VFD015CP43B/4EB-21;
					VFD022CP23A-21;VFD022CP43B/4EB-21;
					VFD037CP23A-21; VFD037CP43B/4EB-21;
					VFD040CP43A/4EA-21; VFD055CP23A-21;
					VFD055CP43B/4EB-21; VFD075CP43B/4EB-21;
					VFD022CP53A-21; VFD037CP53A-21

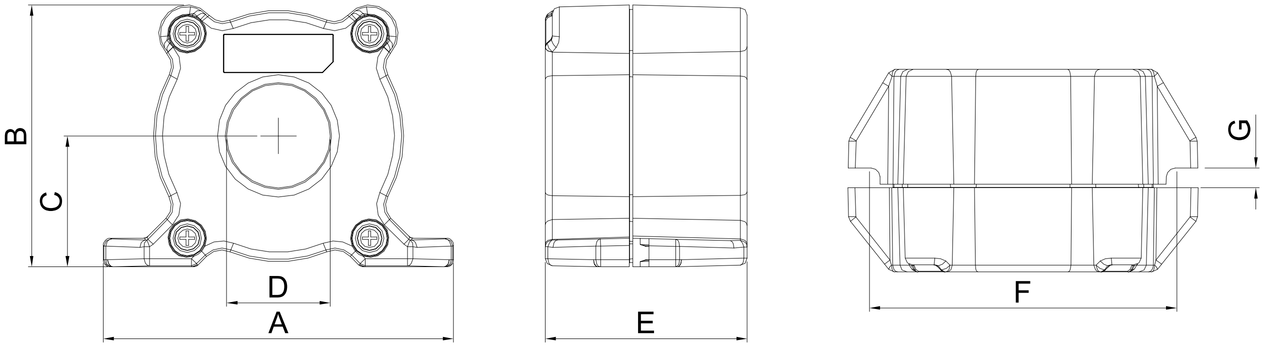
RF004X00A
or
RF004X00N
	≤ 4 AWG	≤ 21.15 mm^2	Diagram A	1	VFD075CP23A-21; VFD110CP23A-21;
					VFD110CP43B/4EB-21; VFD150CP23A-21;
					VFD150CP43B/4EB-21; VFD185CP43B/4EB-21;
					VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21;
					VFD150CP53A-21

RF002X00A
or
RF410X00N
	≤ 2 AWG	≤ 33.62 mm^2	Diagram A	1	VFD185CP23A-21; VFD220CP23A-21;
					VFD220CP43A/4EA-21; VFD300CP23A-21;
					VFD300CP43B/4EB-21; VFD370CP43B/4EB-21;
					VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21;
					VFD370CP63A-21; VFD370CP23A-00/23A-21;
					VFD450CP23A-00/23A-21; VFD750CP43B-00/43B-21;
					VFD900CP43A-00/43A-21; VFD450CP63A-00;
					VFD550CP63A-00; VFD450CP63A-21; VFD550CP63A-21

RF300X00A
or
RF300X00N
	≤ 300 MCM	≤ 152 mm^2	Diagram A	1	VFD450CP43S-00; VFD550CP43S-00; VFD450CP43S-21;
					VFD550CP43S-21;
					VFD550CP23A-00/23A-21; VFD750CP23A-00/23A-21;
					VFD900CP23A-00/23A-21; VFD1100CP43A-00/43A-21;
					VFD1320CP43B-00/43B-21; VFD750CP63A-00;
					VFD900CP63A-00; VFD1100CP63A-00;
					VFD1320CP63A-00; VFD750CP63A-21; VFD900CP63A-21;
					VFD1100CP63A-21; VFD1320CP63A-21;
					VFD1600CP43A-00/43A-21; VFD1850CP43B-00/43B-21;
					VFD1600CP63A-00; VFD2000CP63A-00;
					VFD1600CP63A-21; VFD2000CP63A-21;
					VFD2000CP43A-00/43A-21;
					VFD2200CP43A-00/43A-21;
					VFD2500CP43A-00/43A-21; VFD2800CP43A-00/43A-21;
					VFD2500CP63A-00; VFD3150CP63A-00;
					VFD2500CP63A-21; VFD3150CP63A-21;
					VFD3150CP43A-00/43C-00/43C-21;
					VFD3550CP43A-00/43C-00/43C-21;
					VFD4000CP43A-00/43C-00/43C-21; VFD4000CP63A-00;
					VFD4500CP63A-00; VFD5600CP63A-00;
					VFD6300CP63A-00; VFD4000CP63A-21;
					VFD4500CP63A-21; VFD5600CP63A-21;
					VFD6300CP63A-21

*575V insulated power cable

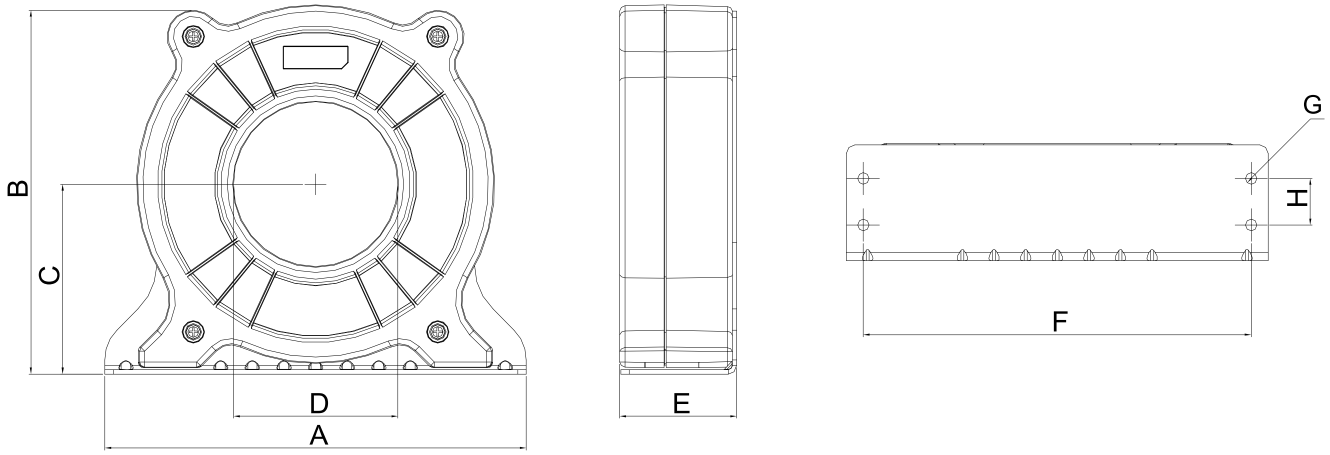
Table 7-70



Unit: mm [inch]

Model	A	B	C	D	E	F	G[Ø]	Torque
RF008X00A	98 [3.858]	73 [2.874]	36.5 [1.437]	29 [1.142]	56.5 [2.224]	86 [3.386]	5.5 [0.217]	< 10 kgf/cm^2
RF004X00A	110 [4.331]	87.5 [3.445]	43.5 [1.713]	36 [1.417]	53 [2.087]	96 [3.780]	5.5 [0.217]	< 10 kgf/cm^2

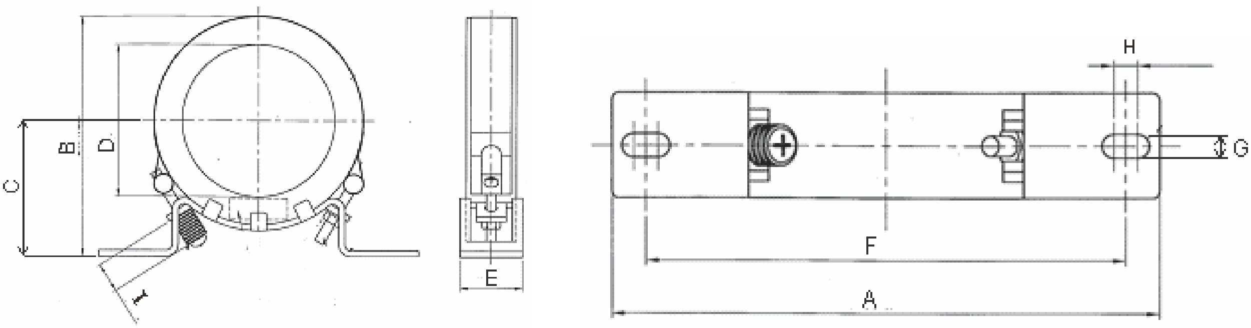
Table 7-71



Unit: mm [inch]

Model	A	B	C	D	E	F	G[Ø]	H	Torque
RF002X00A	200 [7.874]	172.5 [6.791]	90 [3.543]	78 [3.071]	55.5 [2.185]	184 [7.244]	5.5 [0.217]	22 [0.866]	<45 kgf/cm^2

Table 7-72



Unit: mm [inch]

Model	A	B	C	D	E	F	G[Ø]	H	I
RF300X00A	241 [9.488]	217[8.543]	114 [4.488]	155 [6.102]	42 [1.654]	220 [8.661]	6.5 [0.256]	7.0 [0.276]	20 [0.787]

Table 7-73

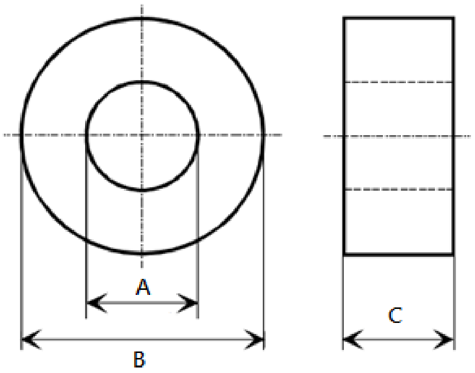


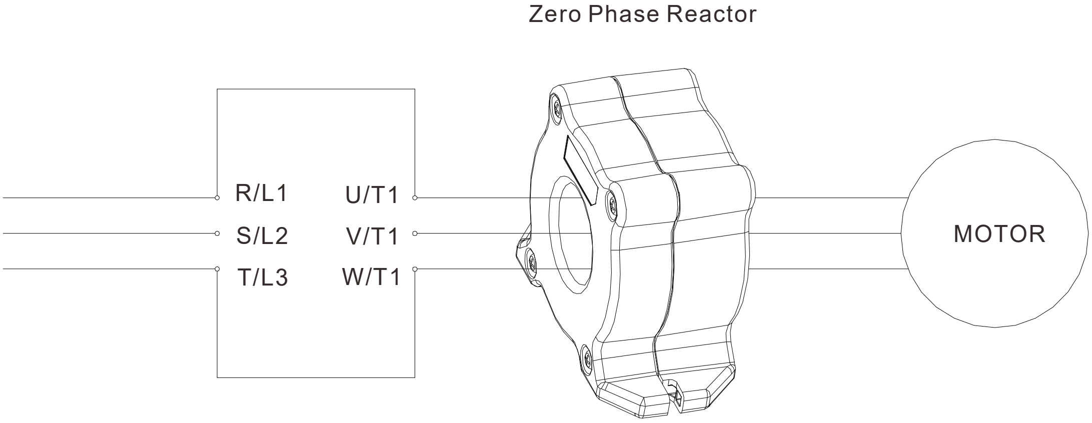
Figure 7-43

Model	A	B	C	Application
RF008X00N	22.5	43.1	18.5	Motor cable
RF004X00N	36.3	53.5	23.4	Motor cable
RF410X00N	108.1	70	30.3	Motor cable
RF300X00N	166.9	123.9	30.5	Motor cable
RF026X00N	10.7	17.8	8.0	Signal cable
RF020X00N	17.5	27.3	12.3	Signal cable

Table 7-74

Diagram A

Put all wires through at least one core without winding.



Note 1: The table above gives approximate wire size for the zero phase reactors, but the selection is ultimately governed by the type and diameter of cable fitted i.e. the cable must fit through the center hole of zero phase reactors.

Note 2: Only the phase conductors should pass through, not the earth core or screen.

Note 3: When using long motor output cables, an output zero phase reactor may be required to reduce radiated emissions from the cable.

7-6 EMC Filter

Following table is the external EMC filter of CP2000 series. User can choose corresponding zero phase reactor and suitable shielded cable length in accord to required noise emission and electromagnetic interference level to achieve the best configuration to suppress the electromagnetic interference. When the application does not consider RE interference and only needs CE to comply with C2 or C1, there is no need to install zero phase reactor on the input side.

230V / 460V Model

Frame	Model	Input Current [A]	Applicable EMC Filter	Zero Phase* Reactor		Carrier Frequency	CE Cable Length		Radiation Emission
				Input Side (R/S/T)	Output Side (U/V/W)		default carrier frequency		
							C1	C2	EN61800-3
A	VFD007CP23A	6.4	EMF021A23A	RF008X00A	RF008X00A	≤ 8 kHz	50 m	100 m	C2
	VFD015CP23A	9.6							
	VFD022CP23A	15							
	VFD037CP23A	22							
	VFD055CP23A	25	EMF056A23A						
B	VFD075CP23A	35		RF004X00A	RF004X00A				
	VFD110CP23A	50							
	VFD150CP23A	65	KMF3100A						
C	VFD185CP23A	83		N/A	RF002X00A	≤ 6 kHz			
	VFD220CP23A	100							
	VFD300CP23A	116	B84143D0150R127						
D	VFD370CP23A	146							
	VFD450CP23A	180	B84143B0250S020						
E	VFD550CP23A	215		N/A	RF300X00A	≤ 4 kHz			
	VFD750CP23A	276	B84143B0400S020						
	VFD900CP23A	322							
A	VFD007CP43A	4.3	EMF014A43A	RF008X00A	RF008X00A	≤ 8 kHz			
	VFD015CP43B	6							
	VFD022CP43B	8.1							
	VFD037CP43B	12.4							
	VFD040CP43A	16	EMF039A43A						
	VFD055CP43B	20							
	VFD075CP43B	22				≤ 8 kHz			
B	VFD110CP43B	26		RF004X00A	RF004X00A				
	VFD150CP43B	35							
	VFD185CP43B	42	KMF370A						
C	VFD220CP43A	50		N/A	RF002X00A	≤ 6 kHz			
	VFD300CP43B	66							
	VFD370CP43B	80	B84143D0150R127						
D0	VFD450CP43S	91							
D0	VFD550CP43S	110	B84143D0150R127	N/A	RF002X00A	≤ 6 kHz	50 m	100 m	Pass
D	VFD750CP43B	150				≤ 4 kHz			
	VFD900CP43A	180	B84143D0200R127						
E	VFD1100CP43A	220		N/A	RF300X00A				
	VFD1320CP43B	260	MIF3400B						
F	VFD1600CP43A	310							
	VFD1850CP43B	370							
G	VFD2000CP43A	395							
	VFD2200CP43A	460	MIF3800						
	VFD2500CP43A	481							
	VFD2800CP43A	530							
H	VFD3150CP43A	616							
	VFD3550CP43A	683							
	VFD4000CP43A	770							
	VFD5000CP43A	930	B84143B1000S020						
	VFD5600CP43A-00	1094	B84143B1600S020	Contact Delta for more information					
	VFD5600CP43C-21	1094							
	VFD6300CP43A-00	1212							
	VFD6300CP43C-21	1212							

Table 7-75

460V Model

CP2000			Applicable EMC Filter	Zero Phase Reactor		Carrier Freq.	Conducted Emission	Radiation Emission
Frame	Model	Rated Input Current [A]		Input Side (R/S/T)	Output Side (U/V/W)		Output Shielded Cable Length	EN61800-3
							EN618000-3 C2	
D0	VFD450CP43S	91	B84143B0120R110	N/A	N/A	≤ 6 kHz	25 m	*C2
	VFD550CP43S	110						
D	VFD750CP43B	150	B84143B0180S020		RF300X00A or RF300X00N			*C3
	VFD900CP43A	180				≤ 4 kHz	13 m	
E	VFD1100CP43A	220	B84143B0250S020					C2
	VFD1320CP43B	260	B84143B0320S020	B64290L0084X830				
F	VFD1600CP43A	310	B84143B0400S020					
	VFD1850CP43B	370						
G	VFD2000CP43A	395						
	VFD2200CP43A	460	B84143B0600S020			≤ 2 kHz		
	VFD2500CP43A	481						
	VFD2800CP43A	530						
H	VFD3150CP43A	616	B84143B1000S020					*C3
	VFD3550CP43A	683						
	VFD4000CP43A	770						
	VFD5000CP43A	930						
	VFD5600CP43A-00	1094	B84143B1600S020	Contact Delta for more information				
	VFD4500CP43C-21	1094						
	VFD6300CP43A-00	1212						
	VFD6300CP43C-21	1212						

*For radiated emission, the drive needs to be placed inside a cabinet.

Table 7-76

CP2000			Applicable EMC Filter	Zero Phase Reactor		Carrier Freq.	Conducted Emission	Radiation Emission
Frame	Model	Rated Input Current [A]		Input Side (R/S/T)	Output Side (U/V/W)		Output Shielded Cable Length	EN61800-3
							EN618000-3 C3	
D0	VFD450CP43S	91	B84143A0120R105	N/A	N/A	≤ 6 kHz	150 m	C3
	VFD550CP43S	110						
D	VFD750CP43B	150	B84143B0180S080					*C3
	VFD900CP43A	180				≤ 4 kHz		
E	VFD1100CP43A	220	B84143B0250S080					C3
	VFD1320CP43B	260	B84143B0320S080					
F	VFD1600CP43A	310	B84143B0400S080					
	VFD1850CP43B	370						
G	VFD2200CP43A	460	B84143B0600S080					
	VFD2800CP43A	530						
H	VFD3150CP43A	616	B84143B1000S080				100 m	
	VFD3550CP43A	683						
	VFD4000CP43A	770						
	VFD5000CP43A	930						
	VFD5600CP43A-00	1094	B84143B1600S080	Contact Delta for more information				
	VFD4500CP43C-21	1094						
	VFD6300CP43A-00	1212						
	VFD6300CP43C-21	1212						

*For radiated emission, the drive needs to be placed inside a cabinet.

Table 7-77

575V / 690V Model

Frame	Model	Input Current [A]	Applicable EMC Filter	Zero Phase* Reactor	CE Cable Length		Radiation Emission
					default carrier frequency		
					C1	C2	EN61800-3
A	VFD022CP53A-21	5.4	EMF008A63A	RF008X00A	50 m	100 m	C2
	VFD037CP53A-21	10.4	EMF014A63A				
B	VFD055CP53A-21	14.9	EMF027A63A				
	VFD075CP53A-21	16.9					
	VFD110CP53A-21	21.3					
	VFD150CP53A-21	26.3					
C	VFD185CP63A-21	29	B84143A0050R021	RF002X00A			
	VFD220CP63A-21	36					
	VFD300CP63A-21	43					
	VFD370CP63A-21	54					
D	VFD450CP63A-00 VFD450CP63A-21	54					
	VFD550CP63A-00 VFD550CP63A-21	67					
E	VFD750CP63A-00 VFD750CP63A-21	84	B84143A0120R021	RF300X00A			
	VFD900CP63A-00 VFD900CP63A-21	102					
	VFD1100CP63A-00 VFD1100CP63A-21	122	B84143B0150S021				
	VFD1320CP63A-00 VFD1320CP63A-21	147					
F	VFD1600CP63A-00 VFD1600CP63A-21	178	B84143B0250S021				
	VFD2000CP63A-00 VFD2000CP63A-21	217					
G	VFD2500CP63A-00 VFD2500CP63A-21	292	B84143B0400S021	RF300X00A	50 m	100 m	C2
	VFD3150CP63A-00 VFD3150CP63A-21	353					
H	VFD4000CP63A-00 VFD4000CP63A-21	454	B84143B0600S021				
	VFD4500CP63A-00 VFD4500CP63A-21	469					
H	VFD5600CP63A-00 VFD5600CP63A-21	595	B84143B0600S021				
	VFD6300CP63A-00 VFD6300CP63A-21	681	B84143B1000S021				

Table 7-78

* For Frame A–C: On both input and output side, a zero phase reactor is required to be wired to the motor drive. There should be in total 2 zero phase reactors.

For Frame D–H: Only one zero phase reactor is required to be wired on the output side of the motor drive.

EMC Filter Dimension

EMC filter model name: EMF021A23A; EMF014A43A

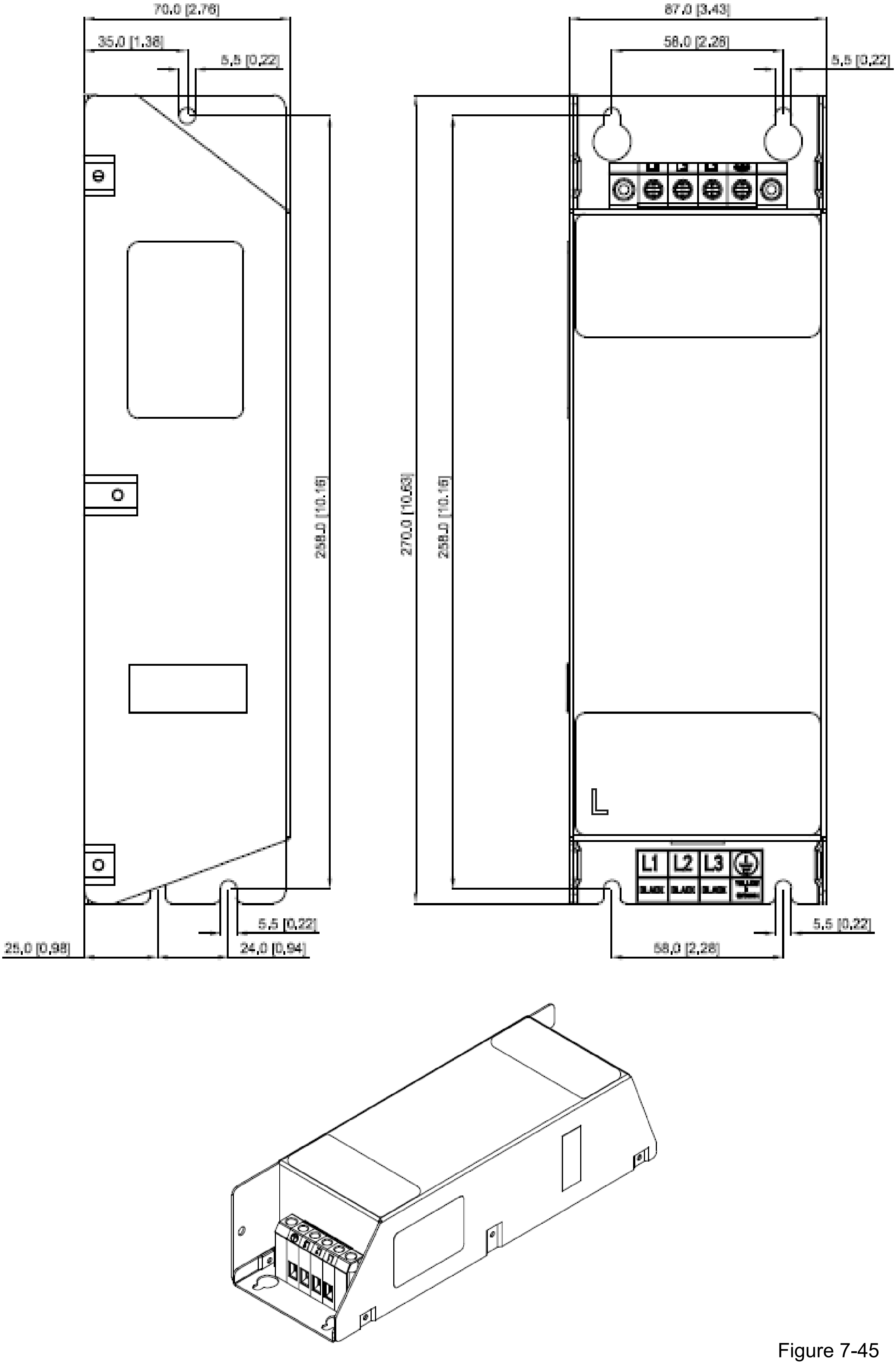


Figure 7-45

EMC filter model name: EMF018A43A

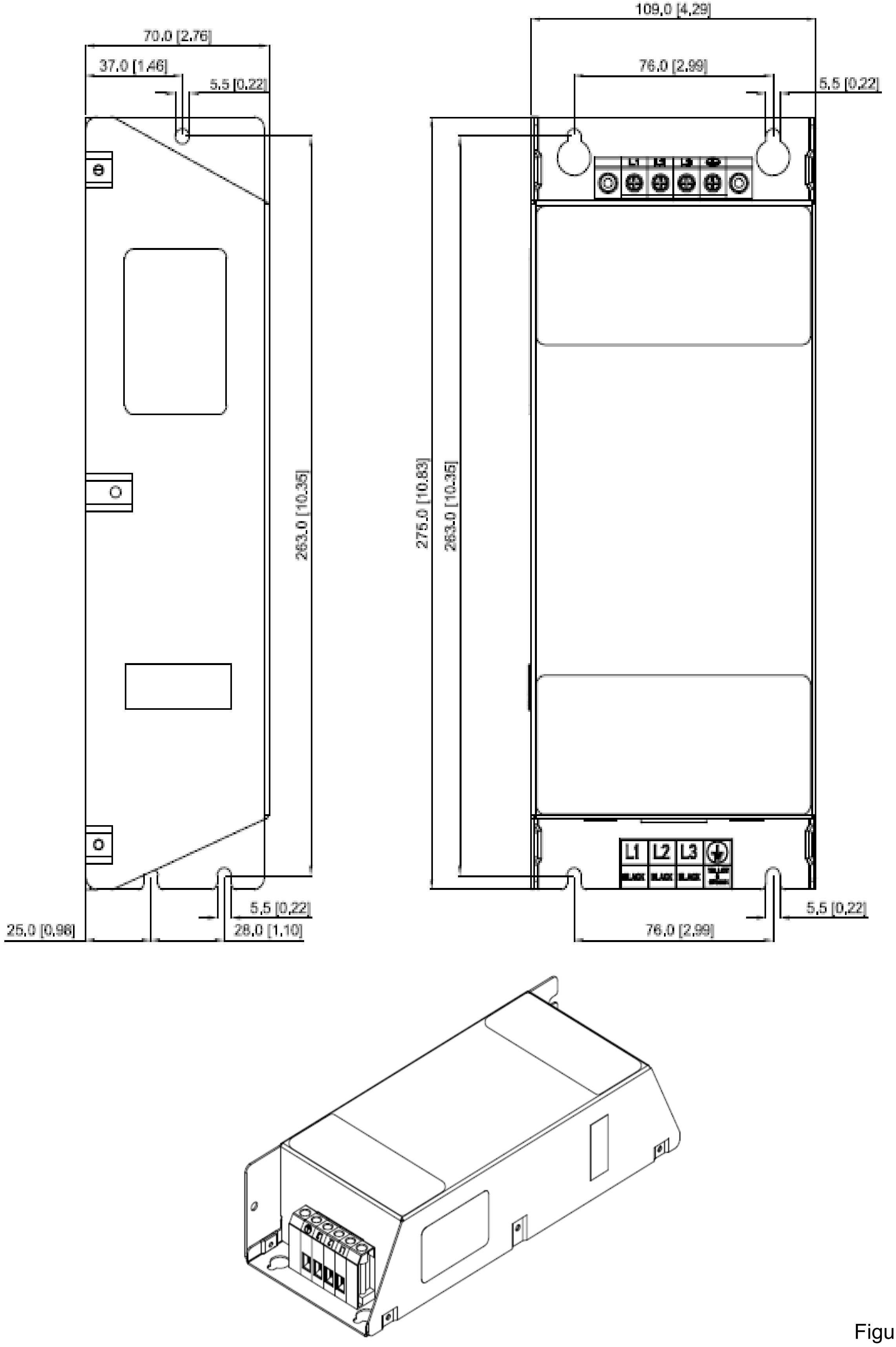


Figure 7-46

EMC filter model name: EMF056A23A; EMF039A43A

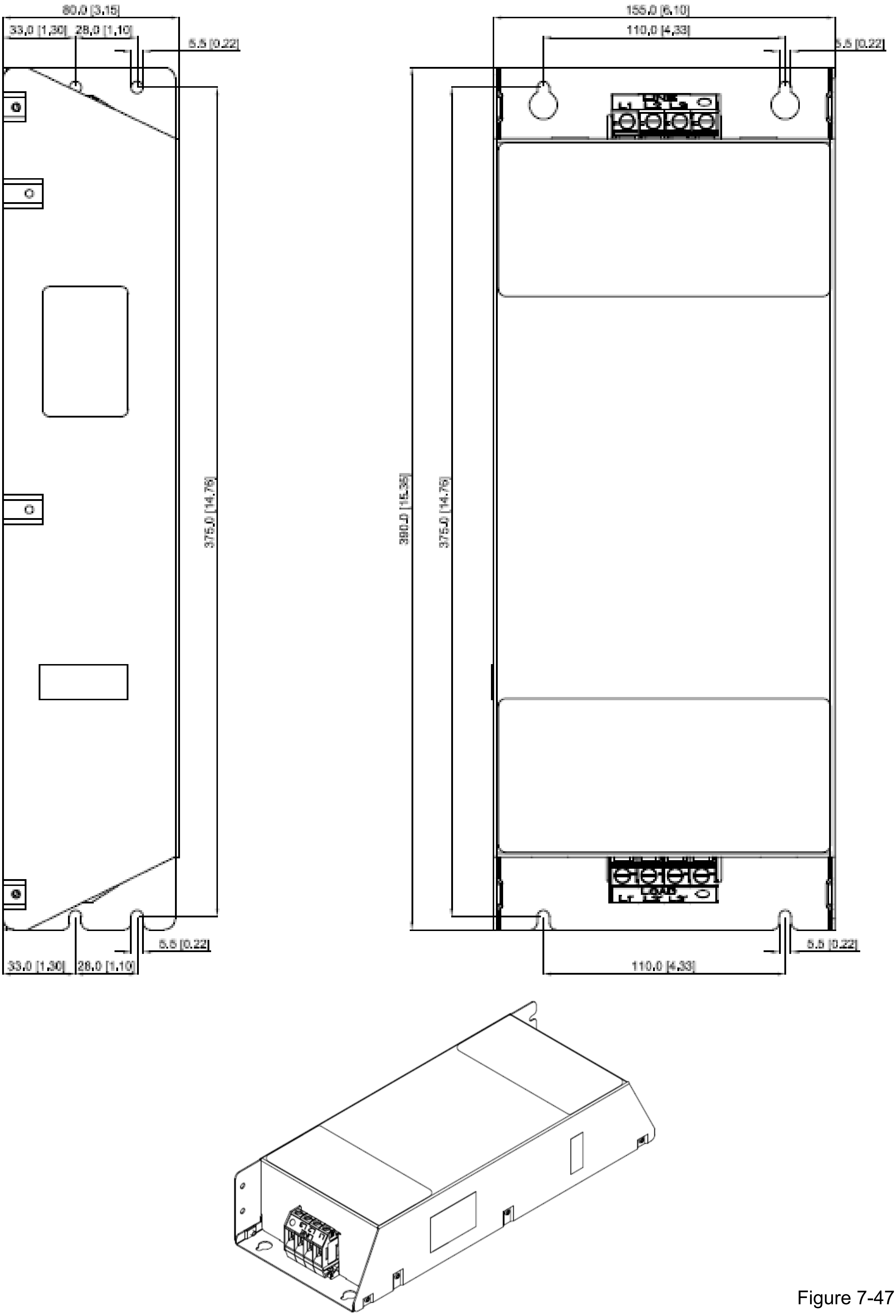


Figure 7-47

EMC filter model name: KMF370A; KMF3100A

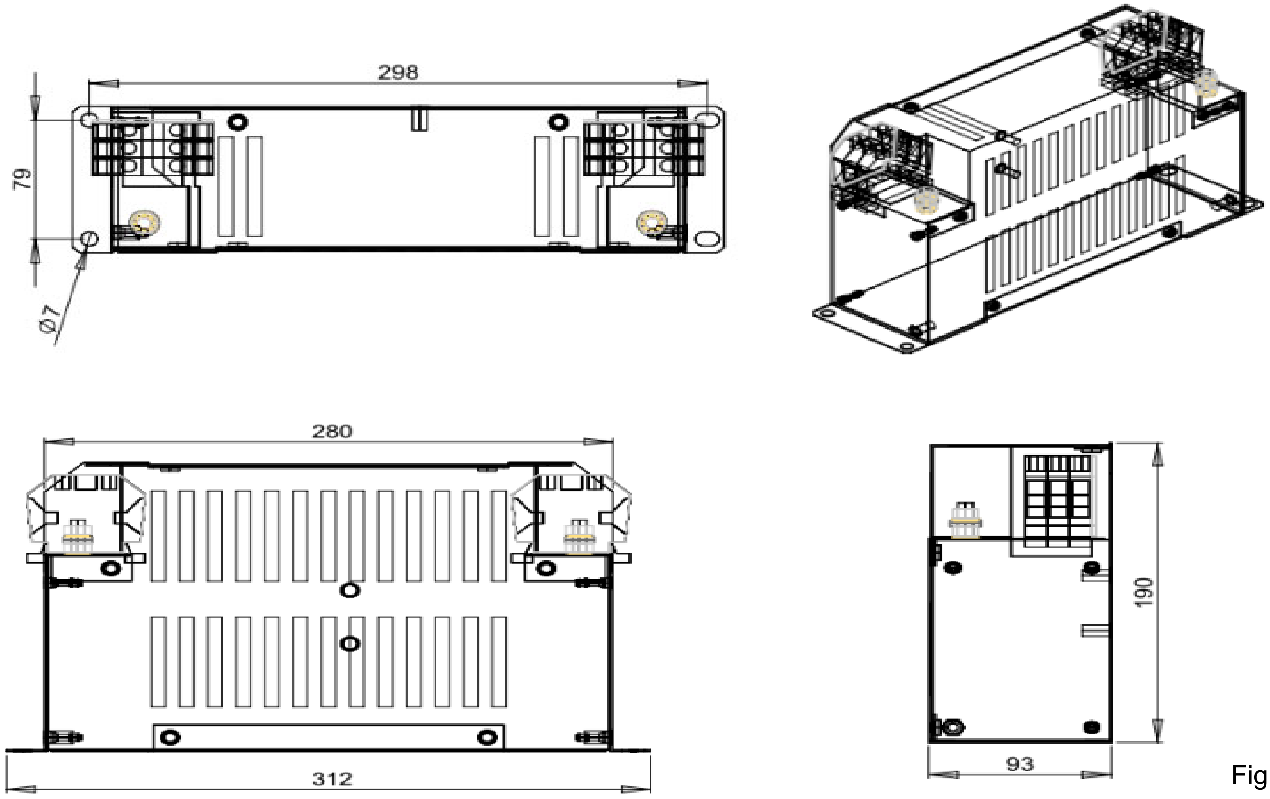


Figure 7-48

EMC filter model name: B84143D0150R127

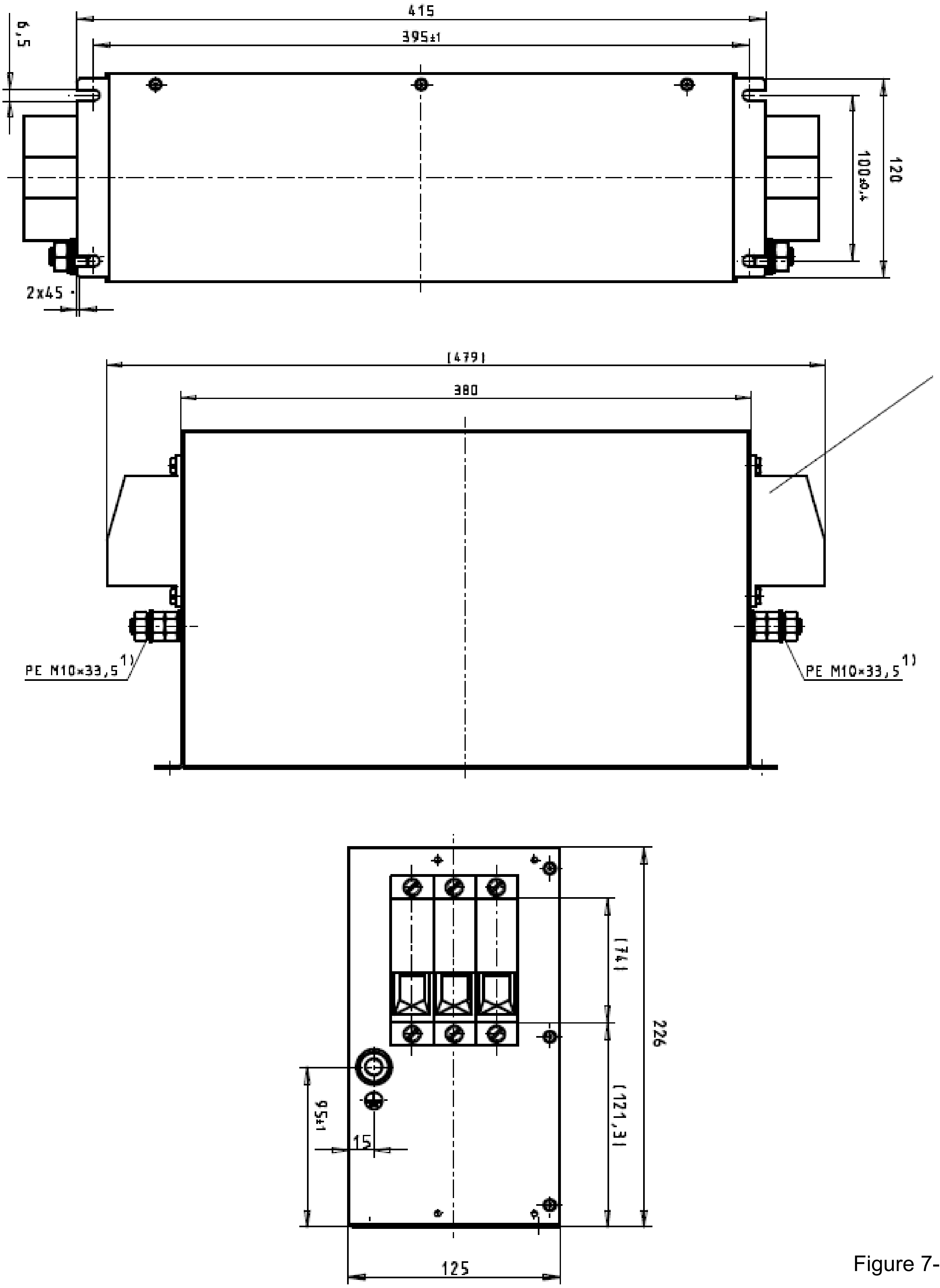


Figure 7-49

EMC filter model name: B84143D0200R127

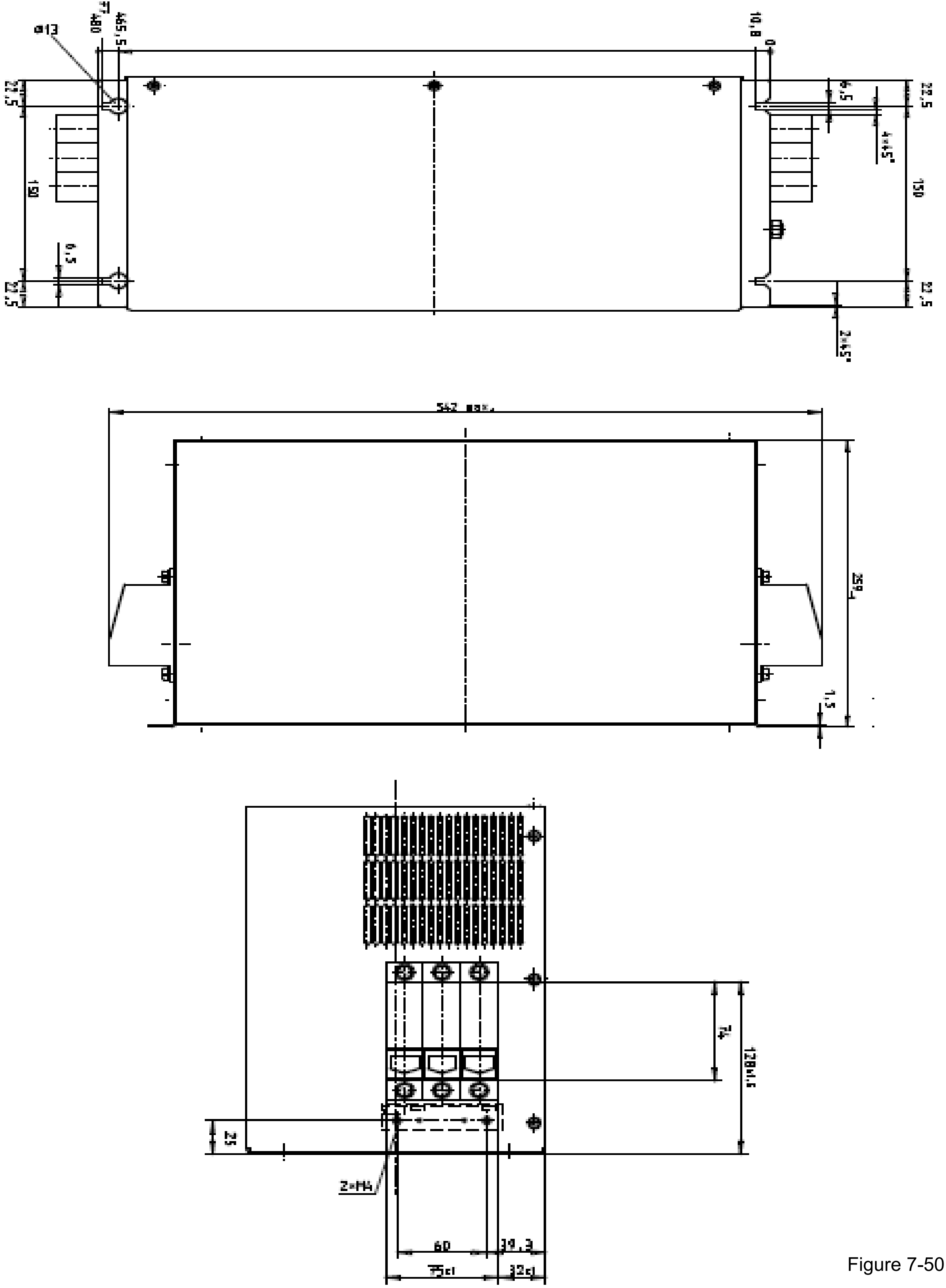


Figure 7-50

EMC filter model name: B84143B0250S020

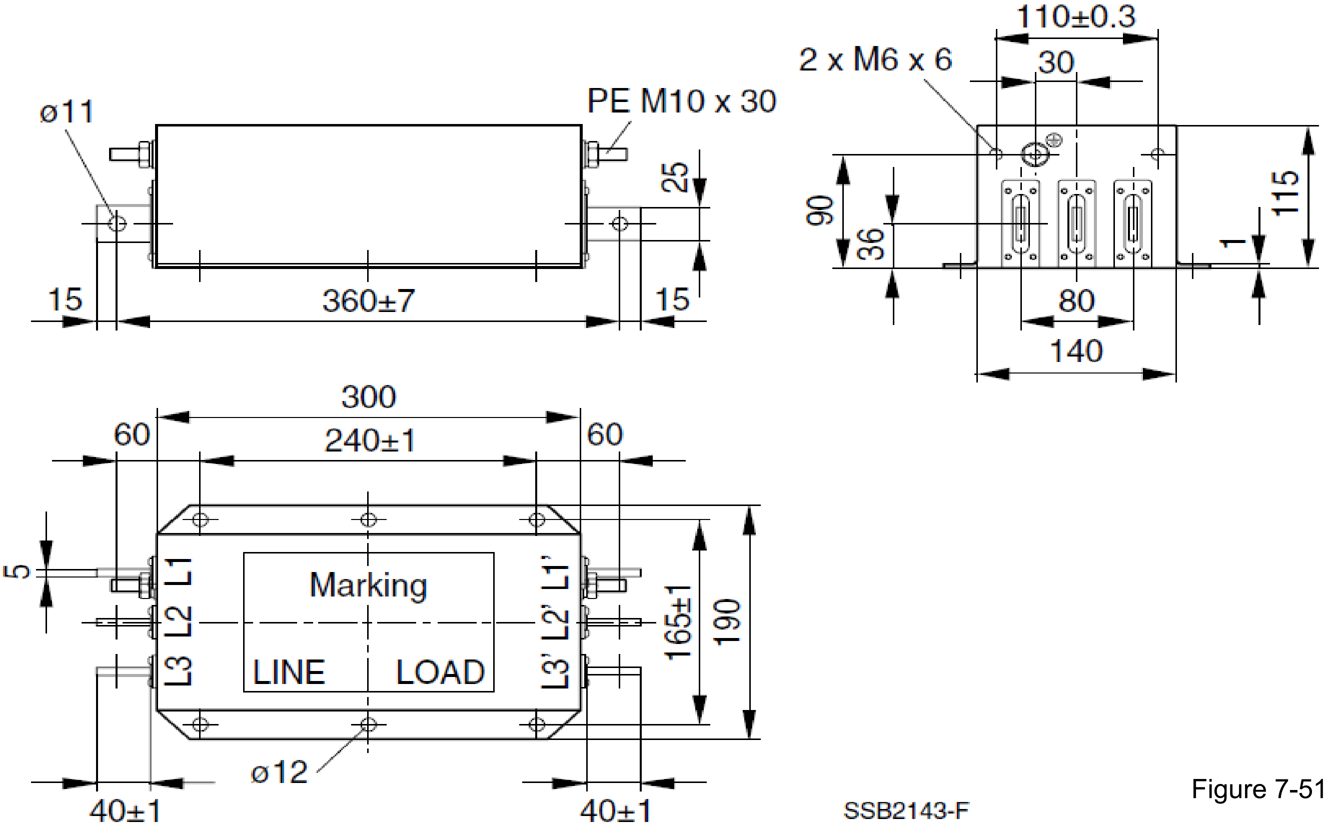


Figure 7-51

EMC filter model name: B84143B0400S020

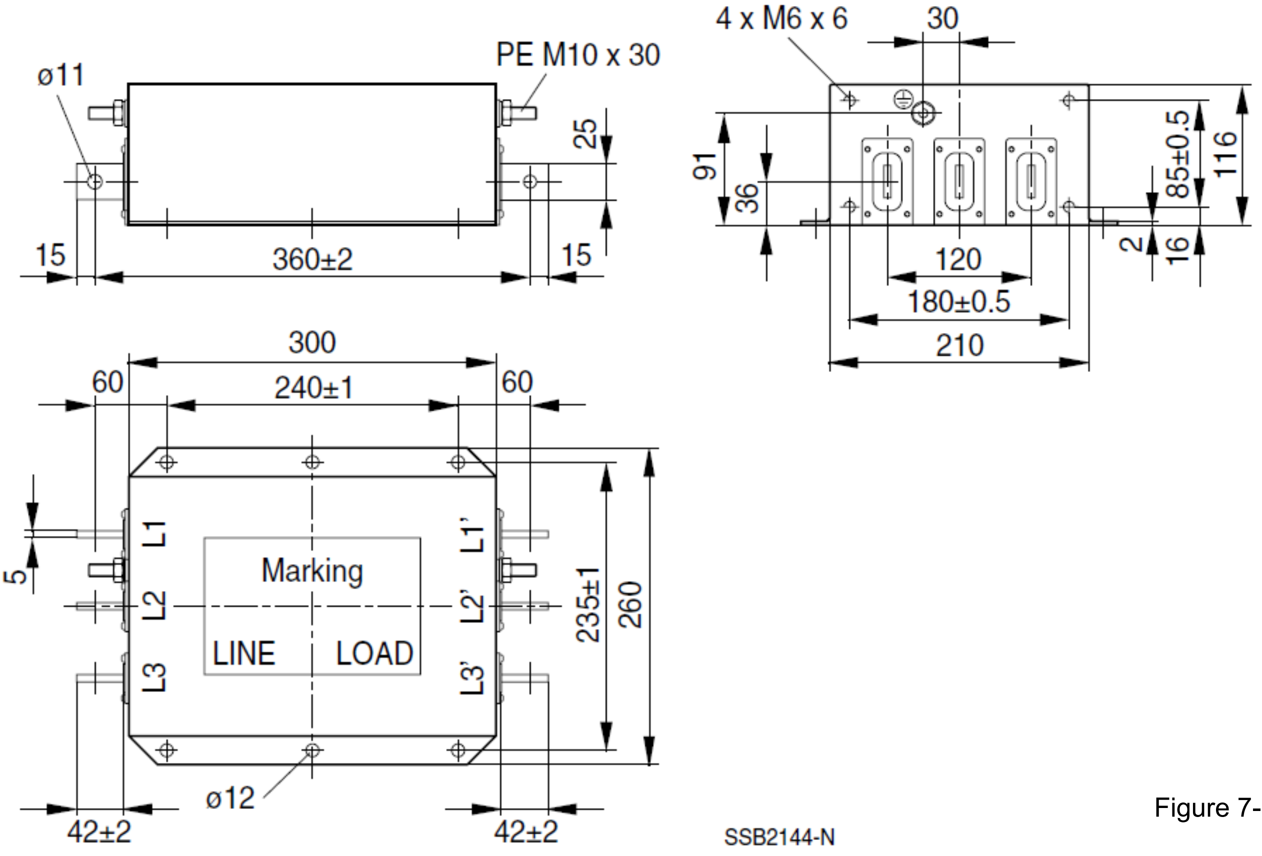


Figure 7-52

EMC filter model name: B84143B1000S020

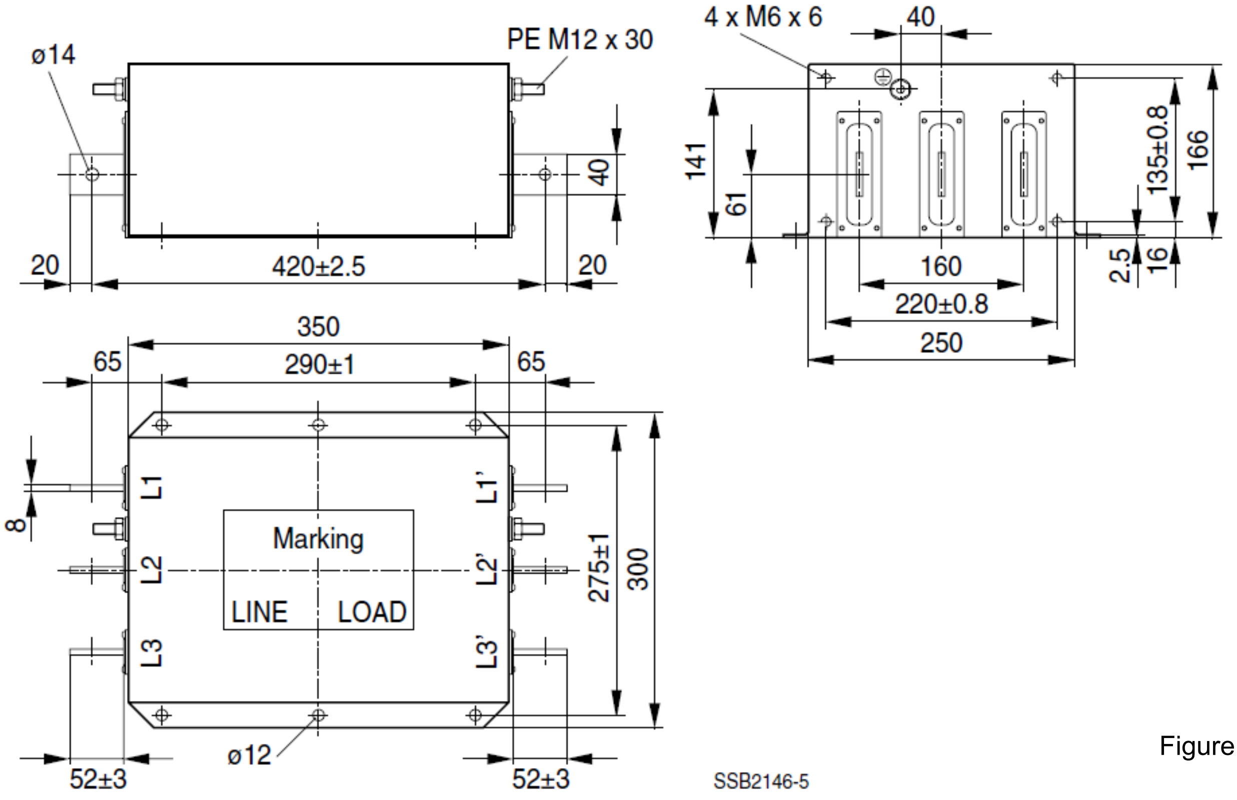


Figure 7-53

EMC filter model name: B84143B1600S020

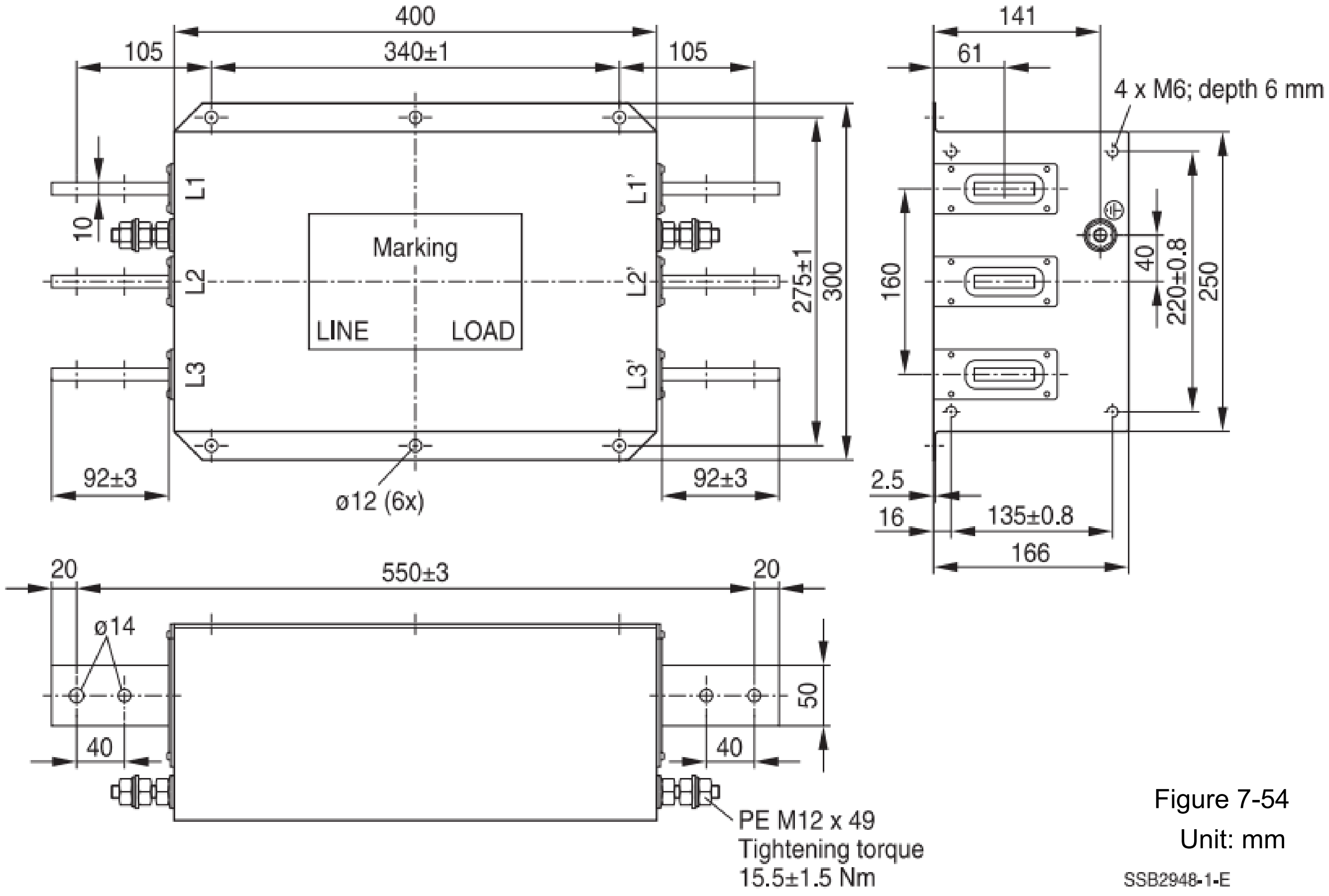


Figure 7-54

Unit: mm

The table below is the suggested shielded cable length for drive models with built-in EMC filters. You can choose the corresponding shielded cable length according to the required noise emission and electromagnetic interference level.

EMC built-in model		Rated current (ND)	Comply with EMC (IEC 61800-3) Class C3		Comply with EMC (IEC 61800-3) Class C2	
Frame	Model		Shielded cable length	Fc	Shielded cable length	Fc
A	VFD007CP4EA-21	3.5	30 m	≤ 8 kHz	10 m	≤ 8 kHz
	VFD015CP4EB-21	4.3				
	VFD022CP4EB-21	5.9				
	VFD037CP4EB-21	8.7				
	VFD040CP4EA-21	14				
	VFD055CP4EB-21	15.5				
	VFD075CP4EB-21	17				
B	VFD110CP4EB -21	20				
	VFD150CP4EB -21	26				
	VFD185CP4EB -21	35		≤ 6 kHz		≤ 6 kHz
C	VFD220CP4EA -21	40				
	VFD300CP4EB -21	47				
	VFD370CP4EB-21	63				

Table 7-79

* To prevent increment of wires parasitic capacitance and leakage current due to excessive cable length, which causes overheating of the built-in EMC filters, the shielded cable length for Frame A should not be longer than 30 m, and that for Frame B, C should not be longer than 50 m.

EMC Filter Installation

All electrical equipment (including AC motor drives) generate high or low frequency noise that interferes with peripheral equipment by radiation or conduction when during operation. Correctly install an EMC filter can eliminate much interference. It is recommended to use DELTA EMC filter to have the best interference elimination performance.

We assure that it can comply with the following rules when the AC motor drive and EMC filter are both installed and wired according to user manual:

- EN61000-6-4
- EN61800-3: 1996
- EN55011 (1991) Class A Group 1 (1st Environment, restricted distribution)

General precaution

To ensure the EMC filter maximizes the effect of suppressing the interference of AC motor drive, the installation and wiring of AC motor drive should follow the user manual. In addition, be sure to observe the following precautions:

1. Install the EMC filter and AC motor drive on the same metal plate.
2. Install the AC motor drive on footprint EMC filter or install the EMC filter as close as possible to the AC motor drive.
3. Wire as short as possible.
4. Ground the metal plate.
5. The cover of EMC filter and AC motor drive or grounding should be fixed on the metal plate and the contact area should be as large as possible.

Choose suitable motor cable and precautions

Improper installation and choice of motor cable affects the performance of EMC filter. Be sure to observe the following precautions when selecting motor cable.

1. Use the cable with shielding (double shielding is the best).
2. The shielding on both ends of the motor cable should be grounded with the minimum length and maximum contact area.
3. Remove any paint on metal saddle for good ground contact with the plate and shielding.

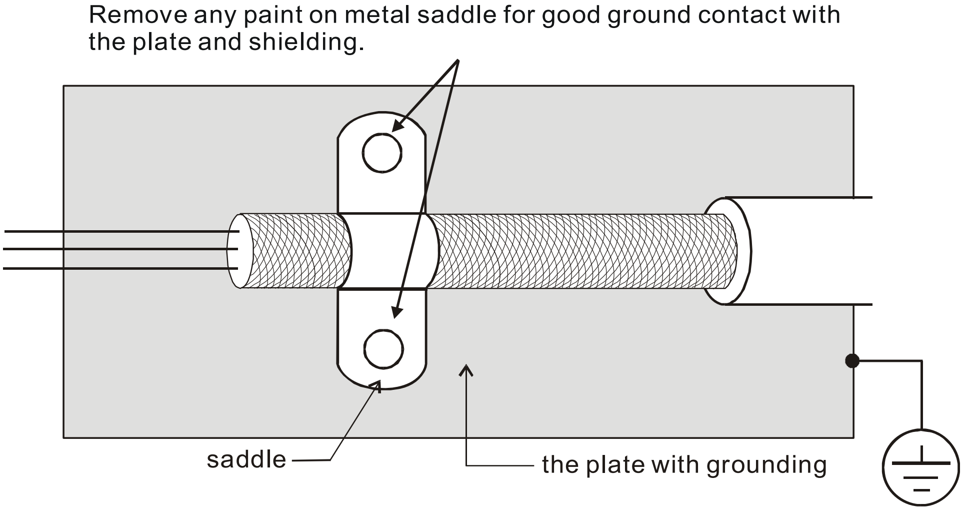
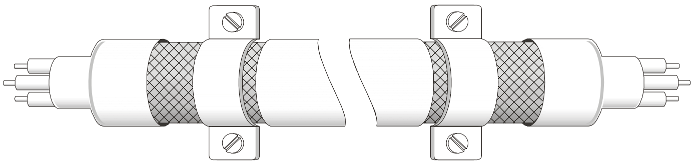
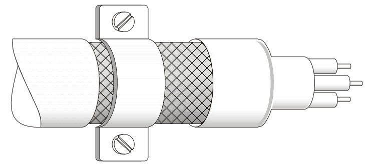

Remove any paint on metal saddle for good ground contact with the plate and shielding.
saddle
the plate with grounding

Figure 1



Saddle on both ends



Saddle on one end

Figure 2

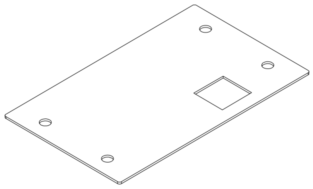
7-7 Panel Mounting (MKC-KPPK)

For MKC-KPPK model, you can choose wall mounting or embedded mounting, the protection level is IP66.

Applicable to the digital keypads (KPC-CC01).

Wall Mounting

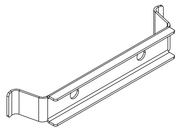
Accessories*1



Screw *4–M4*p 0.7 *L8mm
Torque: 10–12 kg-cm / [8.7–10.4 lb-in.] /
[1.0–1.2 Nm]

Embedded Mounting

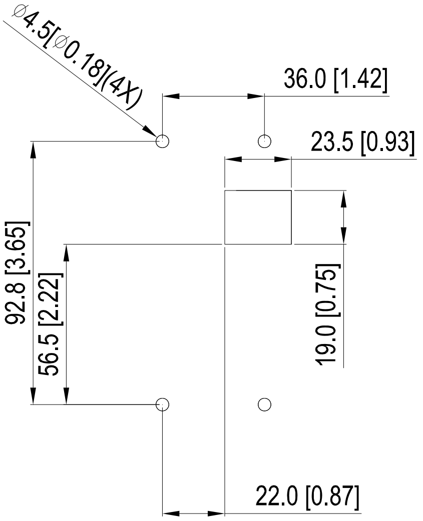
Accessories*2



Screw *4–M4*p 0.7 *L8mm
Torque: 10-12 kg–cm / [8.7–10.4 lb-in.] /
[1.0–1.2 Nm]

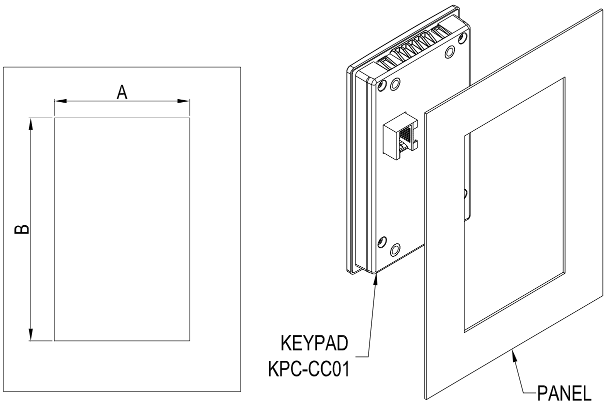
Wall Mounting

Panel cutout dimension Unit: mm [inch]



Embedded Mounting

Panel cutout dimension Unit: mm [inch]



Normal cutout dimension

Panel thickness	1.2 mm	1.6 mm	2.0 mm
A	66.4 [2.614]		
B	110.2 [4.339]	111.3 [4.382]	112.5 [4.429]

*Deviation: ±0.15 mm /±0.0059 inch

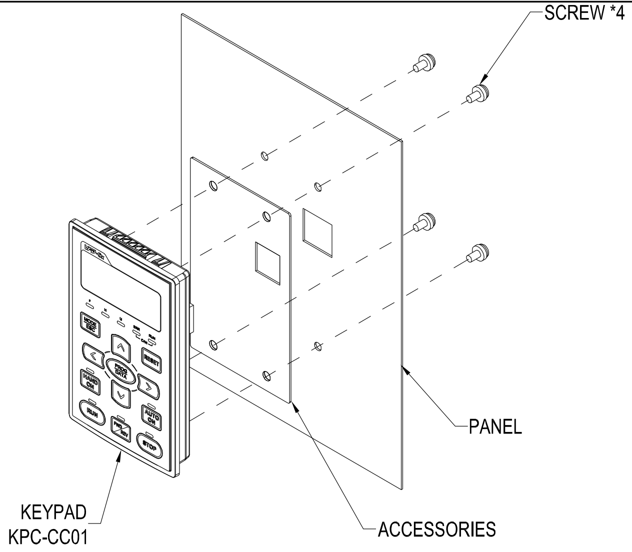
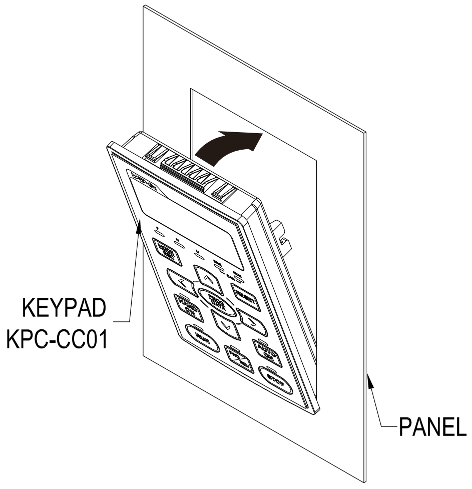
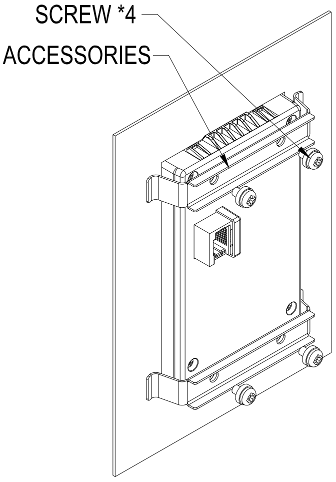
Table 7-80

Cutout dimension (Waterproof level: IP66)

Panel thickness	1.2 mm	1.6 mm	2.0 mm
A	66.4 [2.614]		
B	110.8 [4.362]		

*Deviation: ±0.15 mm /±0.0059 inch

Table 7-81

Wall Mounting	Embedded Mounting
	 

7-8 Conduit Box Kit

- Appearance

Conduit box kit is optional For VFDXXXCPXXA-XX (Frame D and above) and VFDXXXCP43S-XX, the protection level is IP20 / NEMA1 / UL TYPE1 after installation.

Frame D0

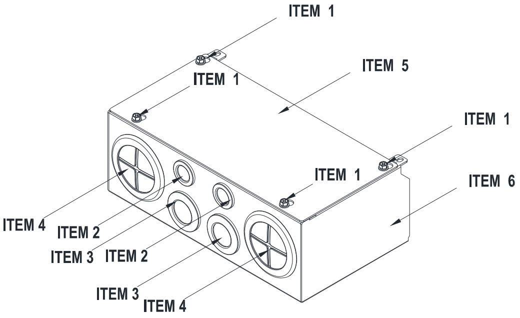
Applicable models:

VFD450CP43S-00, VFD550CP43S-00, VFD450CP43S-21, VFD550CP43S-21

Model number『MKC-D0N1CB』

ITEM	Description	Qty.
1	Screw M5*0.8*10L	4
2	Bushing Rubber 28	2
3	Bushing Rubber 44	2
4	Bushing Rubber 73	2
5	Conduit box cover	1
6	Conduit box base	1

Table 7-82



Frame D

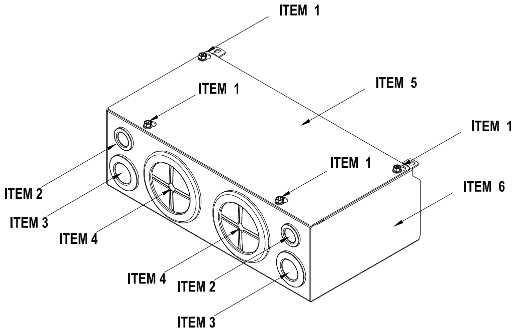
Applicable models:

VFD370CP23A-00, VFD450CP23A-00, VFD750CP43B-00, VFD900CP43A-00, VFD370CP23A-21, VFD450CP23A-21, VFD750CP43B-21, VFD900CP43A-21, VFD450CP63A-00, VFD550CP63A-00, VFD450CP63A-21, VFD550CP63A-21

Model number『MKC-DN1CB』

ITEM	Description	Qty.
1	Screw M5*0.8*10L	4
2	Bushing Rubber 28	2
3	Bushing Rubber 44	2
4	Bushing Rubber 88	2
5	Conduit box cover	1
6	Conduit box base	1

Table 7-83



Frame E

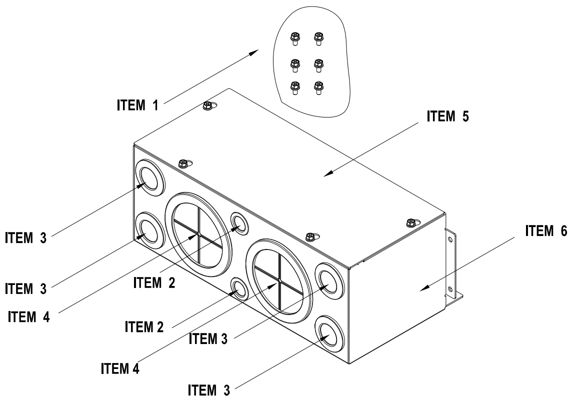
Applicable models:

VFD550CP23A-00, VFD750CP23A-00, VFD900CP23A-00, VFD1100CP43A-00, VFD1320CP43B-00, VFD550CP23A-21, VFD750CP23A-21, VFD900CP23A-21, VFD1100CP43A-21, VFD1320CP43B-21, VFD750CP63A-00, VFD900CP63A-00, VFD1100CP63A-00, VFD1320CP63A-00, VFD750CP63A-21, VFD900CP63A-21, VFD1100CP63A-21, VFD1320CP63A-21

Model number『MKC-EN1CB』

ITEM	Description	Qty.
1	Screw M5*0.8*10L	6
2	Bushing Rubber 28	2
3	Bushing Rubber 44	4
4	Bushing Rubber 100	2
5	Conduit box cover	1
6	Conduit box base	1

Table 7-84



Frame F

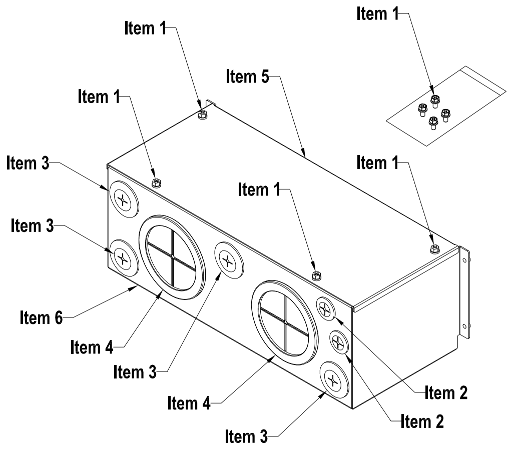
Applicable models:

VFD1600CP43A-00, VFD1850CP43B-00, VFD1600CP43A-21, VFD1850CP43B-21, VFD1600CP63A-00, VFD2000CP63A-00, VFD1600CP63A-21, VFD2000CP63A-21

Model number『MKC-FN1CB』

ITEM	Description	Qty.
1	Screw M5*0.8*10L	8
2	Bushing Rubber 28	2
3	Bushing Rubber 44	4
4	Bushing Rubber 100	2
5	Conduit box cover	1
6	Conduit box base	1

Table 7-85



Frame G

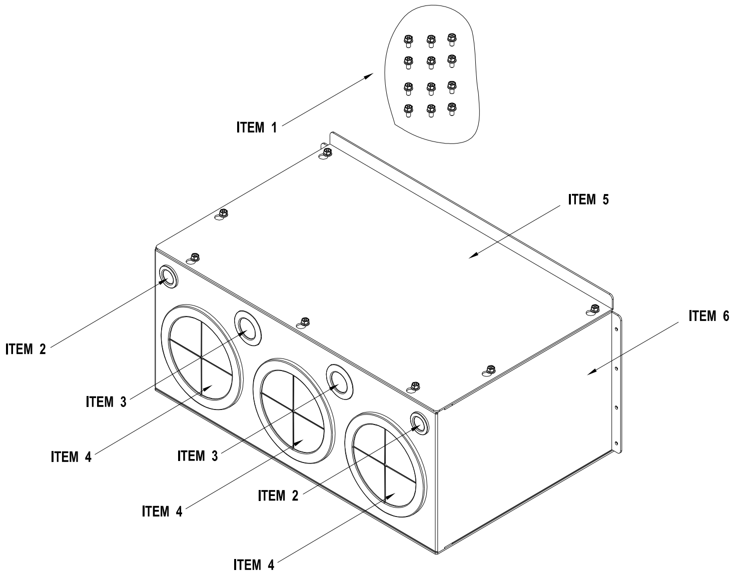
Applicable models:

VFD2000CP43A-00, VFD2200CP43A-00, VFD2500CP43A-00, VFD2800CP43A-00, VFD2000CP43A-21, VFD2200CP43A-21, VFD2500CP43A-21, VFD2800CP43A-21, VFD2500CP63A-00, VFD3150CP63A-00, VFD2500CP63A-21, VFD3150CP63A-21

型號『MKC-GN1CB』

ITEM	Description	Qty.
1	Screw M5*0.8*10L	12
2	Bushing Rubber 28	2
3	Bushing Rubber 44	2
4	Bushing Rubber 130	3
5	Conduit box cover	1
6	Conduit box base	1

Table 7-86



Frame H

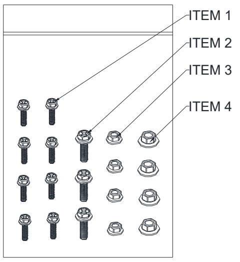
Applicable models:

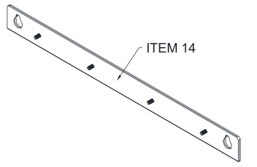
VFD3150CP43A-00, VFD3550CP43A-00, VFD4000CP43A-00, VFD5000CP43A-00, VFD5600CP43A-00, VFD6300CP43A-00, VFD3150CP43C-00, VFD3550CP43C-00, VFD4000CP43C-00, VFD5000CP43C-00, VFD3150CP43C-21, VFD3550CP43C-21, VFD4000CP43C-21, VFD5000CP43C-21, VFD5600CP43C-21, VFD6300CP43C-21, VFD4000CP63A-00, VFD4500CP63A-00, VFD5600CP63A-00, VFD6300CP63A-00, VFD4000CP63A-21, VFD4500CP63A-21, VFD5600CP63A-21, VFD6300CP63A-21

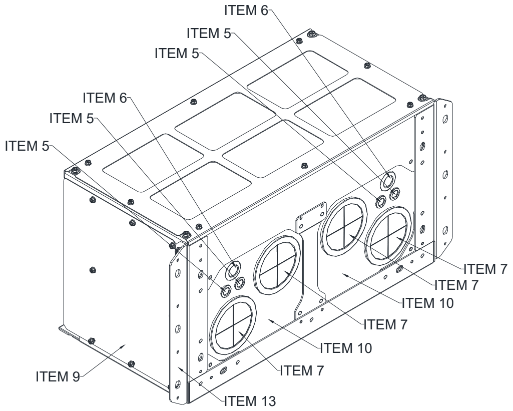
Model number『MKC-HN1CB』

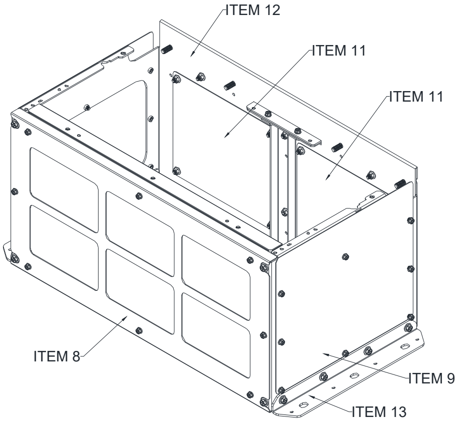
ITEM	Description	Qty.
1	Screw M6*1.0*25L	8
2	Screw M8*1.25*30L	3
3	NUT M8	4
4	NUT M10	4
5	Bushing Rubber 28	4
6	Bushing Rubber 44	2
7	Bushing Rubber 130	4
8	Conduit box cover 1	1
9	Conduit box cover 2	2
10	Conduit box cover 3	2
11	Conduit box cover 4	2
12	Conduit box base	1
13	Accessories 1	2
14	Accessories 2	1

Table 7-87





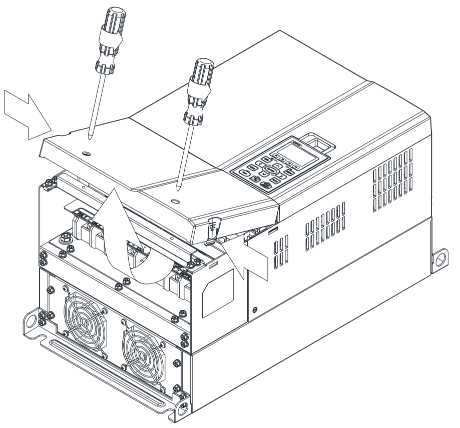




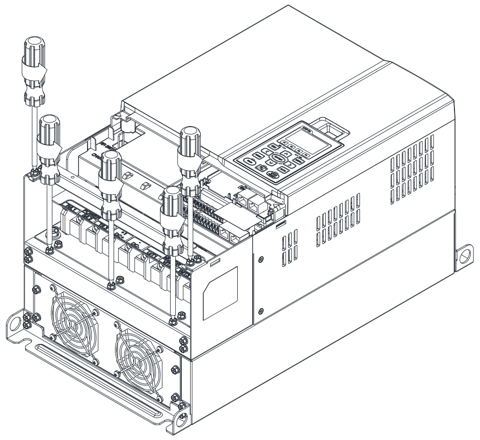
Conduit Box Installation

Frame D0

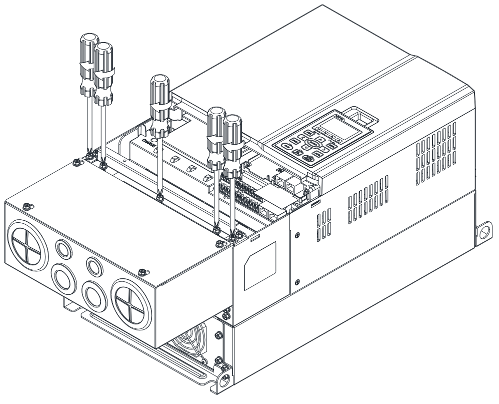
1. Loosen the cover screws and press the tabs on each side of the cover to remove the cover, as shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



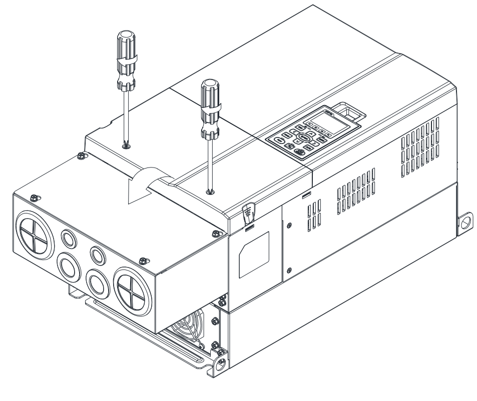
2. Remove the 5 screws shown in the following figure. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



3. Install the conduit box by fasten the 5 screws shown in the following figure. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

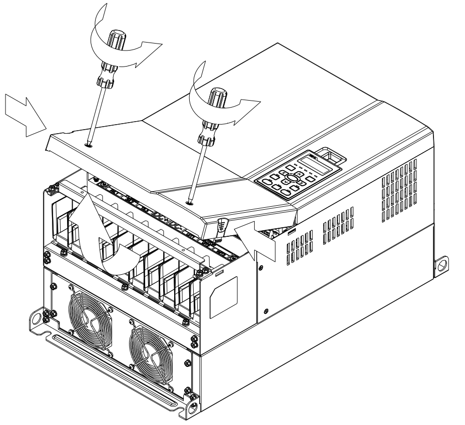


4. Fasten the 2 screws shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]

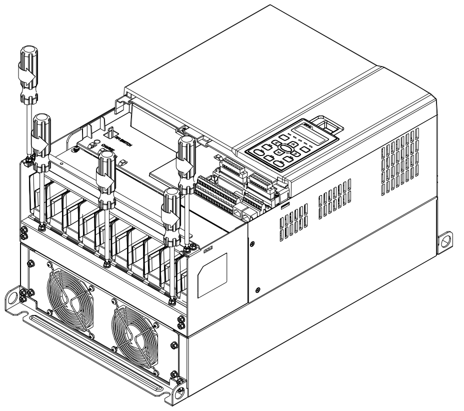


Frame D

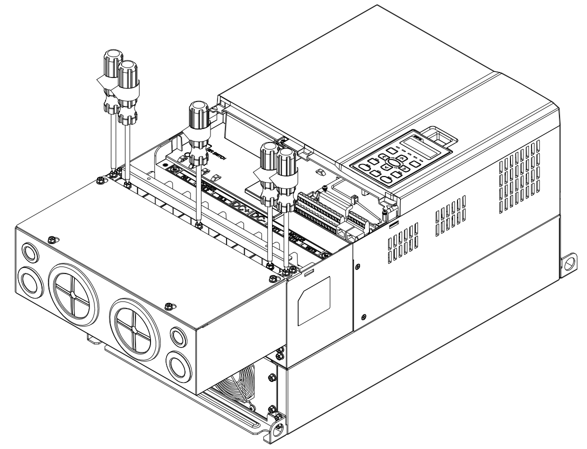
1. Loosen the cover screws and press the tabs on each side of the cover to remove the cover, as shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



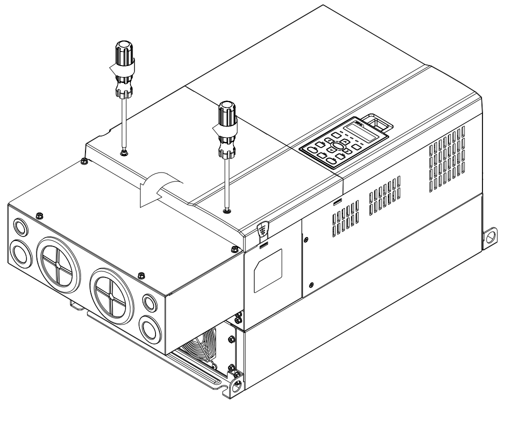
2. Remove the 5 screws shown in the following figure. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



3. Install the conduit box by fasten the 5 screws shown in the following figure. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

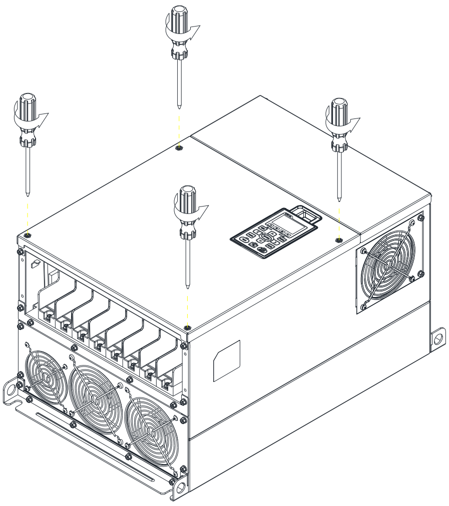


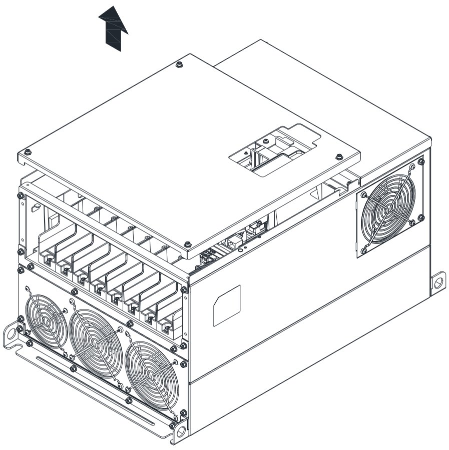
4. Fasten the 2 screws shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



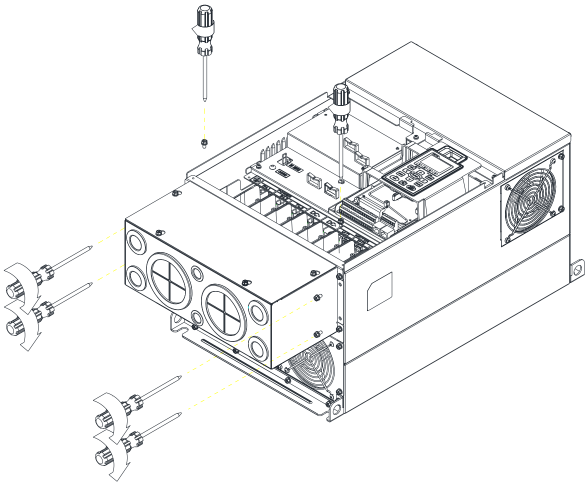
Frame E

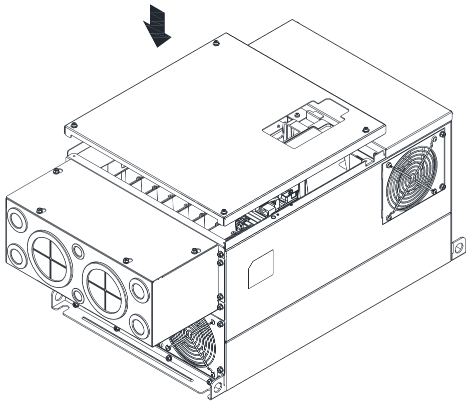
1. Loosen the 4 cover screws and lift the cover; Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



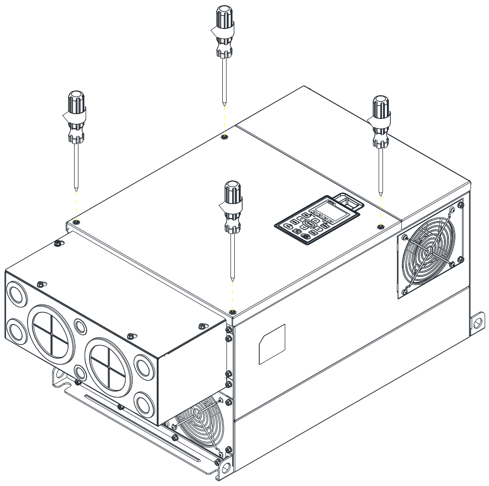


2. Fasten the 6 screws shown in the following figure and place the cover back to the original position. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



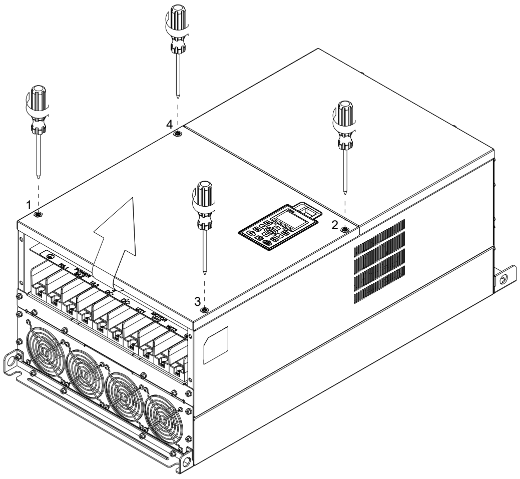


3. Fasten the 4 screws shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]

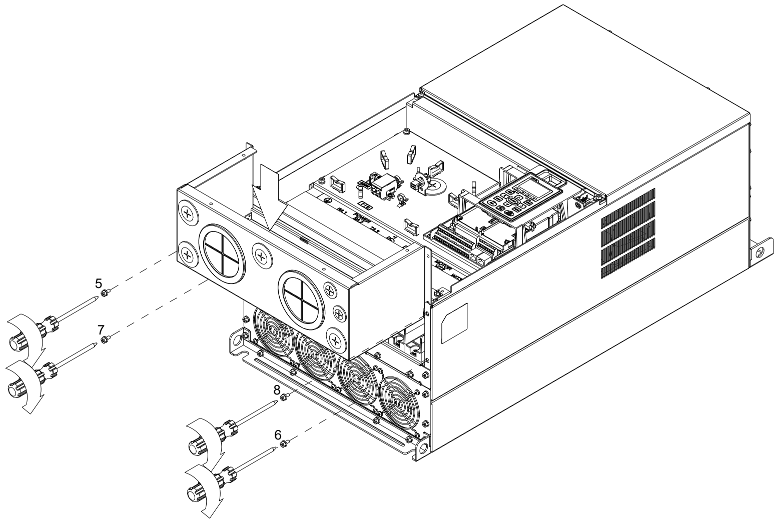


Frame F

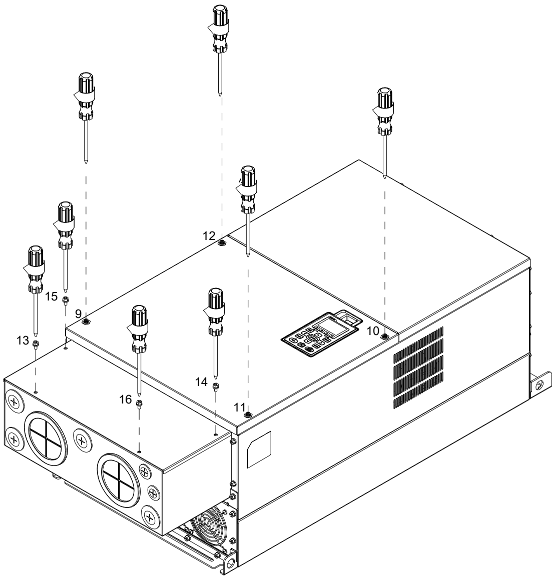
1. Loosen the cover screws and press the tabs on each side of the cover to remove the cover, as shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



2. Install the conduit box by fastens the 4 screws, as shown in the following figure.
   Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

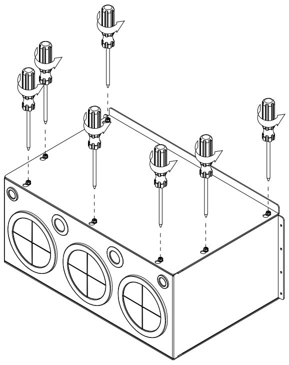


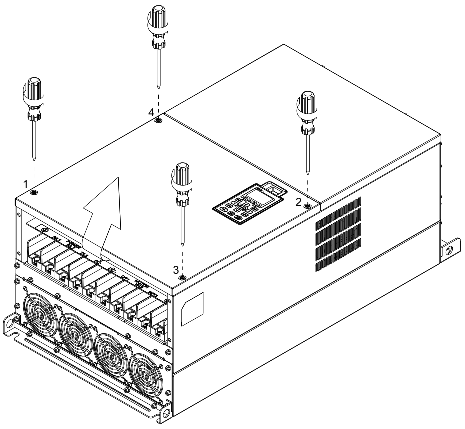
3. Install the conduit box by fasten all the screws shown in the following figure
   Screw 9–12 torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]
   Screw 13–16 torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



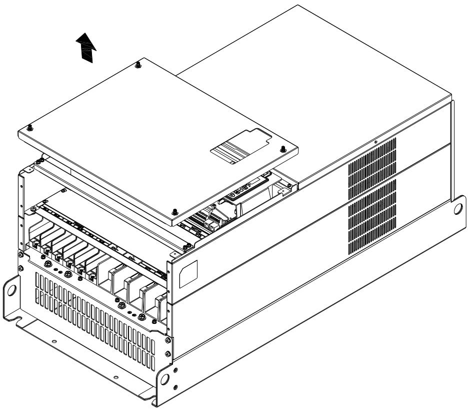
Frame G

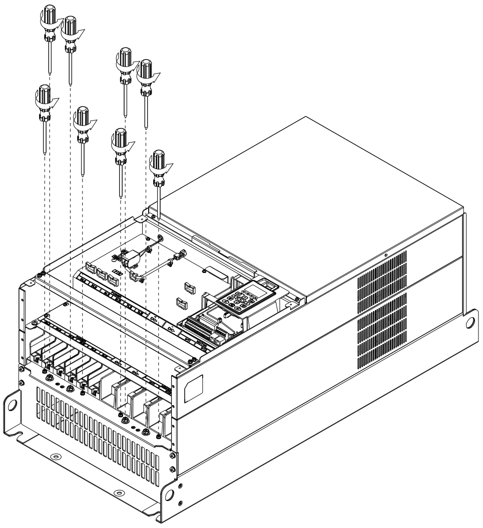
1. On the conduit box, loosen 7 of the cover screws and remove the cover.
   Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in.] / [2.4–2.5 Nm].
2. On the drive, loosen 4 of the cover screws and press the tabs on each side of the cover to remove the cover, as shown in the following figure. Screw torque: 12–15 kg-cm / [10.4–13 lb-in.] / [1.2–1.5 Nm]



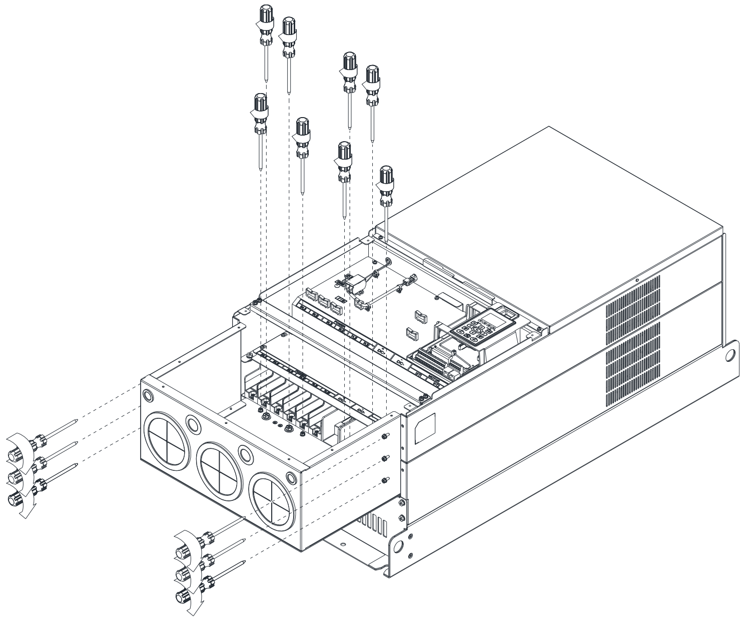


3 Remove the top cover and loosen the screws.
M5 Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in.] / [2.4–2.5 Nm]
M8 Screw torque: 100–120 kg-cm / [86.7–104.1 lb-in.] / [9.8–11.8 Nm]

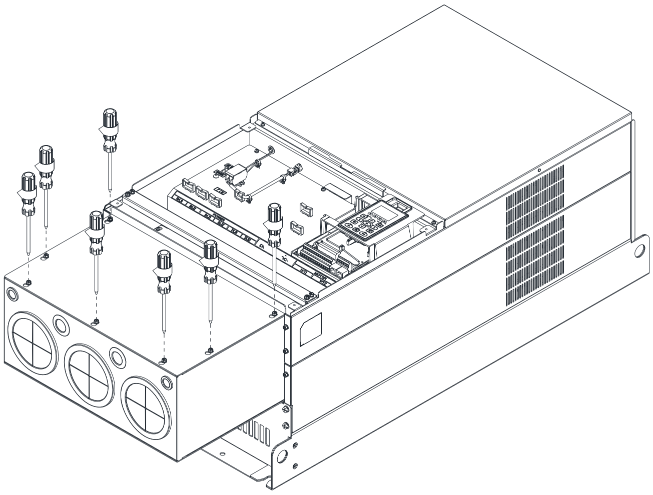




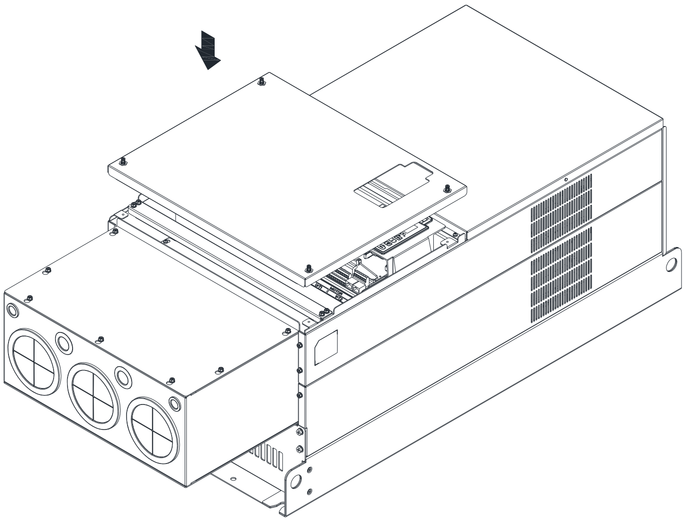
4 Install the conduit box by fastening all the screws shown in the following figure.
M5 Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in] / [2.4–2.5 Nm]
M8 Screw torque: 100–120 kg-cm / [86.7–104.1 lb-in] / [9.8–11.8 Nm]

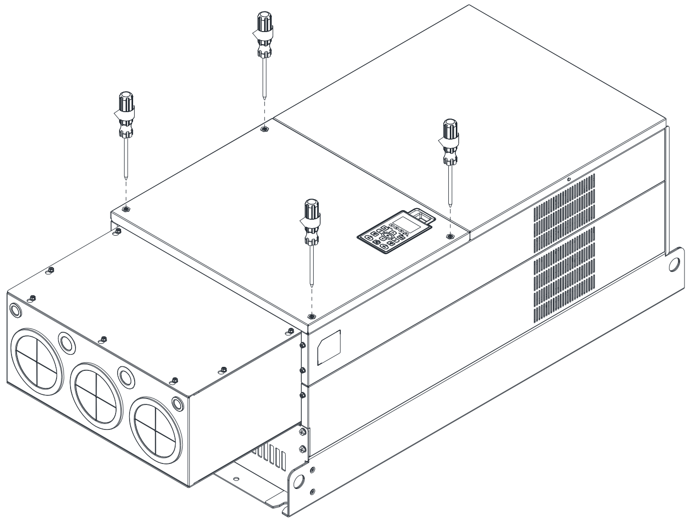


5. Fasten all the screws. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



6. Place the cover back to the top and fasten the screws (as shown in the figure).
   Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]

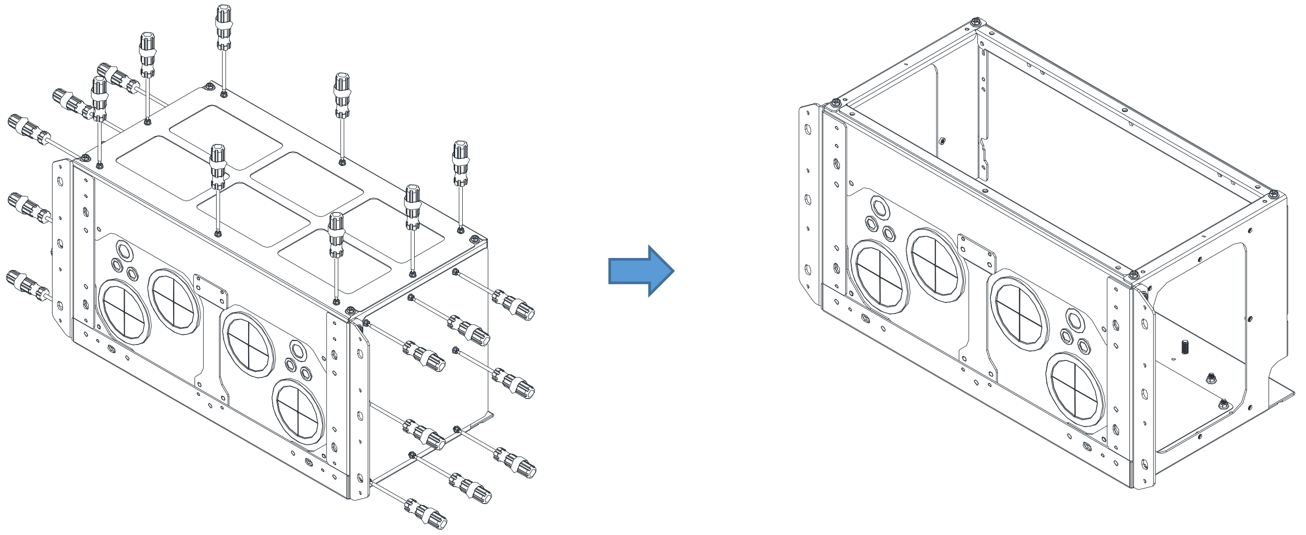




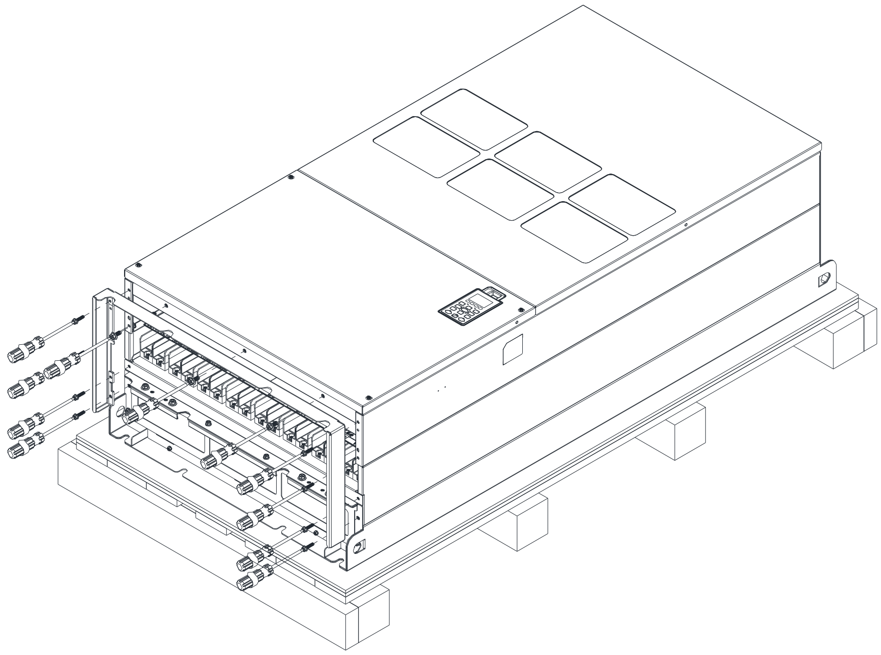
Frame H

Assembly for Frame H3 (Conduit Box Kit)

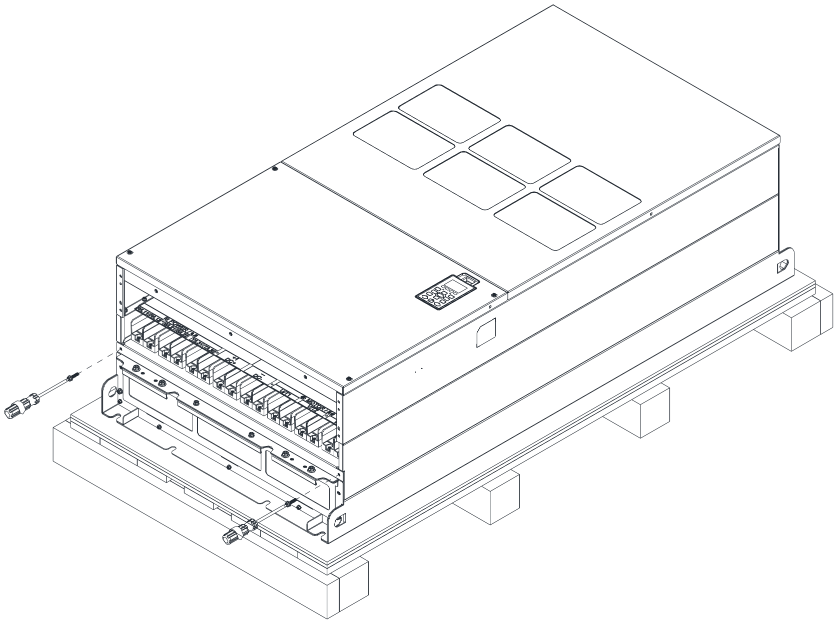
1. Loosen the screws and remove the cover of conduit box H3 as preparation.



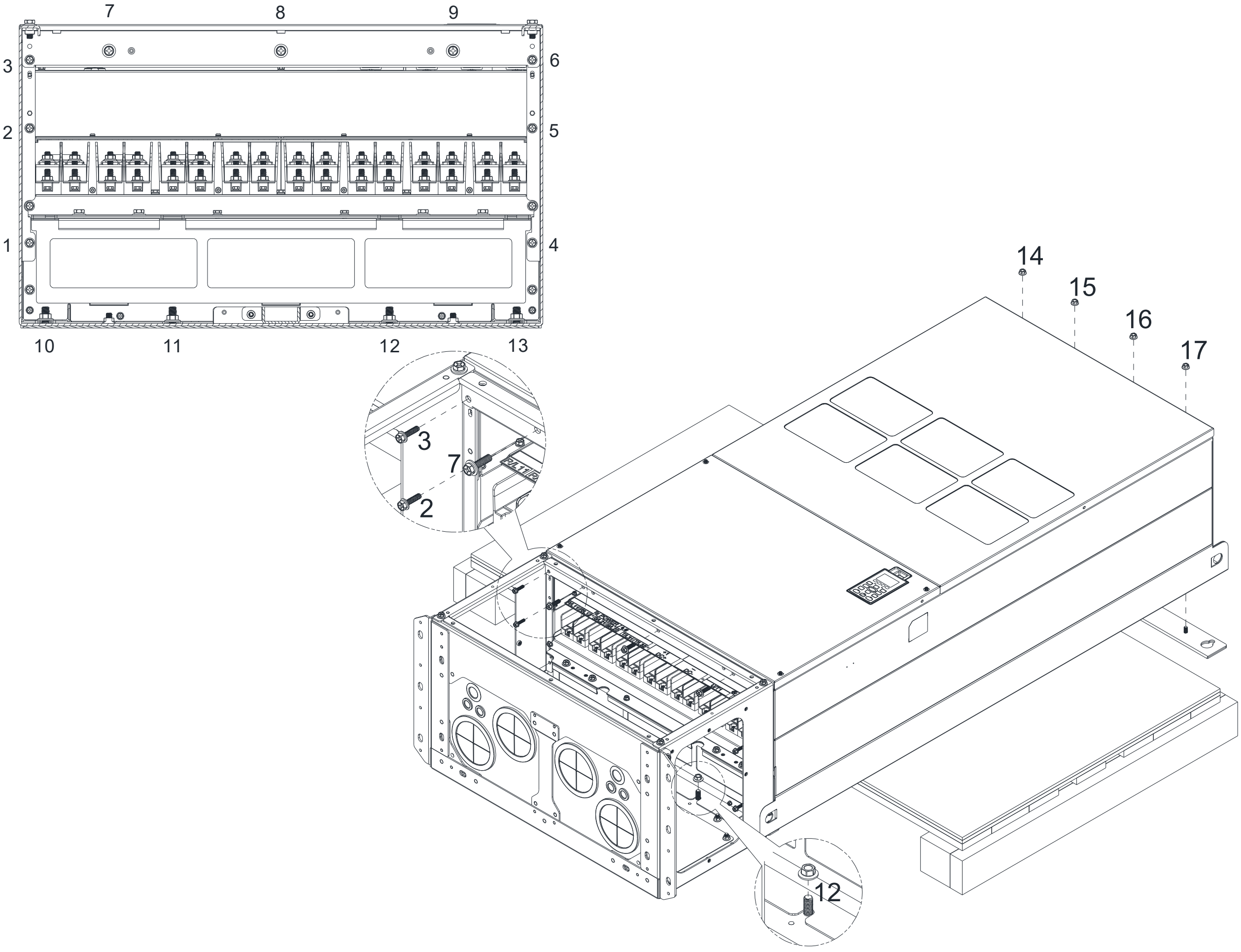
2. Loosen the screws as below figure shown.



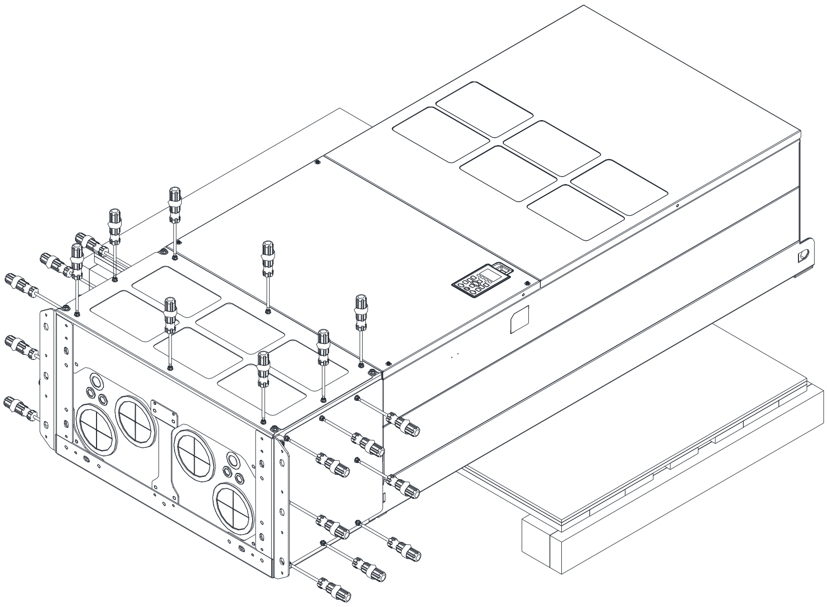
3. Fasten the M6 screws to locations shown in below figure.
   Screw torque: 35–45 kg-cm / [30.3–39 Ib-in.] / [3.4–4.4 Nm]



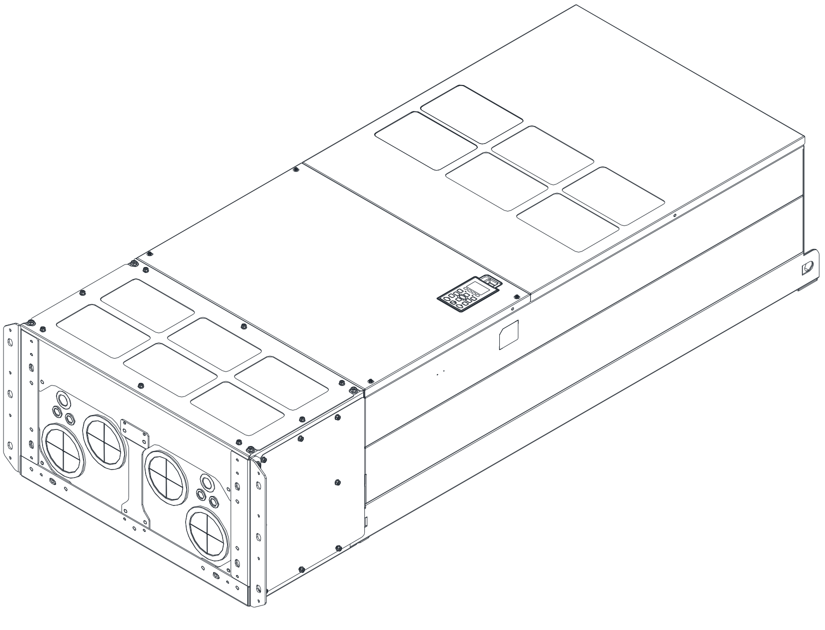
4. Install the conduit box by fasten all the screws shown in the following figure
   Screw 1–6: M6 screw torque: 55–65 kg-cm / [47.7–56.4 Ib-in] / [5.4–6.4 Nm]
   Screw 7–9: M8 screw torque: 100–110 kg-cm / [86.7–95.4 Ib-in] / [9.8–10.8 Nm]
   Screw 10–13: M10 screw torque: 250–300 kg-cm / [216.9–260.3 Ib-in] / [24.5–29.4 Nm]
   Screw 14–17: M8 screw torque: 100–110 kg-cm / [86.7–95.4 Ib-in] / [9.8–10.8 Nm]



5. Fasten the 3 covers and screws, which are loosen from step1, to the original location.
   Screw torque: 35–45 kg-cm / [30.3–39 Ib-in.] / [3.4–4.4 Nm]

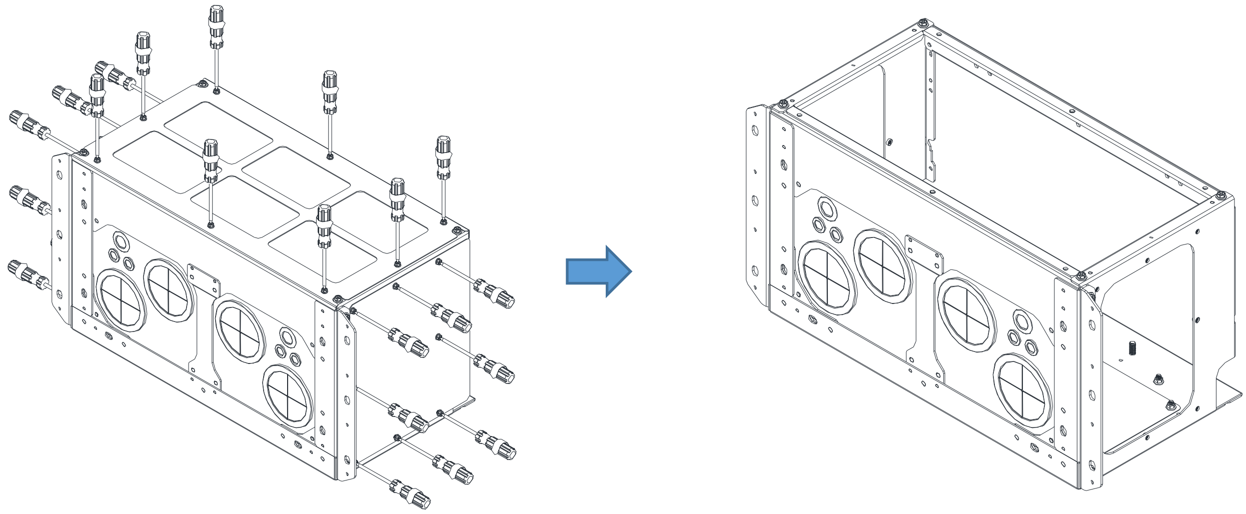


6. Installation complete.

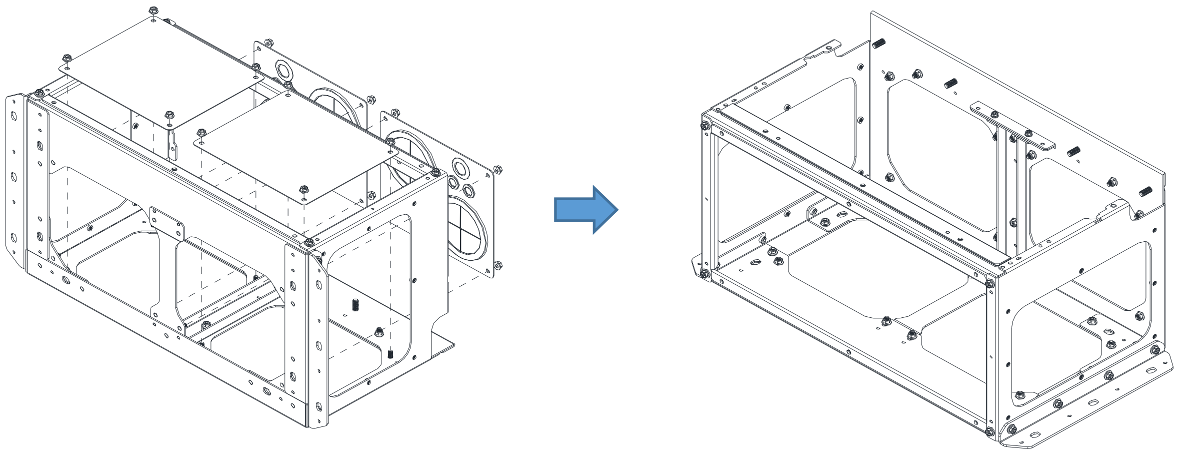


Assembly for Frame H2 (Straight Stand)

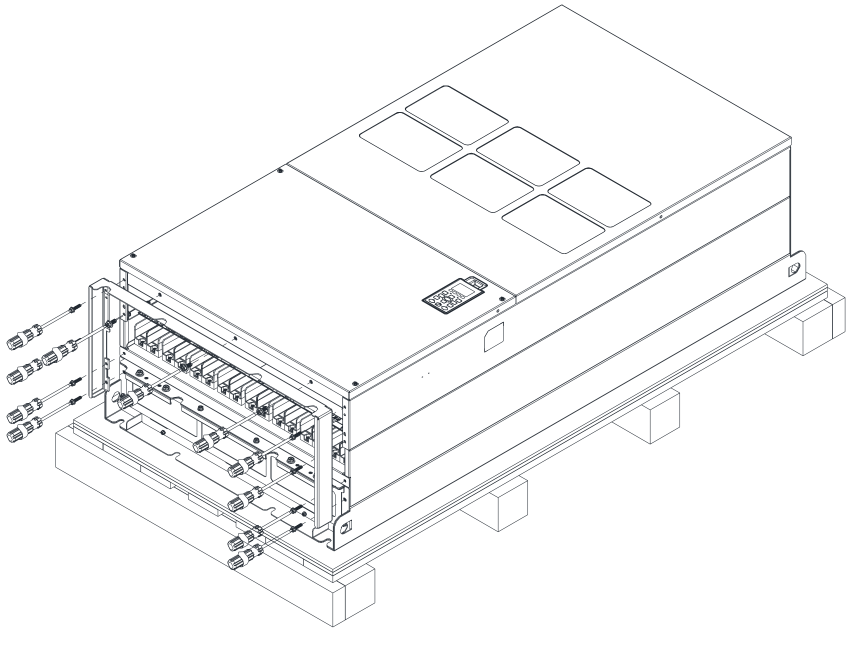
1. Loosen the 3 screws and remove the cover of conduit box.



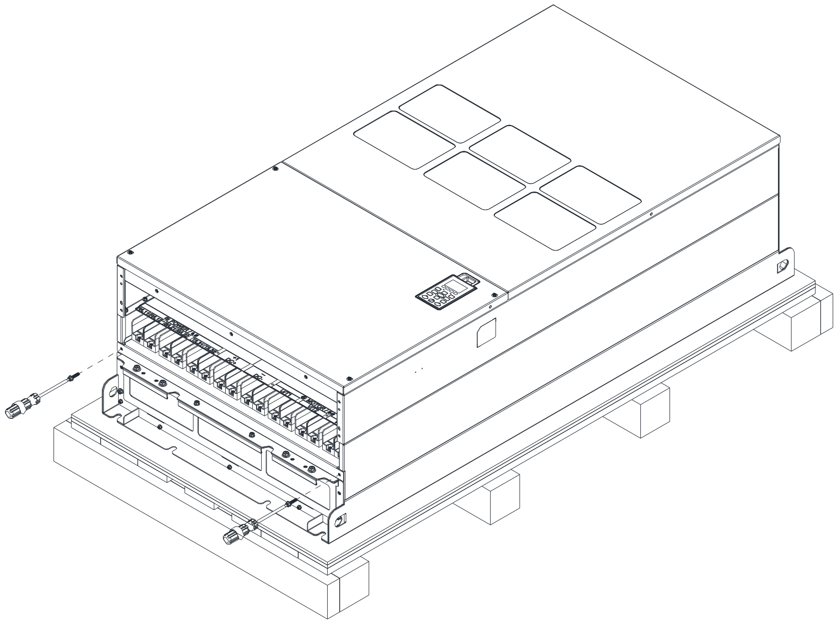
2. Remove the 4 covers of conduit box, and fasten the loosen screws back to the original location.
   Screw torque: 100–110 kg-cm / [86.7–95.4 Ib-in] / [9.8–10.8 Nm]



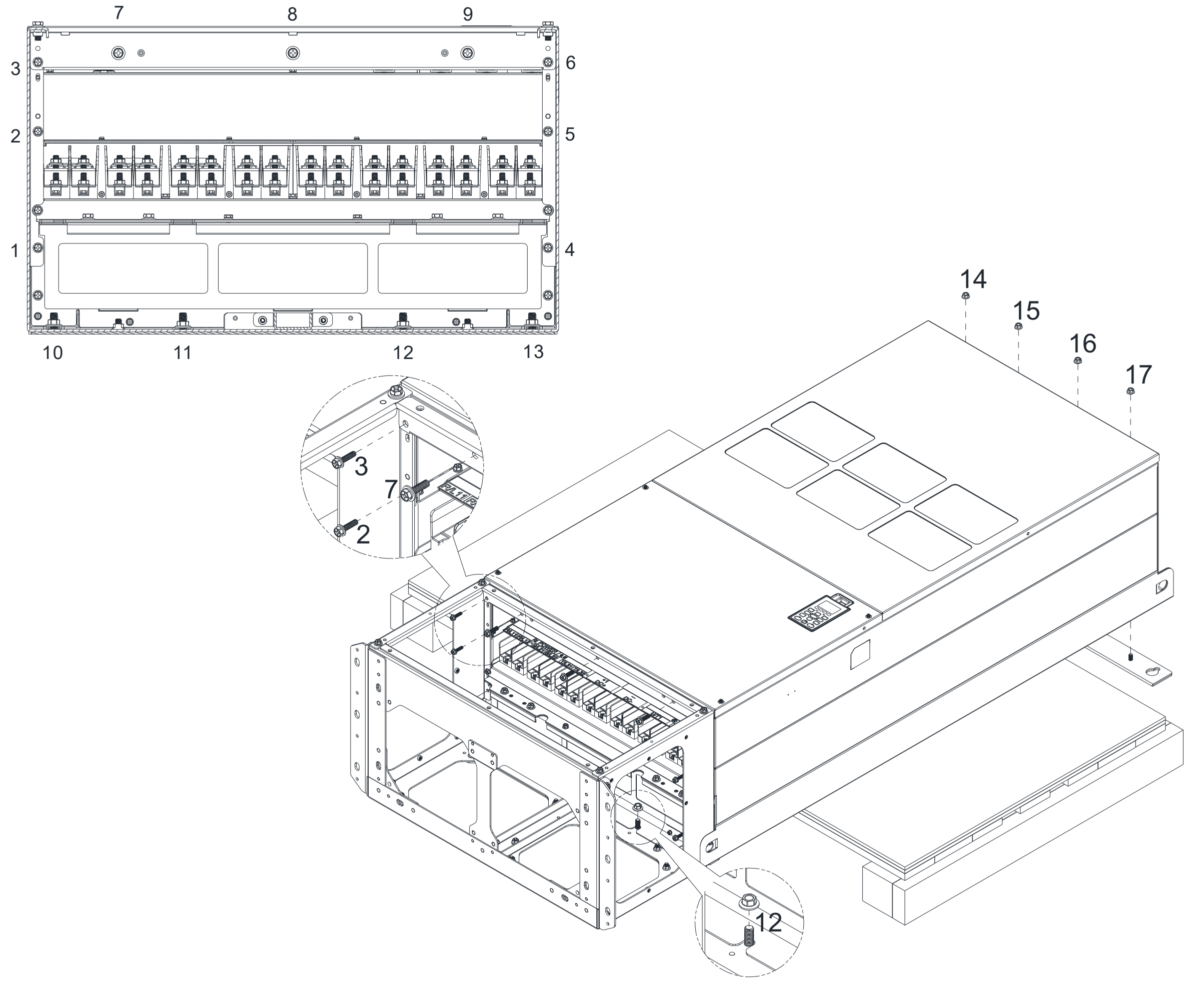
3. Remove the parts and screws as below figure shown.



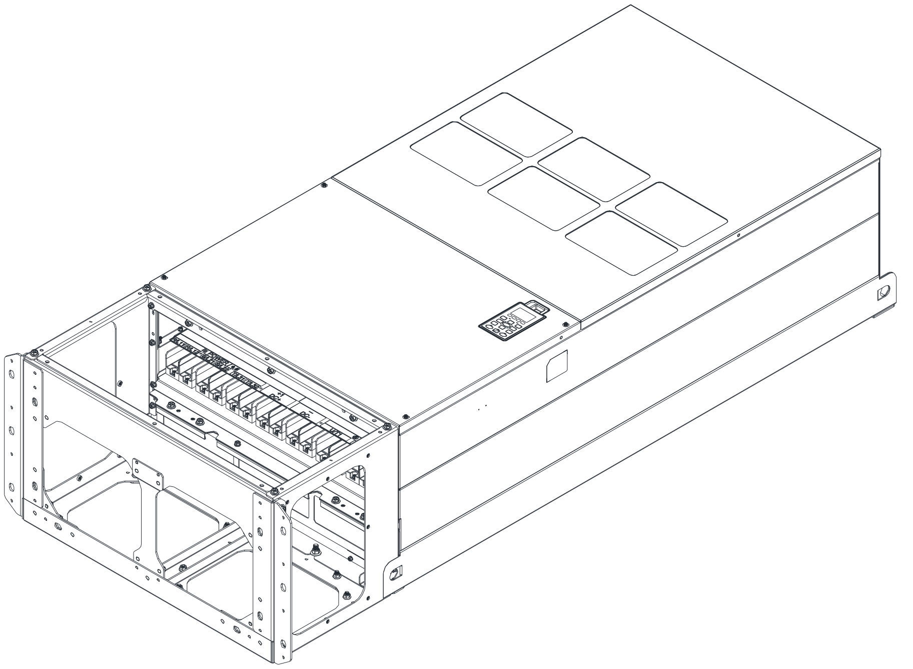
4. Fasten the M6 screws to locations shown in below figure.
   Screw torque: 35–45 kg-cm / [30.3–39 Ib-in.] / [3.4–4.4 Nm]



5. Install conduit box and accessories by fasten all the screws shown in the following figure.
   Screws 1–6: M6 screw torque: 55–65 kg-cm / [47.7–56.4 Ib-in] / [5.4–6.4 Nm]
   Screws 7–9: M8 screw torque: 100–110 kg-cm / [86.7–95.4 Ib-in] / [9.8–10.8 Nm]
   Screws 10–13: M10 screw torque: 250–300 kg-cm / [216.9–260.3 Ib-in] / [24.5–29.4 Nm]
   Screws 14–17: M8 screw torque: 100–110 kg-cm / [86.7–95.4 Ib-in] / [9.8–10.8 Nm]



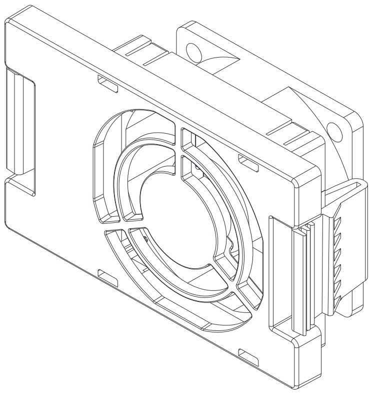
6. Installation complete.

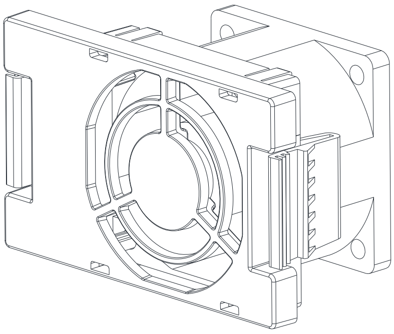


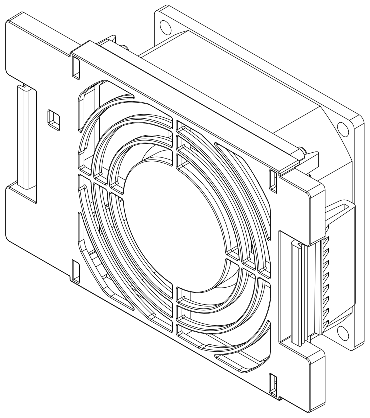
7-9 Fan Kit

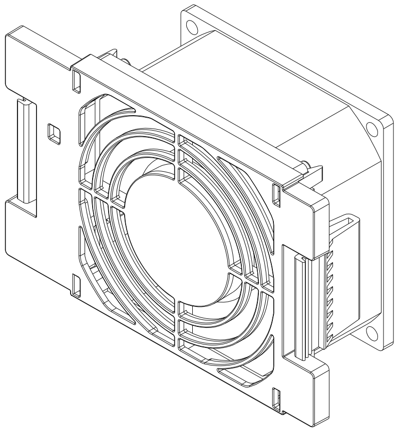
- Appearance of the fan kit

NOTE: The fan does not support hot swap function. For replacement, turn the power off before replacing the fan.

Frame A
Applicable Model
VFD022CP23A-21; VFD037CP23A-21;
VFD055CP23A-21; VFD022CP43B-21;
VFD022CP4EB-21; VFD037CP43B-21;
VFD037CP4EB-21; VFD040CP43A-21;
VFD040CP4EA-21; VFD055CP43B-21;
VFD055CP4EB-21; VFD015CP53A-21;
VFD022CP53A-21; VFD037CP53A-21
	Heat sink Fan Model『MKC-AFKM』
	

Frame A Applicable Model VFD075CP43B-21; VFD075CP4EB-21	Heat sink Fan Model『MKCB-AFKM2』 

Frame B
Applicable Model
VFD075CP23A-21; VFD110CP43B-21;
VFD110CP4EB-21; VFD055CP53A-21;
VFD075CP53A-21; VFD110CP53A-21;
VFD150CP53A-21
	Heat sink Fan Model『MKC-BFKM1』
	

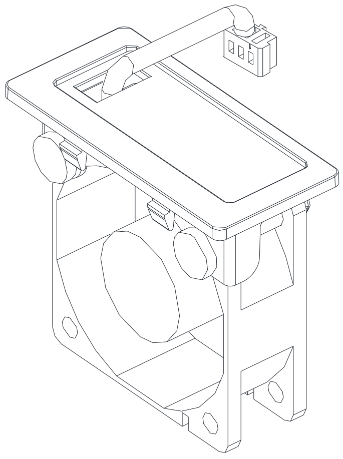
Frame B Applicable Model MKC-BFKM2: VFD110CP23A-21; VFD150CP43B-21; VFD150CP4EB-21; VFD185CP43B-21; VFD185CP4EB-21 MKC-BFKM3: VFD150CP23A-21 (The MKC-BFKM2 and MKC-BFKM 3 have the same shape)	Heat sink Fan Model 『MKC-BFKM2』『MKC-BFKM3』 

Frame B

Capacitor Fan Model 『MKC-BFKB』

Applicable Model

VFD075CP23A-21; VFD110CP23A-21;
VFD110CP43B-21; VFD110CP4EB-21;
VFD150CP23A-21; VFD150CP43B-21;
VFD150CP4EB-21; VFD185CP43B-21;
VFD185CP4EB-21; VFD055CP53A-21;
VFD075CP53A-21; VFD110CP53A-21;
VFD150CP53A-21

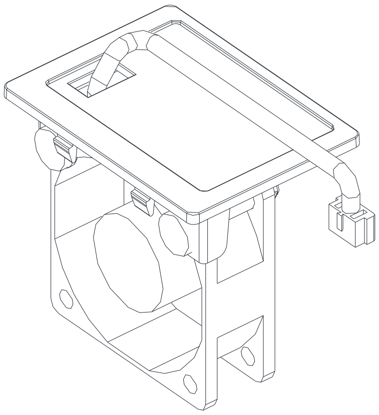


Frame C

Capacitor Fan Model 『MKC-CFKB1』

Applicable Model

VFD185CP23A-21; VFD220CP23A-21;
VFD300CP23A-21; VFD185CP63A-21;
VFD220CP63A-21; VFD300CP63A-21;
VFD370CP63A-21

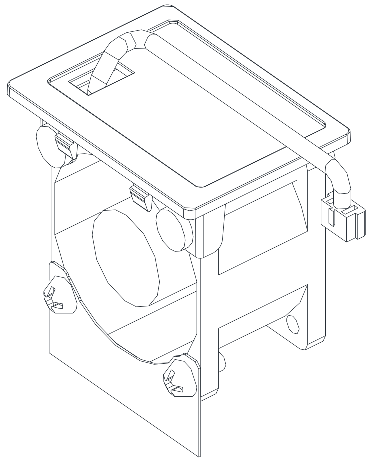


Frame C

Capacitor Fan Model 『MKC-CFKB2』

Applicable Model

VFD220CP43A-21; VFD220CP4EA-21;
VFD300CP43B-21; VFD300CP4EB-21;
VFD370CP43B-21; VFD370CP4EB-21

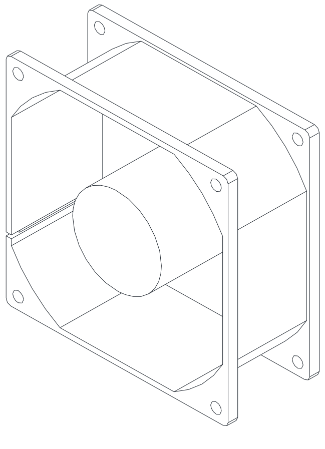


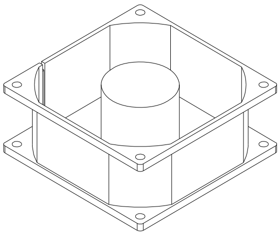
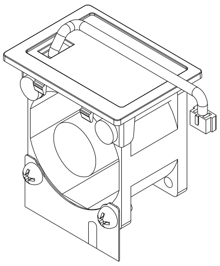
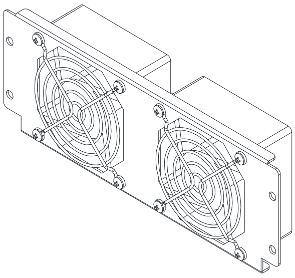
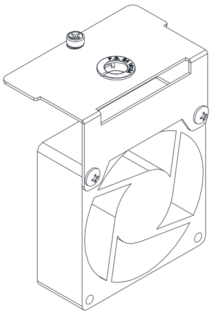
Frame C

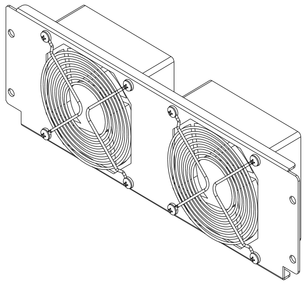
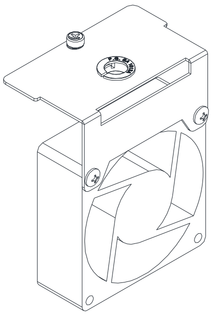
Heat sink Fan 『MKC-CFKM』

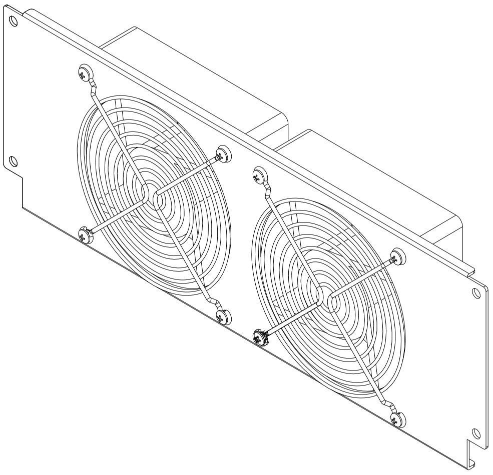
Following Models use one set of MKC-CFKM:
VFD220CP43A-21; VFD220CP4EA-21;
VFD300CP43B-21; VFD300CP4EB-21;
VFD370CP43B-21

Following Models use two sets of MKC-CFKM:
VFD185CP23A-21; VFD220CP23A-21;
VFD300CP23A-21; VFD370CP4EB-21



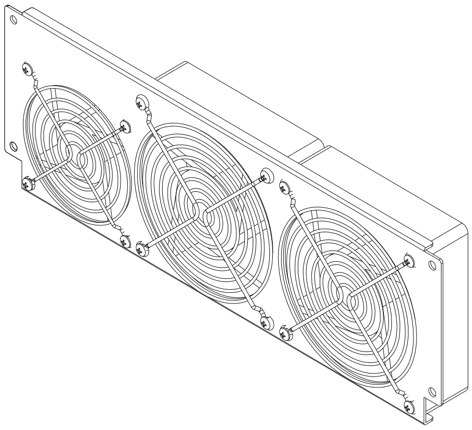
Frame C Applicable Model VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21	Heat sink Fan Model 『MKC-CFKM1』 	Capacitor Fan Model 『MKC-CFKB3』 
Frame D0 Applicable Model VFD450CP43S-00; VFD450CP43S-21; VFD550CP43S-00; VFD550CP43S-21	Heat sink Fan Model 『MKC-D0FKM』 	Capacitor Fan Model 『MKC-DFKB』 

Frame D
Applicable Model
VFD370CP23A-00; VFD370CP23A-21;
VFD450CP23A-00; VFD450CP23A-21;
VFD750CP43B-00; VFD750CP43B-21;
VFD900CP43A-00; VFD900CP43A-21;
VFD450CP63A-00; VFD450CP63A-21;
VFD550CP63A-00; VFD550CP63A-21
	Heat sink Fan Model
	『MKC-DFKM』
	
		Capacitor Fan Model
		『MKC-DFKB』
		

Frame E Applicable Model VFD550CP23A-00; VFD550CP23A-21; VFD750CP23A-00; VFD750CP23A-21	Heat sink Fan Model 『MKC-EFKM1』 	

Frame E

Heat sink Fan Model『MKC-EFKM2』

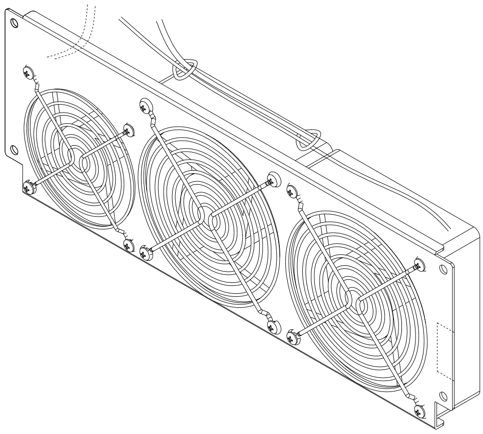


Applicable Model

VFD900CP23A-00; VFD900CP23A-21;
VFD1100CP43A-00; VFD1100CP43A-21;
VFD1320CP43B-00; VFD1320CP43B-21

Frame E

Fan Model 『MKC-EFKM3』

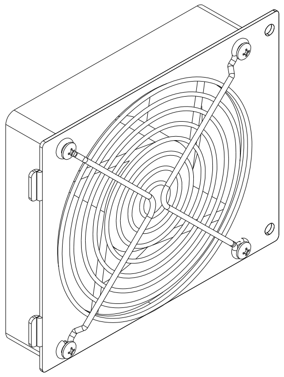


Applicable Model

VFD750CP63A-00; VFD750CP63A-21;
VFD900CP63A-00; VFD900CP63A-21;
VFD1100CP63A-00; VFD1100CP63A-21;
VFD1320CP63A-00; VFD1320CP63A-21

Frame E

Capacitor Fan Model 『MKC-EFKB』

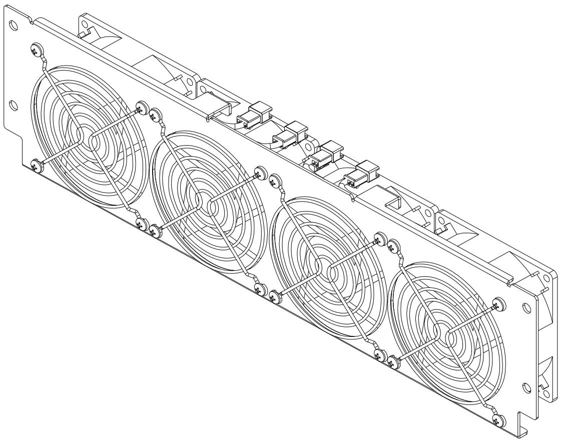


Applicable Model

VFD550CP23A-00; VFD550CP23A-21;
VFD750CP23A-00; VFD750CP23A-21;
VFD900CP23A-00; VFD900CP23A-21;
VFD1100CP43A-00; VFD1100CP43A-21;
VFD1320CP43B-00; VFD1320CP43B-21;
VFD900CP63A-00; VFD900CP63A-21;
VFD1100CP63A-00; VFD1100CP63A-21;
VFD1320CP63A-00; VFD1320CP63A-21

Frame F

Heat sink Fan Model 『MKC-FFKM』



Applicable Model

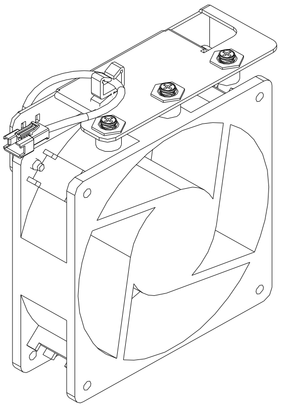
VFD1600CP43A-00; VFD1600CP43A-21;
VFD1850CP43B-00; VFD1850CP43B-21;
VFD1600CP63A-00; VFD1600CP63A-21;
VFD2000CP63A-00; VFD2000CP63A-21

Frame F

Capacitor Fan Model 『MKC-FFKB』

Applicable Model

VFD1600CP43A-00; VFD1600CP43A-21;
VFD1850CP43B-00; VFD1850CP43B-21;
VFD1600CP63A-00; VFD1600CP63A-21;
VFD2000CP63A-00; VFD2000CP63A-21

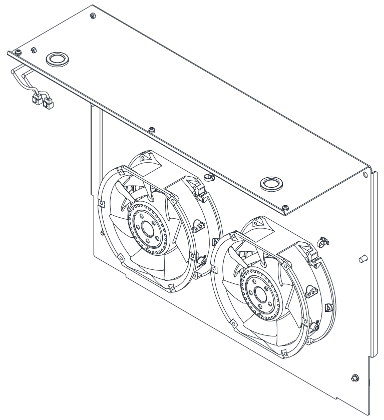


Frame G

Heat sink Fan Model 『MKC-GFKM』

Applicable Model

VFD2000CP43A-00; VFD2000CP43A-21;
VFD2200CP43A-00; VFD2200CP43A-21;
VFD2500CP43A-00; VFD2500CP43A-21;
VFD2800CP43A-00; VFD2800CP43A-21;
VFD2500CP63A-00; VFD2500CP63A-21;
VFD3150CP63A-00; VFD3150CP63A-21

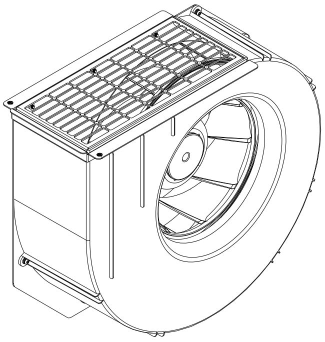


Frame H

Heat sink Fan Model 『MKC-HFKM』

Applicable Model

Following models use two sets of MKC-HFKM:
VFD3150CP43A-00; VFD3150CP43C-00;
VFD3150CP43C-21; VFD3550CP43A-00;
VFD3550CP43C-00; VFD3550CP43C-21;
VFD4000CP43A-00; VFD4000CP43C-00;
VFD4000CP43C-21

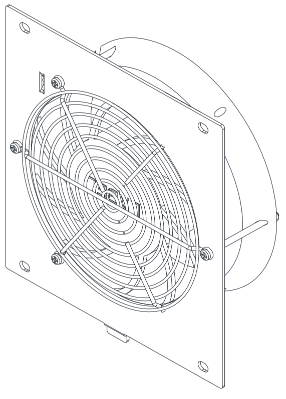


Frame H

Heat sink Fan Model 『MKCHS-HFKM』

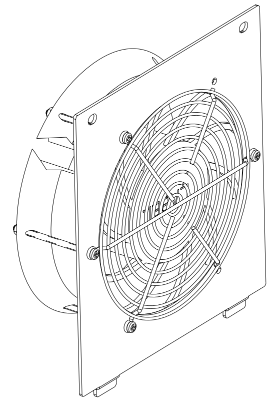
Applicable Model

Following models use three sets of MKCHS-HFKM:
VFD5000CP43A-00; VFD5000CP43C-00;
VFD5000CP43C-21; VFD5600CP43A-00;
VFD5600CP43C-21; VFD6300CP43A-00;
VFD6300CP43C-21



Frame H

Heat sink Fan Model 『MKC-HFKM1』



Applicable Model

Following models use two sets of MKC-HFKM1:
VFD4000CP63A-00; VFD4000CP63A-21

Following models use three sets of MKC-HFKM1:
VFD4500CP63A-00; VFD4500CP63A-21;
VFD5600CP63A-00; VFD5600CP63A-21;
VFD6300CP63A-00; VFD6300CP63A-21

■ Fan Removal

Frame A

Model『MKC-AFKM』: Heat Sink Fan

Applicable model

VFD022CP23A-21; VFD037CP23A-21; VFD055CP23A-21; VFD022CP43B-21; VFD022CP4EB-21; VFD037CP43B-21; VFD037CP4EB-21; VFD040CP43A-21; VFD040CP4EA-21; VFD055CP43B-21; VFD055CP4EB-21; VFD015CP53A-21; VFD022CP53A-21; VFD037CP53A-21

Model『MKCB-AFKM2』: Heat Sink Fan

Applicable model

VFD075CP43B-21; VFD075CP4EB-21

1. Refer to Figure 1, press the tabs on both side of the fan to successfully remove the fan.
2. Disconnect the power terminal before removing the fan. (As shown below.)

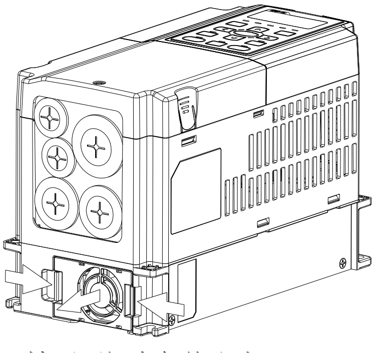


Figure 1

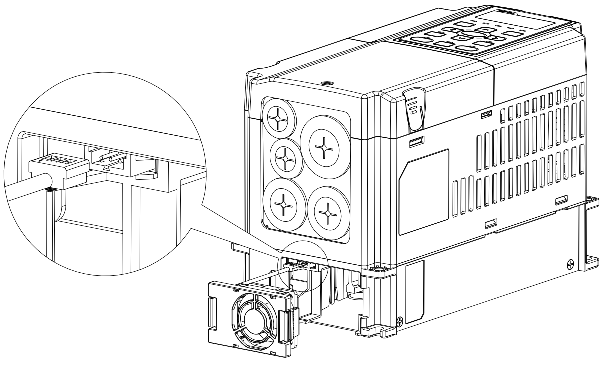


Figure 2

Frame B

Model『MKC-BFKM1』Heat Sink Fan

Applicable model

VFD075CP23A-21; VFD110CP43B-21; VFD110CP4EB-21; VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21; VFD150CP53A-21

Model『MKC-BFKM2』Heat Sink Fan

Applicable model

VFD110CP23A-21; VFD150CP43B-21; VFD150CP4EB-21; VFD185CP43B-21; VFD185CP4EB-21

Model『MKC-BFKM3』Heat Sink Fan

Applicable model

VFD150CP23A-21

1. Refer to Figure 1, press the tabs on both side of the fan to successfully remove the fan.
2. Disconnect the power terminal before removing the fan. (As shown below.)

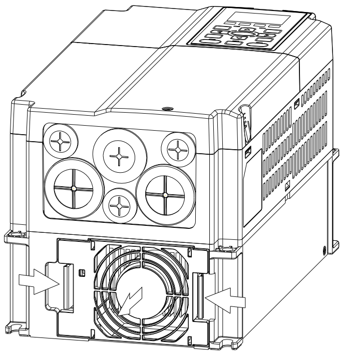


Figure 1

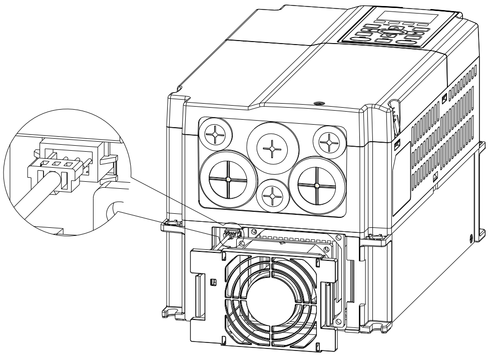


Figure 2

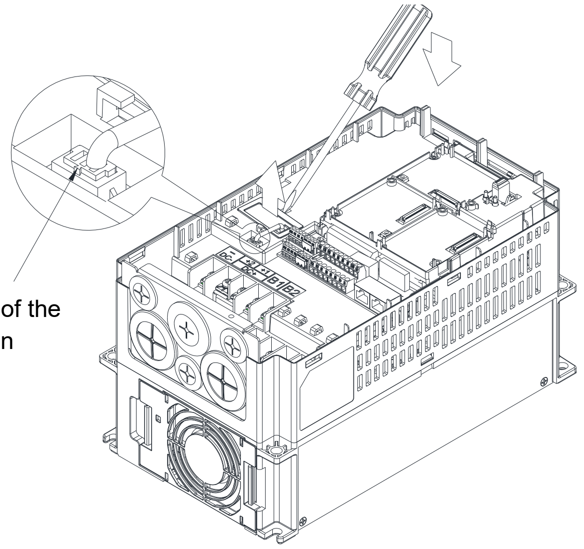
Frame B

Model『MKC-BFKB』Capacitor Fan

Applicable model

VFD075CP23A-21; VFD110CP23A-21; VFD110CP43B-21; VFD110CP4EB-21; VFD150CP23A-21; VFD150CP43B-21; VFD150CP4EB-21; VFD185CP43B-21; VFD185CP4EB-21; VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21; VFD150CP53A-21

Disconnect fan power and pull out the fan by using flathead screwdriver. (As shown in the larger picture)



Disconnect fan power and pull out the fan by flathead screwdriver

Pay attention to direction of the latch during the installation

Frame C

Model『MKC-CFKM』Heat Sink Fan

Applicable model

Single fan kit applicable models (only fan kit 1 is required to be installed):

VFD220CP43A-21; VFD220CP4EA-21; VFD300CP43B-21; VFD300CP4EB-21; VFD370CP43B-21;

Dual fan kit applicable models (both fan kit 1 and 2 are required to be installed):

VFD185CP23A-21; VFD220CP23A-21; VFD300CP23A-21; VFD370CP4EB-21

Model『MKC-CFKM1』Heat Sink Fan

Applicable model

VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21

1. (As shown Figure 1) Before removing the fan, remove the cover by using a slotted screwdriver.

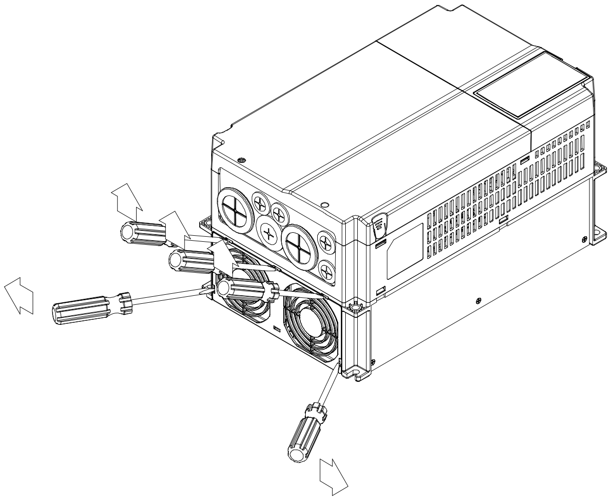


Figure 1

2. (As shown in Figure 2), remove the power connector, loosen the screw and remove the fan kit. When installing the fan kit, have the label on the fan kit facing inside of the motor drive.
   Screw's torque: 10–12 kg-cm / [8.7–10.4 lb-in.] / [1.0–1.2 Nm]

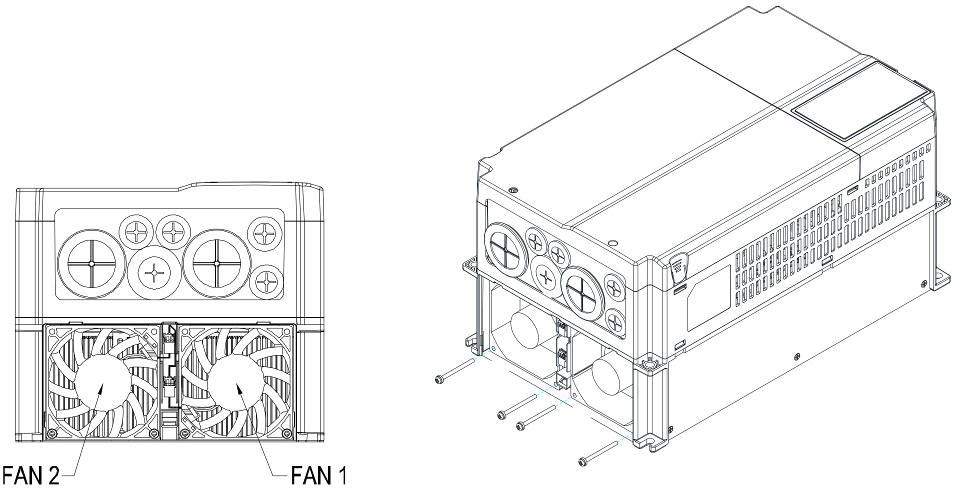


Figure 2

Frame C

Model『MKC-CFKB1』Capacitor Fan

Applicable model
VFD185CP23A-21; VFD220CP23A-21; VFD300CP23A-21; VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21

Model『MKC-CFKB2』Capacitor Fan

Applicable model
VFD220CP43A-21; VFD220CP4EA-21; VFD300CP43B-21; VFD300CP4EB-21; VFD370CP43B-21; VFD370CP4EB-21

Model『MKC-CFKB3』Capacitor Fan

Applicable model
VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21
Disconnect fan power and pull out the fan by using flathead screwdriver. (As shown in the larger picture)

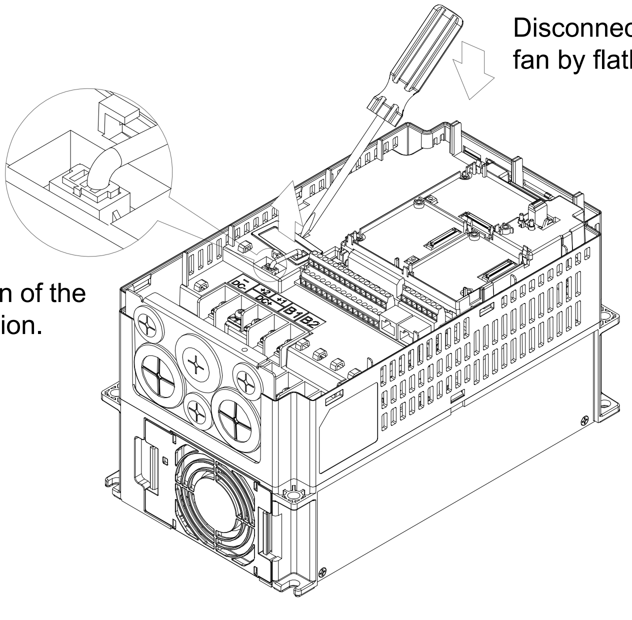

Disconnect fan power and pull out the fan by flathead screwdriver
Pay attention to direction of the latch during the installation.

Figure 1

Frame D0

Model『MKC-DFKB』Capacitor Fan

Applicable model

VFD450CP43S-00; VFD450CP43S-21; VFD550CP43S-00; VFD550CP43S-21

1. Loosen screw 1 and screw 2, press the tabs on the right and left to remove the cover, follow the direction the arrows indicate. Press on top of digital keypad to properly remove it. Screw 1, 2 Torque: 12–15 kg-cm / [10.4–13 lb-in.] / [1.2–1.5 Nm]

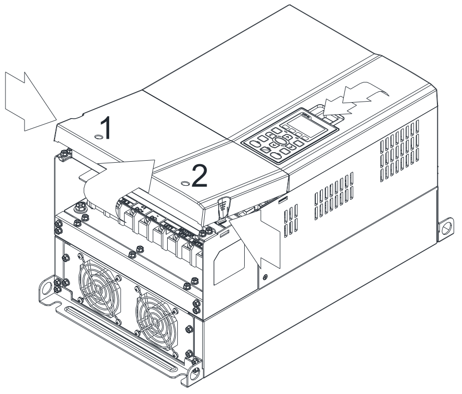


Figure 1

2. (Figure 2) Loosen screw 3, press the tabs on the right and the left to remove the cover. Screw 3 Torque: 6–8 kg-cm / [5.2–6.9 lb-in.] / [0.6–0.8 Nm]

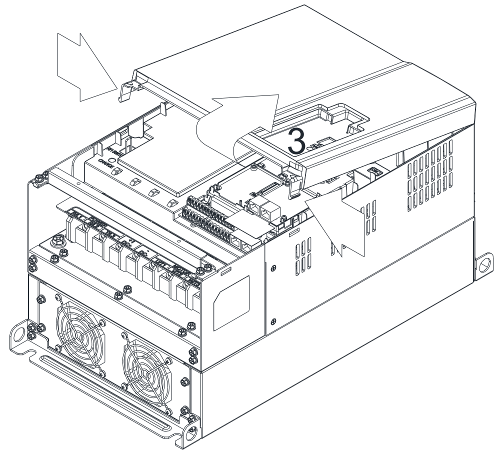


Figure 2

3. Loosen screw 4 (figure 3) and disconnect fan power and pull out the fan. (As shown in the enlarged picture 3) Screw 4 Torque: 10–12 kg-cm / [8.7–10.4 lb-in.] / [1.0–1.2 Nm]

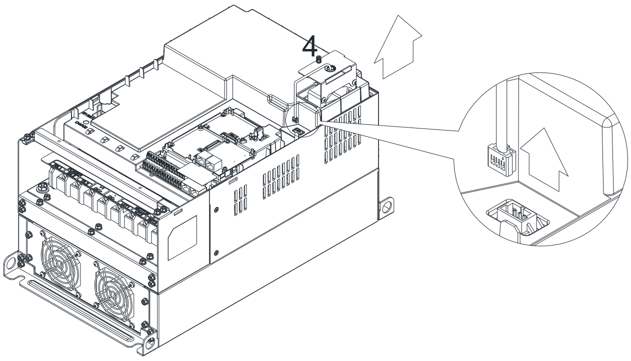


Figure 3

Frame D0

Model『MKC-D0FKM』Heat Sink Fan

Applicable model

VFD450CP43S-00; VFD450CP43S-21; VFD550CP43S-00; VFD550CP43S-21

1. Loosen the screw and remove the fan kit. Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in. / [2.4–2.5 Nm]
2. (As shown Figure 1) Before removing the fan, remove the cover by using a slotted screwdriver.

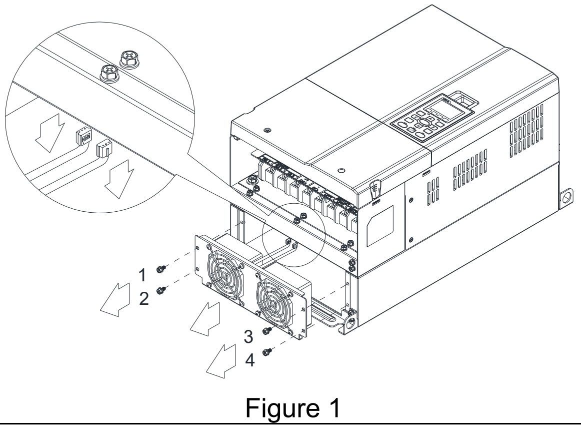


Figure 1

Frame D

Model『MKC-DFKB』Capacitor Fan

Applicable model

VFD370CP23A-00; VFD370CP23A-21; VFD450CP23A-00; VFD450CP23A-21; VFD750CP43B-00; VFD750CP43B-21; VFD900CP43A-00; VFD900CP43A-21; VFD450CP63A-00; VFD450CP63A-21; VFD550CP63A-00; VFD550CP63A-21

1. Loosen screw 1 and screw 2, press the tab on the right and the left to remove the cover, follow the direction the arrows indicate. Press on top of digital keypad to properly remove it. Screw 1, 2 Torque: 12–15 kg-cm / [10.4–13 lb-in.] / [1.2–1.5 Nm]
2. (Figure 2) Loosen screw 3, press the tab on the right and the left to remove the cover. Screw 3, 4 Torque: 6–8 kg-cm / [5.2–6.9 lb-in.] / [0.6–0.8 Nm]

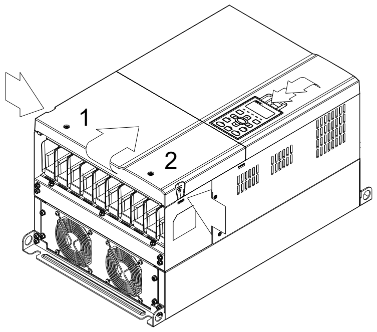


Figure 1

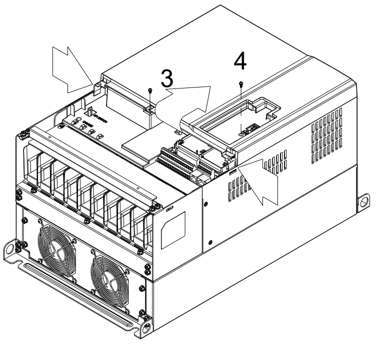


Figure 2

3. Loosen screw 5 (figure 3) and disconnect fan power and pull out the fan. (As shown in the enlarged picture 3) Screw 5 Torque: 10–12 kg-cm / [8.6–10.4 lb-in.] / [1.0–1.2 Nm]

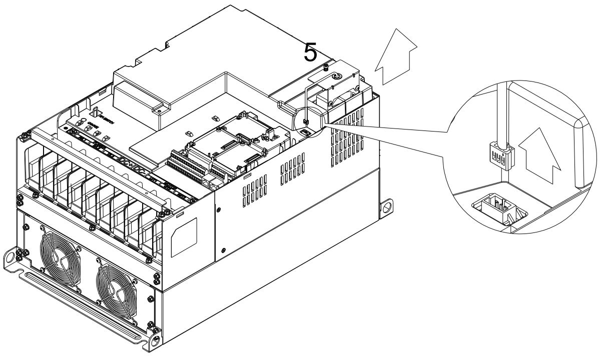


Figure 3

Frame D

Model『MKC-DFKM』Heat Sink Fan

Applicable model

VFD370CP23A-00; VFD370CP23A-21; VFD450CP23A-00; VFD450CP23A-21; VFD750CP43B-00; VFD750CP43B-21; VFD900CP43A-00; VFD900CP43A-21; VFD450CP63A-00; VFD450CP63A-21; VFD550CP63A-00; VFD550CP63A-21

1. Loosen the screw and remove the fan kit. Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in.] / [2.4–2.5 Nm]
2. (As shown Figure 1) Before removing the fan, remove the cover by using a slotted screwdriver.

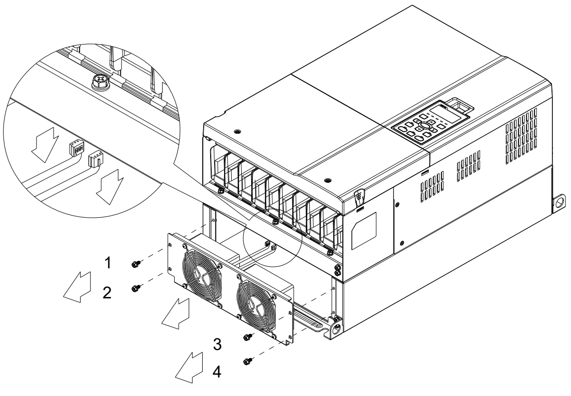


Figure 1

Frame E

Applicable models for MKC-EFKM1:
VFD550CP23A-00; VFD550CP23A-21; VFD750CP23-00; VFD750CP23A-21

Applicable models for MKC-EFKM2:
VFD900CP23A-00; VFD900CP23A-21; VFD1100CP43A-00; VFD1100CP43A-21; VFD1320CP43B-00; VFD1320CP43B-21

Applicable models for MKC-EFKM3:
VFD750CP63A-00; VFD750CP63A-21; VFD900CP63A-00; VFD900CP63A-21; VFD1100CP63A-00; VFD1100CP63A-21; VFD1320CP63A-00; VFD1320CP63A-21

Applicable models for MKC-EFKB:
VFD550CP23A-00; VFD550CP23A-21; VFD750CP23A-00; VFD750CP23A-21; VFD900CP23A-00; VFD900CP23A-21; VFD1100CP43A-00; VFD1100CP43A-21; VFD1320CP43B-00; VFD1320CP43B-21; VFD900CP63A-00; VFD900CP63A-21; VFD1100CP63A-00; VFD1100CP63A-21; VFD1320CP63A-00; VFD1320CP63A-21

Model『MKC-EFKM1』Heat Sink Fan

1. Loosen screw 1–4 (figure 1) and disconnect fan power and pull out the fan. (As shown in the enlarged picture 1) Screw1–4 Torque: 24–26 kg-cm / [20.8–22.6 lb-in.] / [2.4–2.5 Nm]

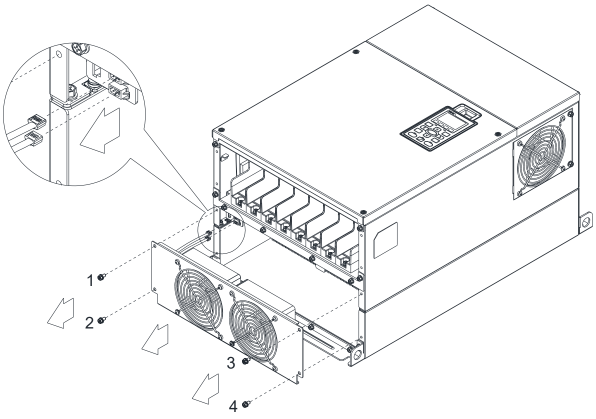


Figure 1

Model『MKC-EFKM2 / MKC-EFKM3』Heat Sink Fan

1. Loosen screw 1–4 (figure 2) and disconnect fan power and pull out the fan. (As shown in the enlarged picture 2) Screw1–4 Torque: 24–26 kg-cm / [20.8–22.6 lb-in.] / [2.4–2.5 Nm]

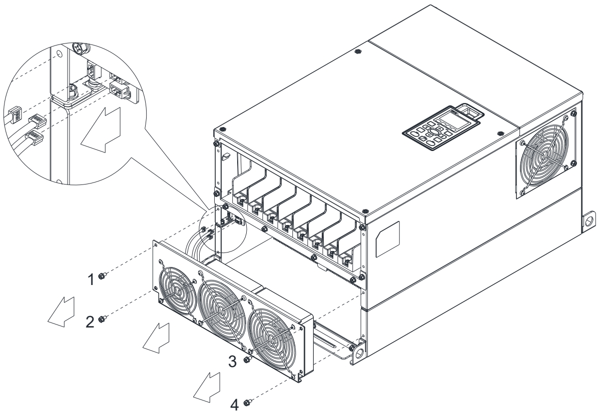


Figure 2

Model『MKC-EFKB』: Heat Sink Fan

1. Loosen screw 1–2 and disconnect fan power and pull out the fan. (As shown in the enlarged picture 3) Screw1–2 Torque: 24–26 kg-cm / [20.8–22.6 lb-in] / [2.4–2.5 Nm]

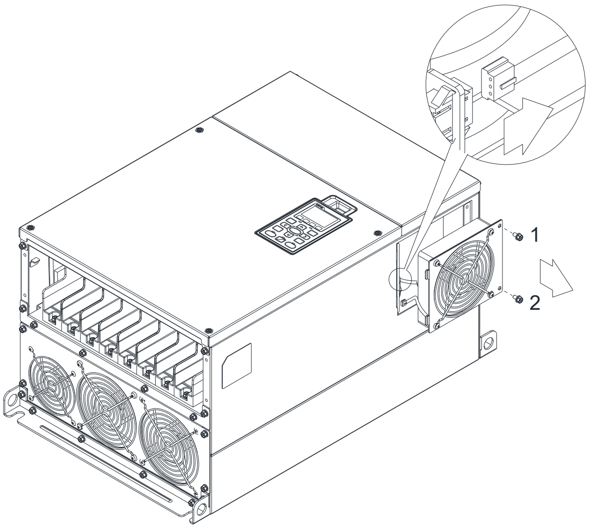


Figure 3

Frame F

Applicable model

VFD1600CP43A-00; VFD1600CP43A-21; VFD1850CP43B-00; VFD1850CP43B-21; VFD1600CP63A-00; VFD1600CP63A-21; VFD2000CP63A-00; VFD2000CP63A-21

Fan model『MKC-FFKM』Heat Sink Fan

1. Loosen the screws and plug out the power of fan before removing it (figure 1). Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

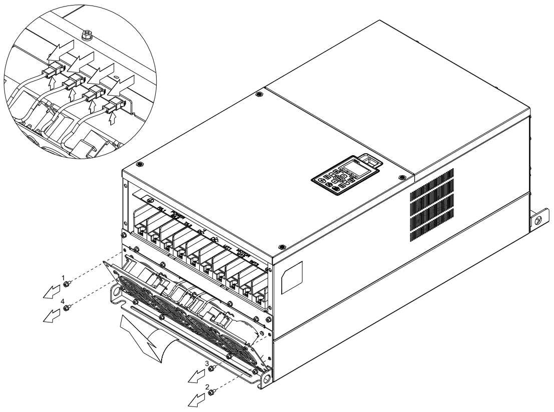


Figure 1

Fan model 『MKC-FFKB』Capacitor Fan

1. Loosen the screw (figure 1) and remove the cover. Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]

2. Loosen the screw (figure 2) and remove the cover. Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

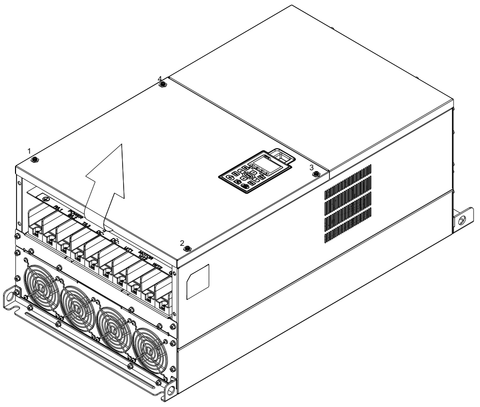


Figure 1

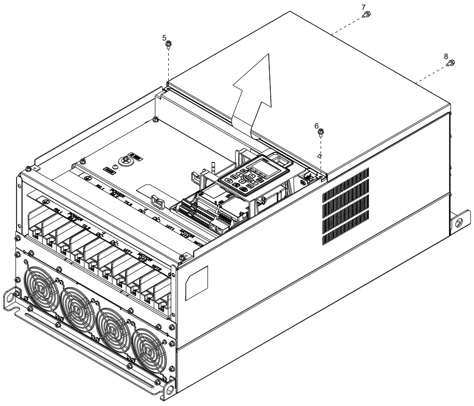


Figure 2

3. Loosen the screws and remove the fan. (figure 3 and figure 4) Screw torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]

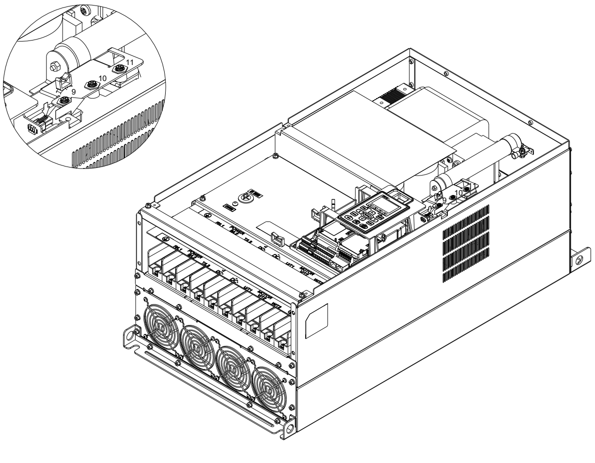


Figure 3

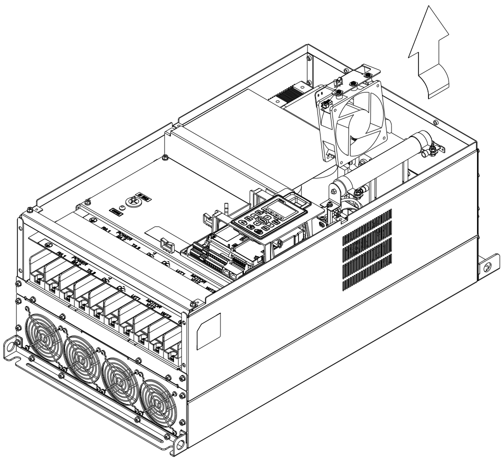


Figure 4

Frame G

Fan model『MKC-GFKM』Heat Sink Fan

Applicable model

VFD2000CP43A-00; VFD2000CP43A-21; VFD2200CP43A-00; VFD2200CP43A-21; VFD2500CP43A-00; VFD2500CP43A-21; VFD2800CP43A-00; VFD2800CP43A-21; VFD2500CP63A-00; VFD2500CP63A-21; VFD3150CP63A-00; VFD3150CP63A-21

1. Loosen the screw (figure 1) and remove the cover. Screw torque: 12–15 kg-cm / [10.4–13.1 Ib-in.] / [1.2–1.5 Nm]

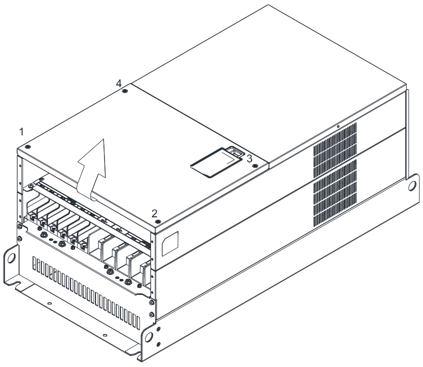


Figure 1

2. For 1–8 shown in the figure 2: Loosen the screws Screw M6 torque: 35–40 kg-cm / [30.4–34.7 Ib-in.] / [3.4–3.9 Nm]
3. For 9–10 shown in the figure 2: Loosen the screws and remove the cover. Screw M4 torque: 14–16 kg-cm / [12.2–13.9 Ib-in.] / [1.4–1.6 Nm]

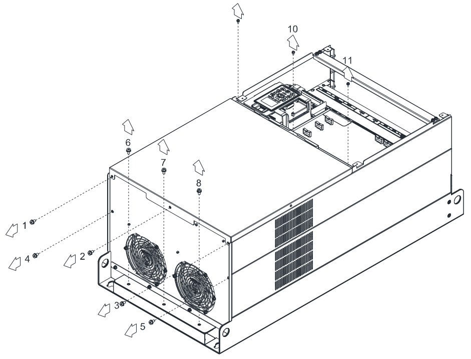


Figure 2

4. Loosen screw 1–3 and remove the protective ring (as shown in figure 3) Screw torque: 14–16 kg-cm / [12.2–13.9 Ib-in.] / [1.4–1.6 Nm]

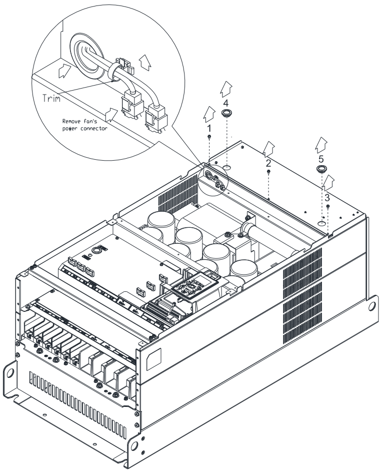


Figure 3

5. Lift the fan by putting your finger through the protective holes, as indicates in 1 and 2 on the figure 4.

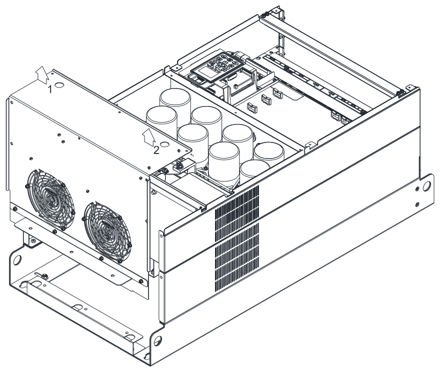


Figure 4

5. If you are switching new fan on old AC motor drive, follow the steps below:
   Loosen screws 1–5, remove the cover (as shown in figure below). M4 screw torque: 14–16 kg-cm / [12.2–13.9 Ib-in] / [1.4–1.6 Nm]

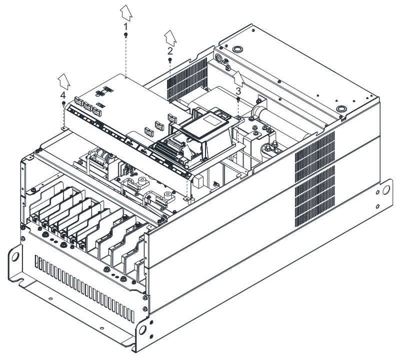


Figure 5

6. Add cable model 3864483201 to connect the power board and fan connector. (The cable 3864483201 goes with the fan as accessory.)

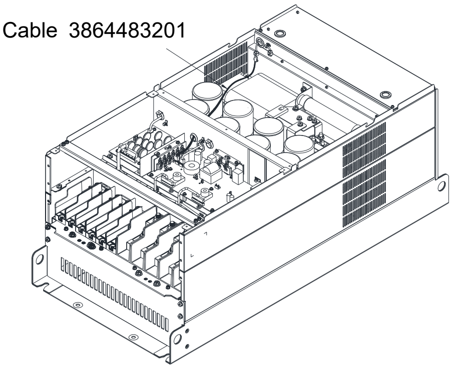


Figure 6

Frame H

Fan model『MKC-HFKM』Heat Sink Fan

Applicable model

VFD3150CP43A-00; VFD3150CP43C-00; VFD3150CP43C-21; VFD3550CP43A-00; VFD3550CP43C-00; VFD3550CP43C-21; VFD4000CP43A-00; VFD4000CP43C-00; VFD4000CP43C-21; VFD5000CP43A-00; VFD5000CP43C-00; VFD5000CP43C-21; VFD5600CP43A-00; VFD5600CP43C-21; VFD6300CP43A-00; VFD6300CP43C-21

1. Loosen the screw 1–4 and remove the top cover (figure 1). Screw torque: 14–16 kg-cm / [12.2–13.9 lb-in] / [1.4–1.6 Nm]

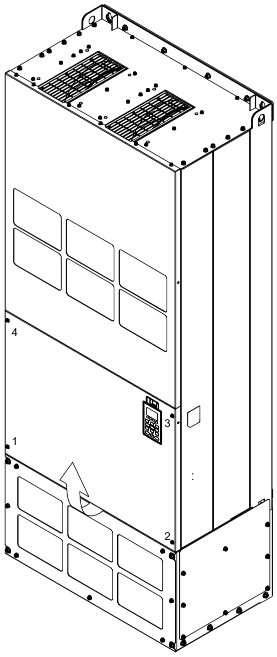


Figure 1

2. Loosen the screw 5–12 and remove the top cover (figure 2). Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in] / [2.4–2.5 Nm]

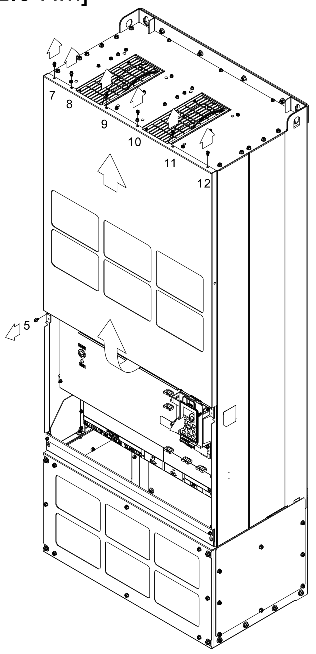
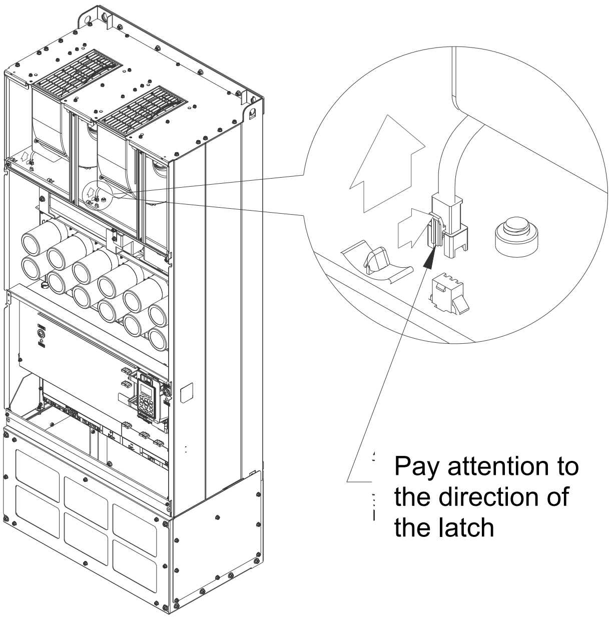


Figure 2

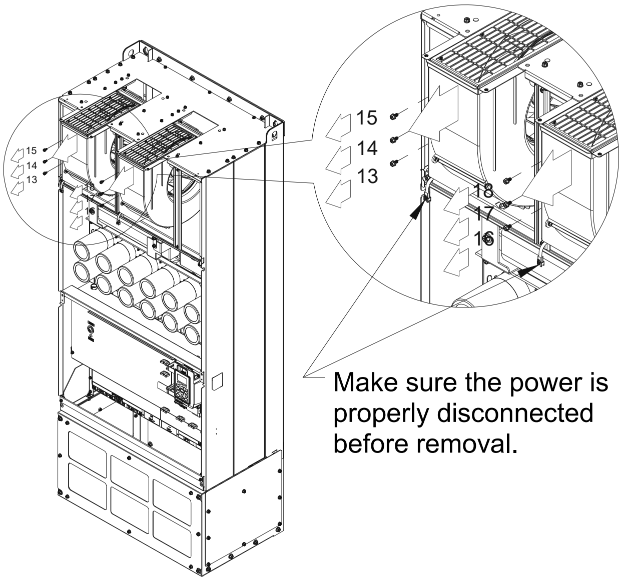
3. Press the latch to disconnect fan power (as shown in the enlarged picture of figure 3).



Pay attention to the direction of the latch

Figure 3

4. Loosen the screw 13–18 and remove the fan. Screw torque: 24–26 kg-cm / [20.8–22.6 lb-in] / [2.4–2.5 Nm] (as shown in figure 4)



Make sure the power is properly disconnected before removal.

Figure 4

Frame H

Fan model『MKCHS-HFKM』Heat Sink Fan

Applicable model

Following models use three sets of MKCHS-HFKM:

VFD5000CP43A-00; VFD5000CP43C-00; VFD5000CP43C-21; VFD5600CP43A-00; VFD5600CP43C-21; VFD6300CP43A-00; VFD6300CP43C-21

1. Loosen the screw 1–4 and remove the top cover (figure 1) Screw torque: 14–16 kg-cm / [12.2–13.9 Ib-in.] / [1.4–1.6 Nm]

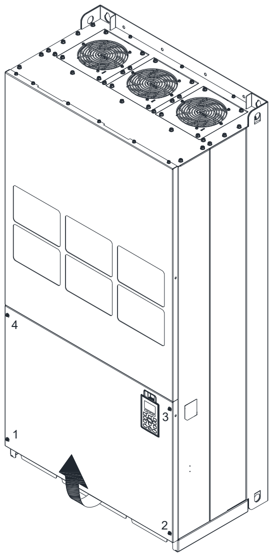


Figure 1

2. Loosen the screw 5–12 and remove the top cover (figure 2). Screw torque: 24–26kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

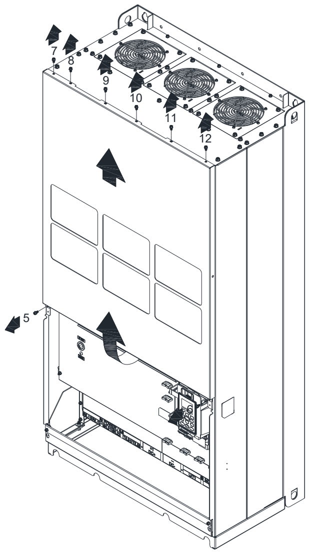


Figure 2

3. Press the latch to disconnect fan power, and cut the cable tie

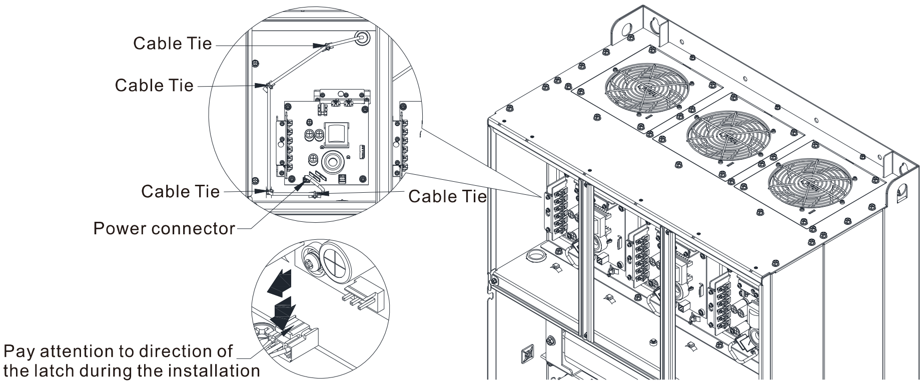

Cable Tie
Cable Tie
Cable Tie
Cable Tie
Power connector
Pay attention to direction of the latch during the installation

Figure 3

4. Loosen the screw 13–24 and remove the fan.

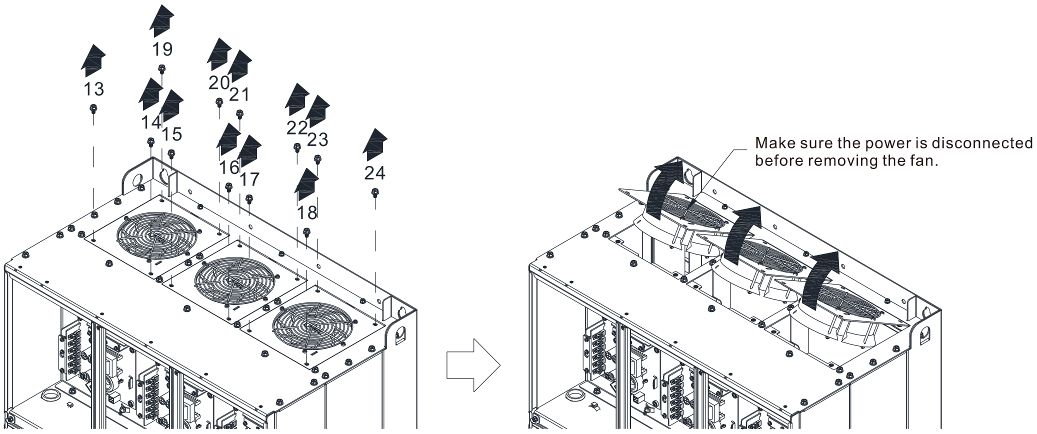

19
13
20
21
14
15
22
23
16
17
24
18
Make sure the power is disconnected before removing the fan.

Figure 4

Fan model『MKC-HFKM1』Heat Sink Fan

Applicable model

Following models use two sets of MKC-HFKM1:

VFD4000CP63A-00; VFD4000CP63A-21

1. Loosen the screw 1–4 and remove the top cover (figure 1) Screw torque: 14–16 kg-cm / [12.2–13.9 Ib-in.] / [1.4–1.6 Nm]

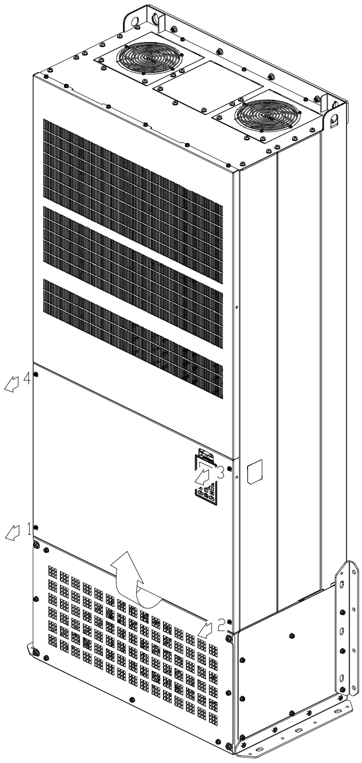


Figure 1

2. Loosen the screw and remove the top cover (figure 2). Screw torque: 24–26kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

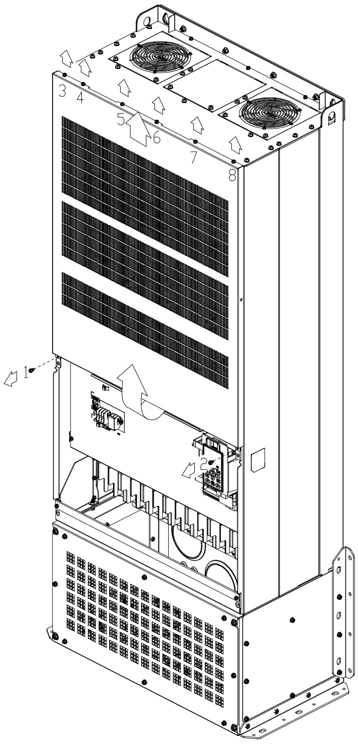


Figure 2

3. Disconnect the fan (figure 3).

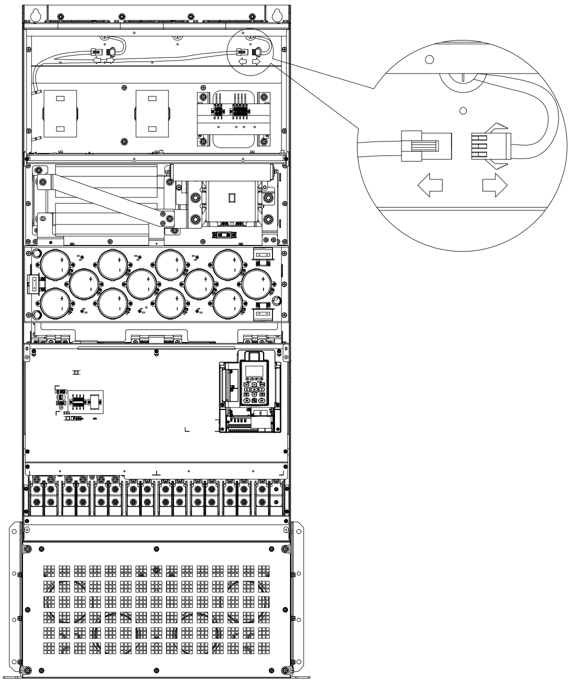


Figure 3

4. Loosen the screw 1–4 (as shown below) and remove the fan. Make sure fan power is disconnected before removal. Screw torque: 24–26kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

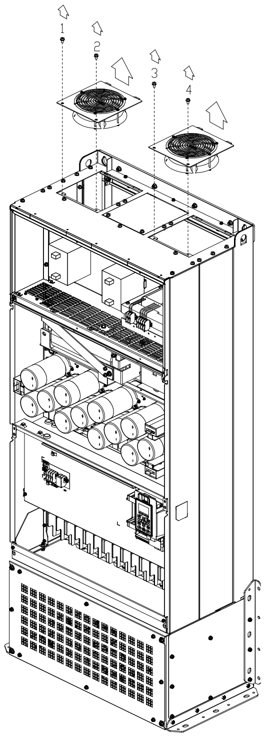


Figure 4

Fan model『MKC-HFKM1』Heat Sink Fan

Applicable model

Following models use three sets of MKC-HFKM1:

VFD4500CP63A-00; VFD4500CP63A-21; VFD5600CP63A-00; VFD5600CP63A-21; VFD6300CP63A-00; VFD6300CP63A-21

1. Loosen the screw 1–4 and remove the top cover (figure 1) Screw torque: 14–16 kg-cm / [12.2–13.9 Ib-in.] / [1.4–1.6 Nm]

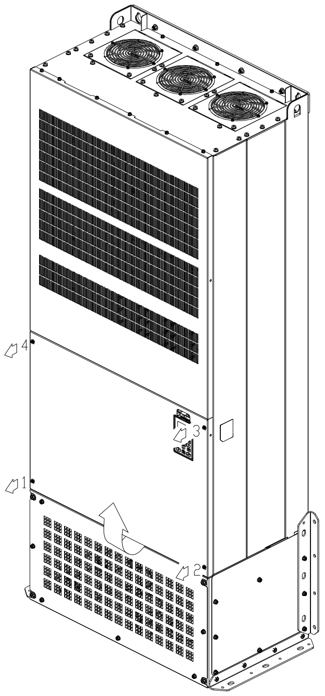


Figure 1

2. Loosen the screw and remove the top cover (figure 2). Screw torque: 24–26kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

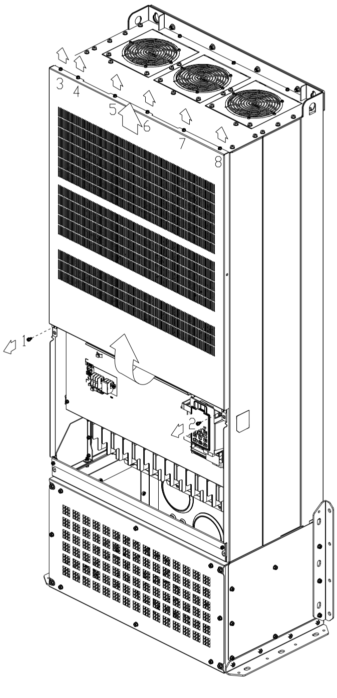


Figure 2

3. Disconnect the fan (figure 3).

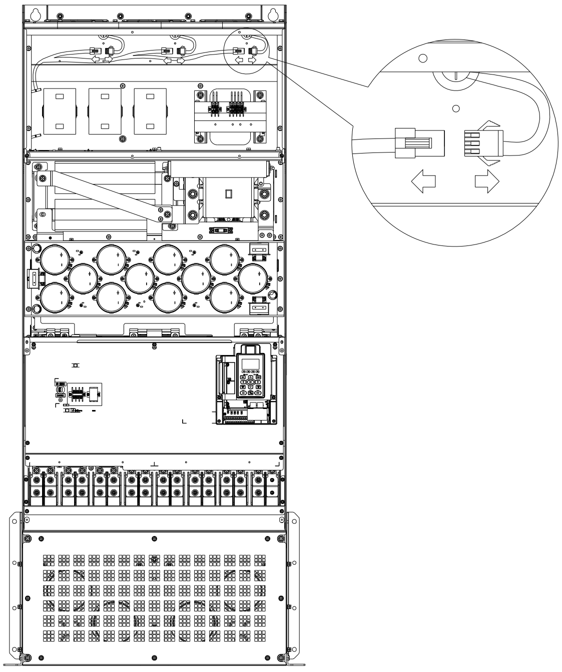


Figure 3

4. Loosen the screw 1–6 (as shown below) and remove the fan. Make sure fan power is disconnected before removal. Screw torque: 24–26kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]

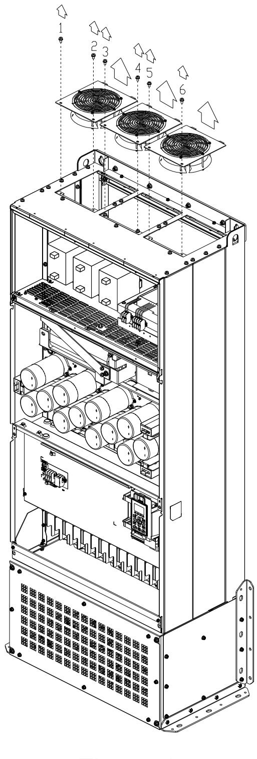


Figure 4

7-10 Flange Mounting Kit

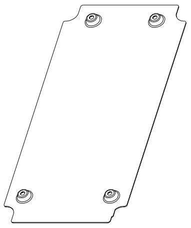
Applicable Models, Frame A–F

Frame A

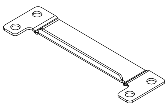
『MKC-AFM1』

Applicable model

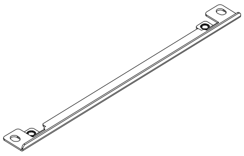
VFD022CP23A-21; VFD022CP43B-21; VFD022CP4EB-21; VFD037CP23A-21; VFD015CP53A-21; VFD022CP53A-21; VFD037CP53A-21



Accessories 1*1



Accessories 2*2



Accessories 3*2

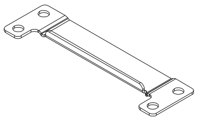
Screw 1 *4
M3*P 0.5; L=6mm

Screw 2*8
M6*P 1.0; L=16mm

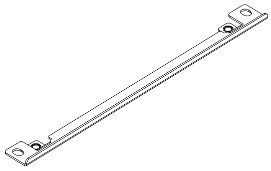
『MKC-AFM』

Applicable model

VFD007CP4EA-21; VFD015CP23A-21; VFD015CP43B-21; VFD015CP4EB-21; VFD022CP23A-21; VFD037CP43B-21; VFD037CP4EB-21; VFD055CP23A-21; VFD040CP43A-21; VFD040CP4EA-21; VFD055CP43B-21; VFD055CP4EB-21; VFD075CP43B-21; VFD075CP4EB-21



Accessory 2*2

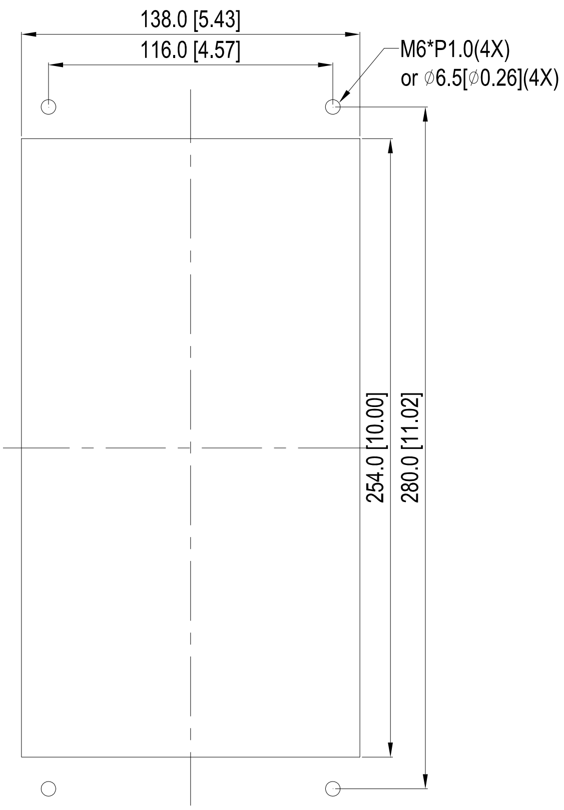


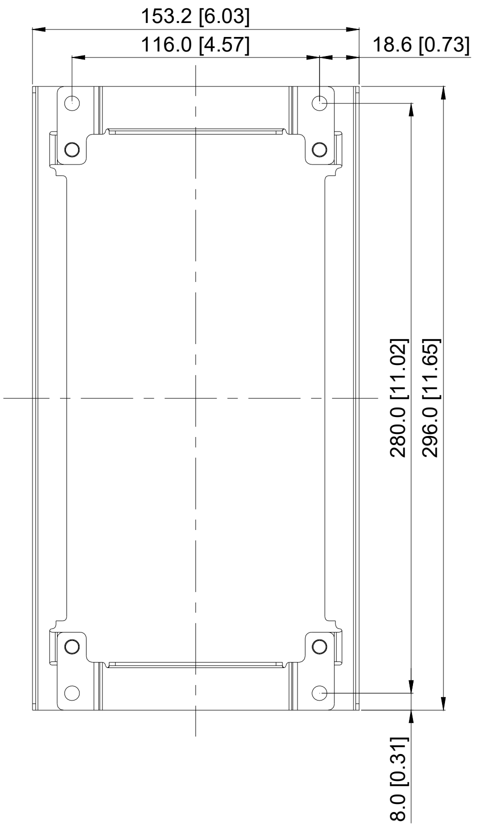
Accessory 3*2

Screw *8
M6*P 1.0; L=16mm

Cutout dimension

Unit : mm [inch]





『MKC-AFM1』Installation

1. Install accessory 1 by fastening 4 of the screw 1(M3) (figure 1). Screw torque: 6–8 kg-cm / [5.21–6.94 Ib-in.] / [0.6–0.8 Nm]

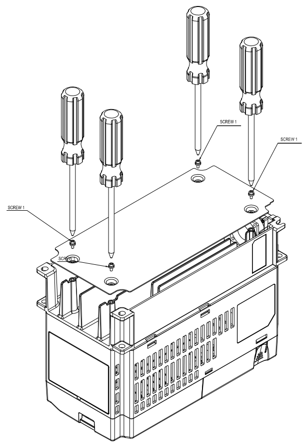


Figure 1

2. Install accessory 2&3 by fastening 2 of the screw 2 (M6) (figure 2). Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm]

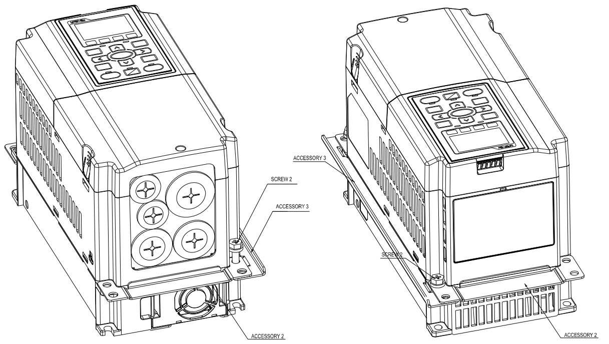


Figure 2

3. Install accessory 2&3 by fastening 2 of the screw 2(M6) (figure 3). Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm]

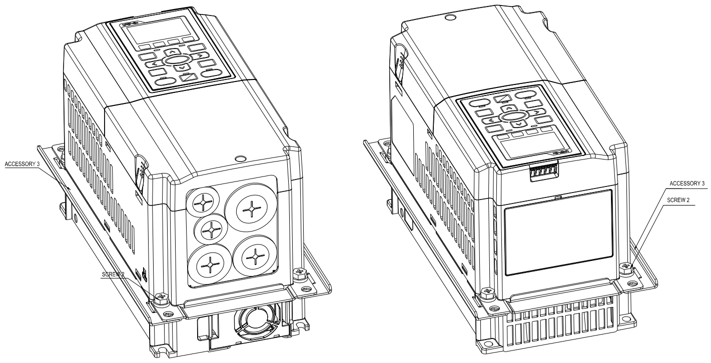


Figure 3

4. Plate installation, place 4 of the screw 2 (M6) (figure 4) through accessory 2&3 and the plate then fasten the screws. Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm]

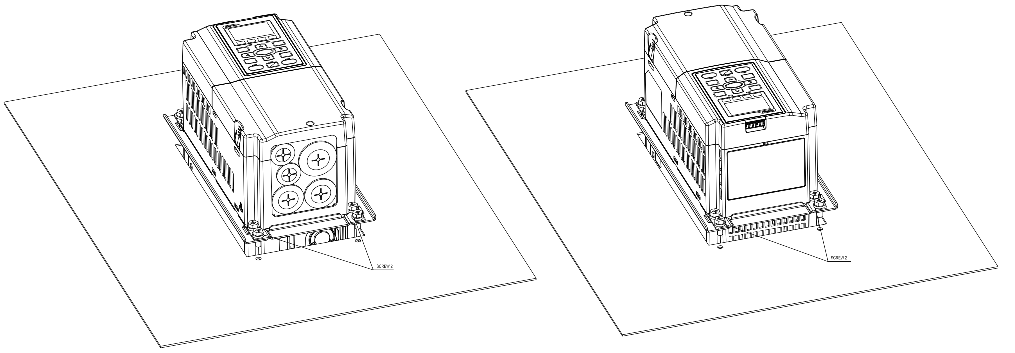


Figure 4

『MKC-AFM』 Installation

1. Install accessory 2 & 3 by fastening 2 of the screw 2 (M6). Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm] (figure 1)

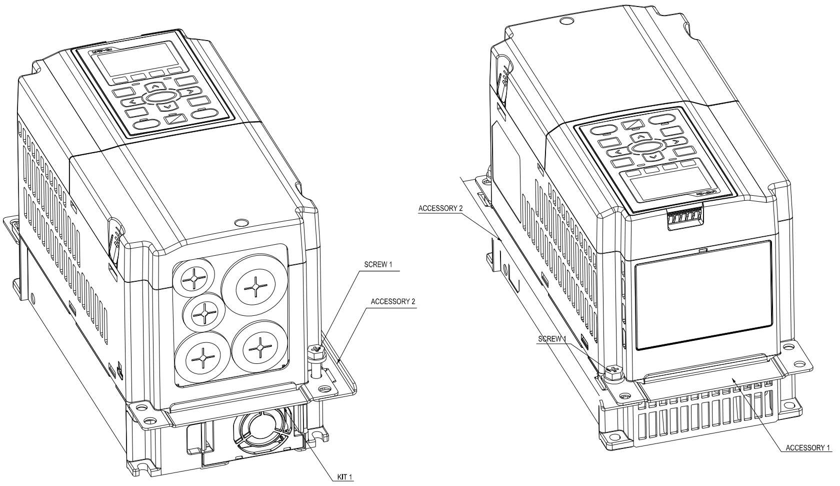


Figure 1

2. Install accessory 2 & 3 by fastening 2 of the screw 2 (M6). Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm] (figure 2)

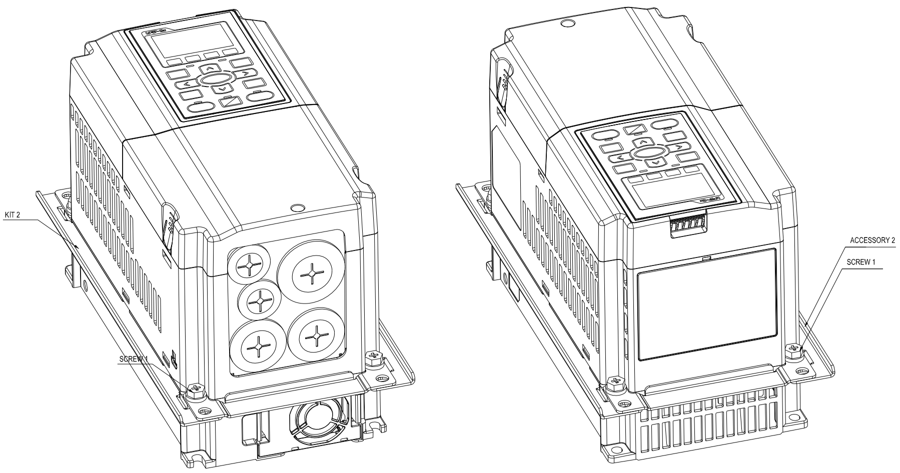


Figure 2

3. Plate installation, place 4 of the screw *4 (M6) through accessory 2&3 and the plate, then fasten the screws. Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm] (figure 3)

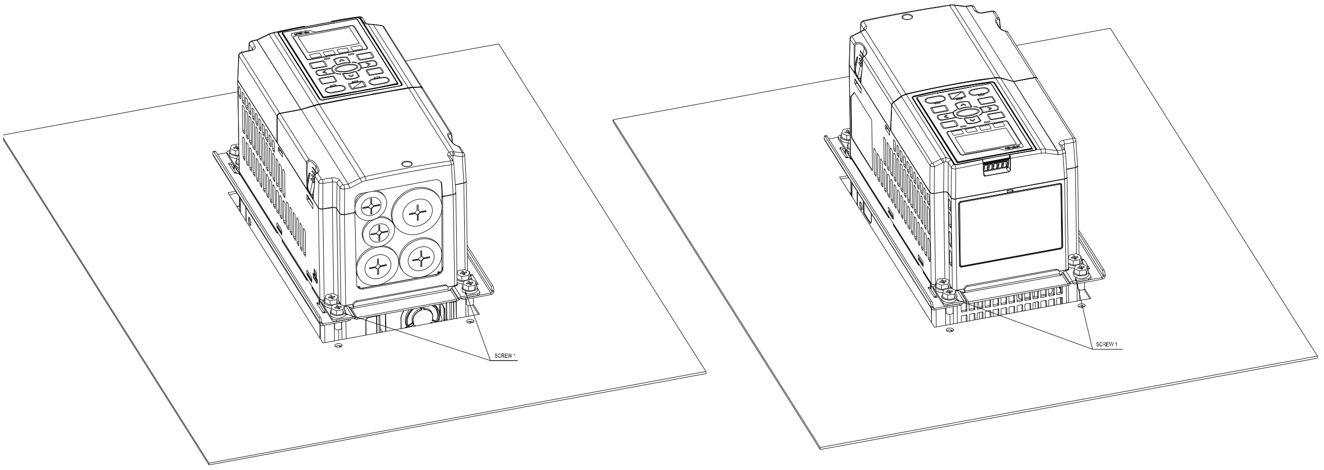


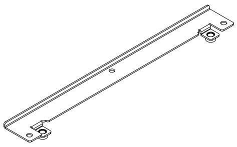
Figure 3

Frame B

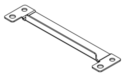
『MKC-BFM』

Applicable model

VFD075CP23A-21; VFD110CP23A-21; VFD110CP43B-21; VFD110CP4EB-21; VFD150CP23A-21; VFD150CP43B-21; VFD150CP4EB-21; VFD185CP43B-21; VFD185CP4EB-21; VFD055CP53A-21; VFD075CP53A-21; VFD110CP53A-21; VFD150CP53A-21



Accessory 1*2

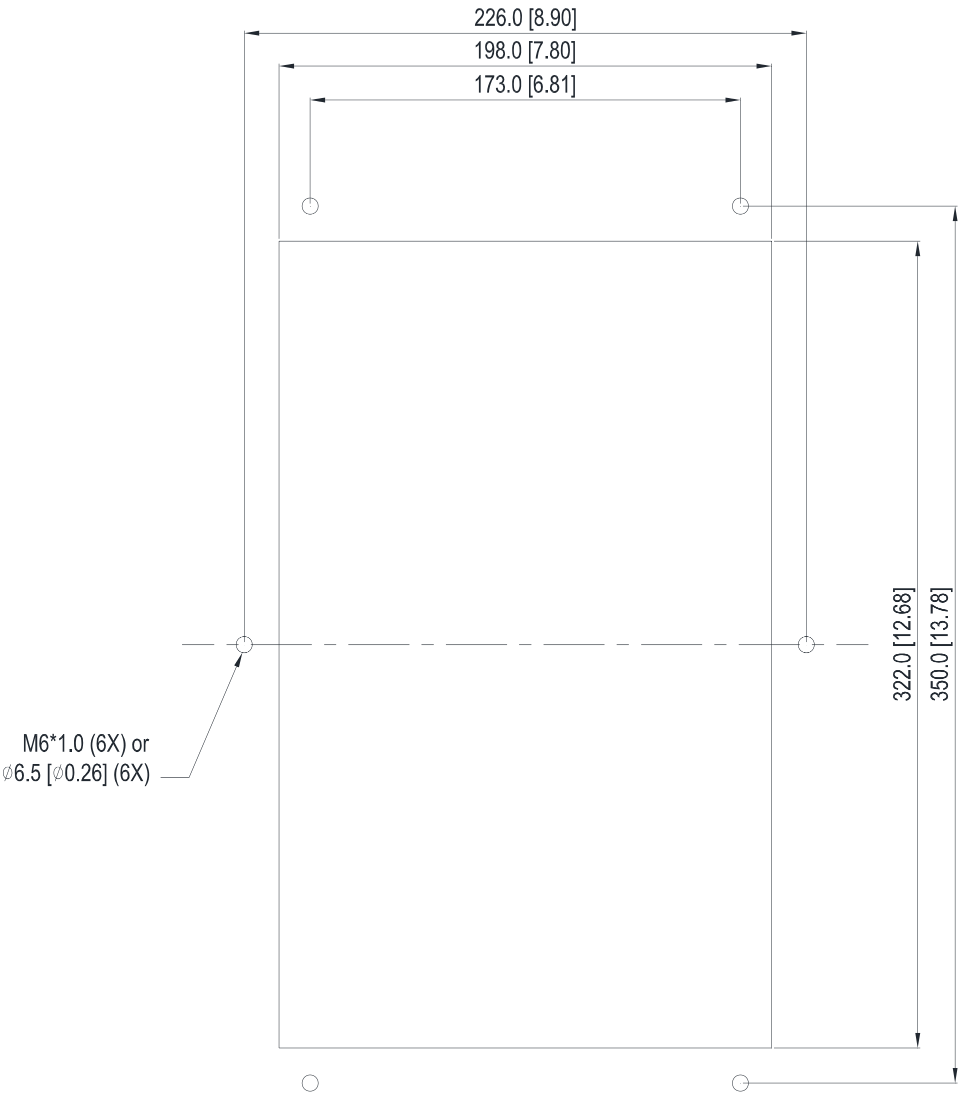


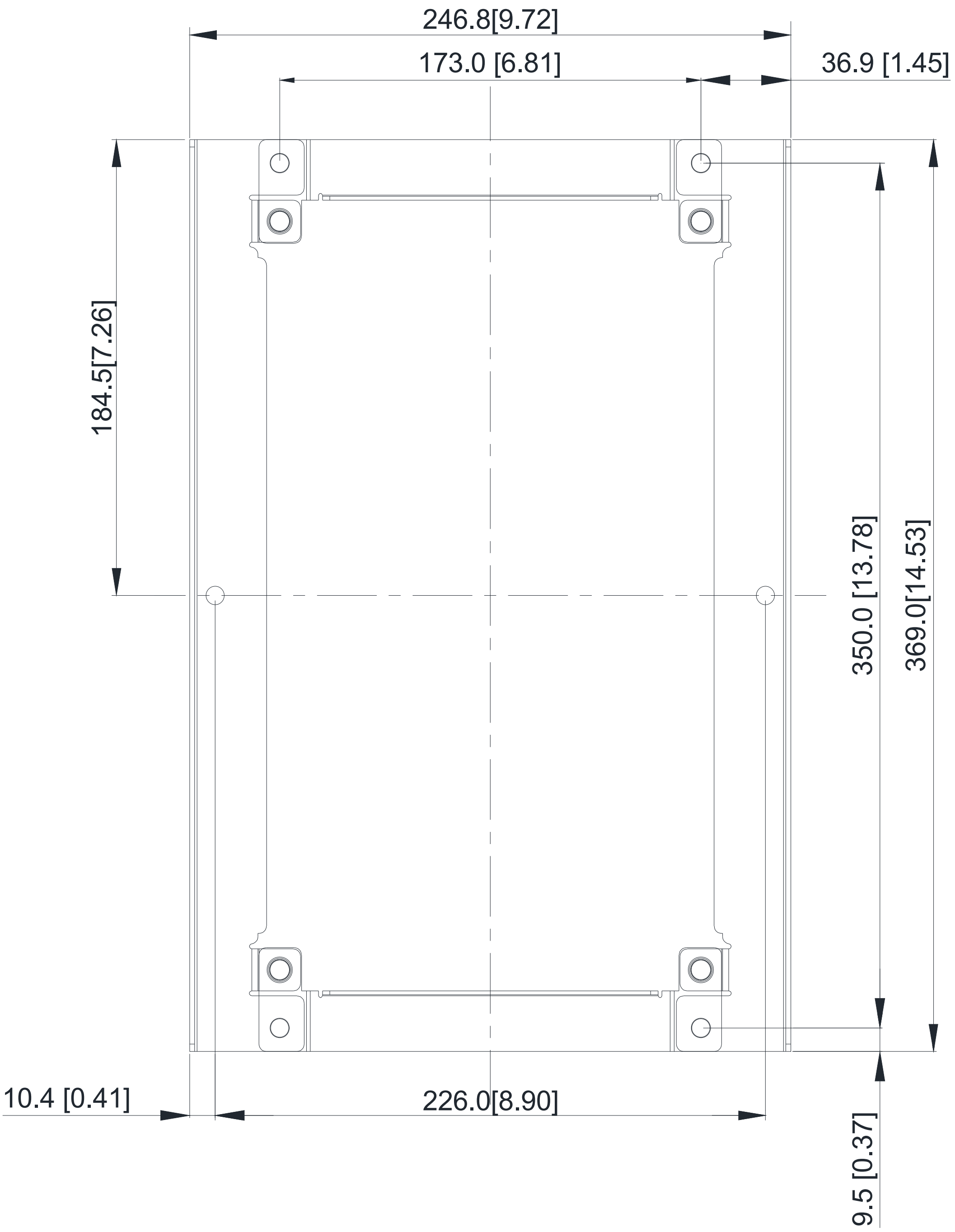
Accessory 2*2

Screw 1 *4–M8*P 1.25;
Screw 2*6–M6*P 1.0

Cutout dimension

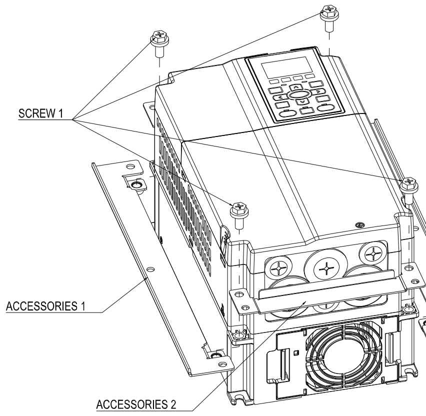
Unit : mm [inch]

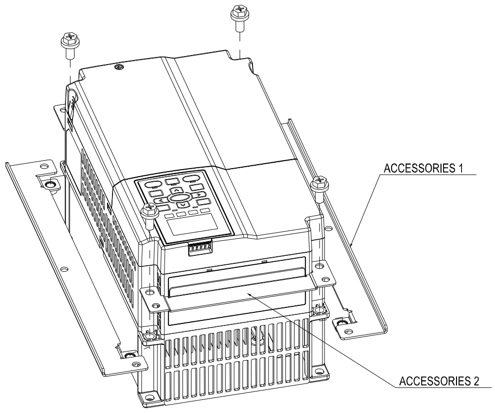



246.8[9.72]
173.0 [6.81]
36.9 [1.45]
184.5[7.26]
350.0 [13.78]
369.0[14.53]
10.4 [0.41]
226.0[8.90]
9.5 [0.37]

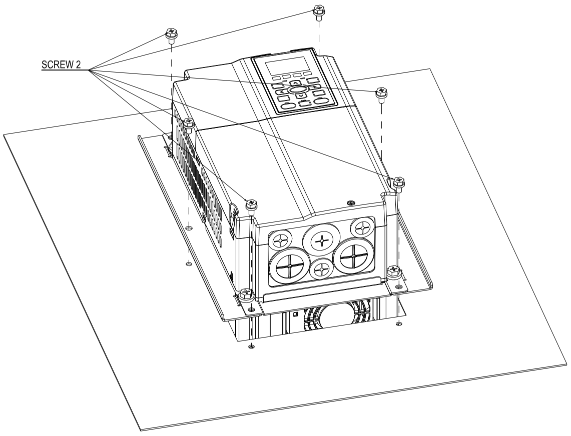
『MKC-BFM』Installation

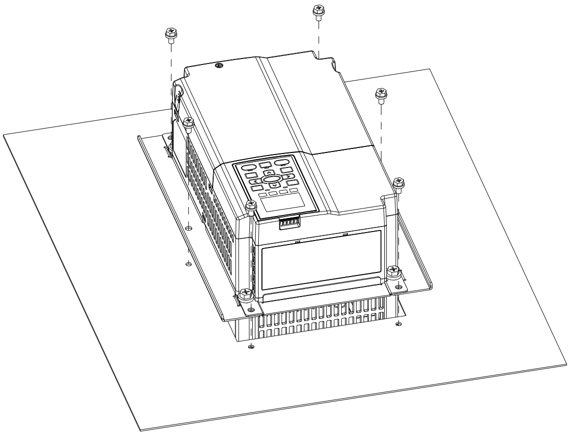
1. Install accessory 1& 2 by fastening 4 of the screw 1 (M8). Screw torque: 40–45 kg-cm / [34.7–39.0 Ib-in.] / [3.9–4.4 Nm] (As shown in the following figure)





2. Plate installation, place 6 of the screw 2 (M6) through accessory 1&2 and the plate, then fasten the screws. Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm] (As shown in the following figure)



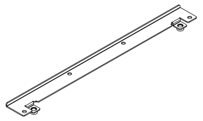


Frame C

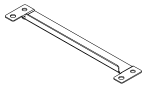
『MKC-CFM』

Applicable model

VFD185CP23A-21; VFD220CP23A-21; VFD220CP43A-21; VFD220CP4EA-21; VFD300CP23A-21; VFD300CP43B-21; VFD300CP4EB-21; VFD370CP43B-21; VFD370CP4EB-21; VFD185CP63A-21; VFD220CP63A-21; VFD300CP63A-21; VFD370CP63A-21



Accessory 1*2

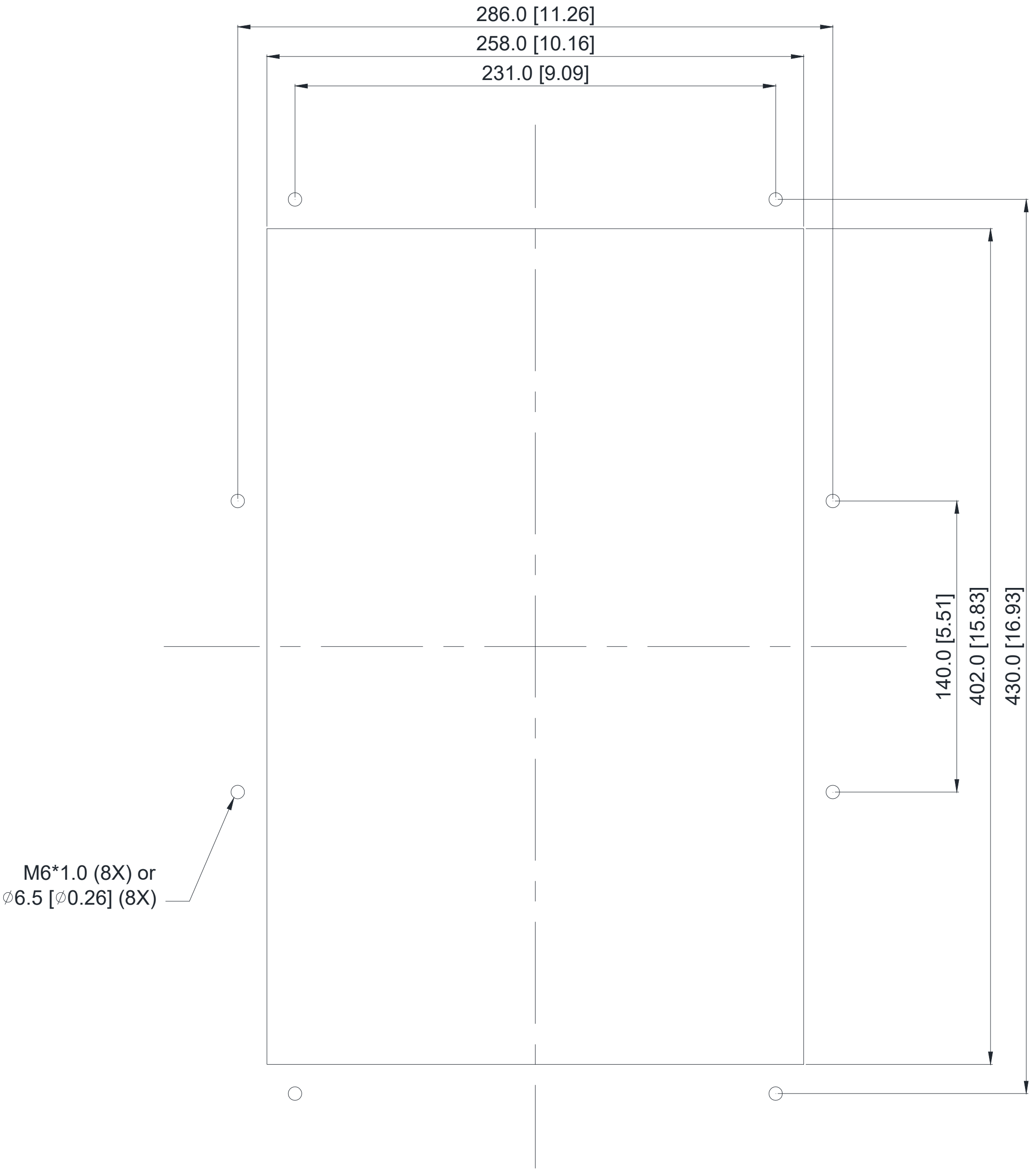


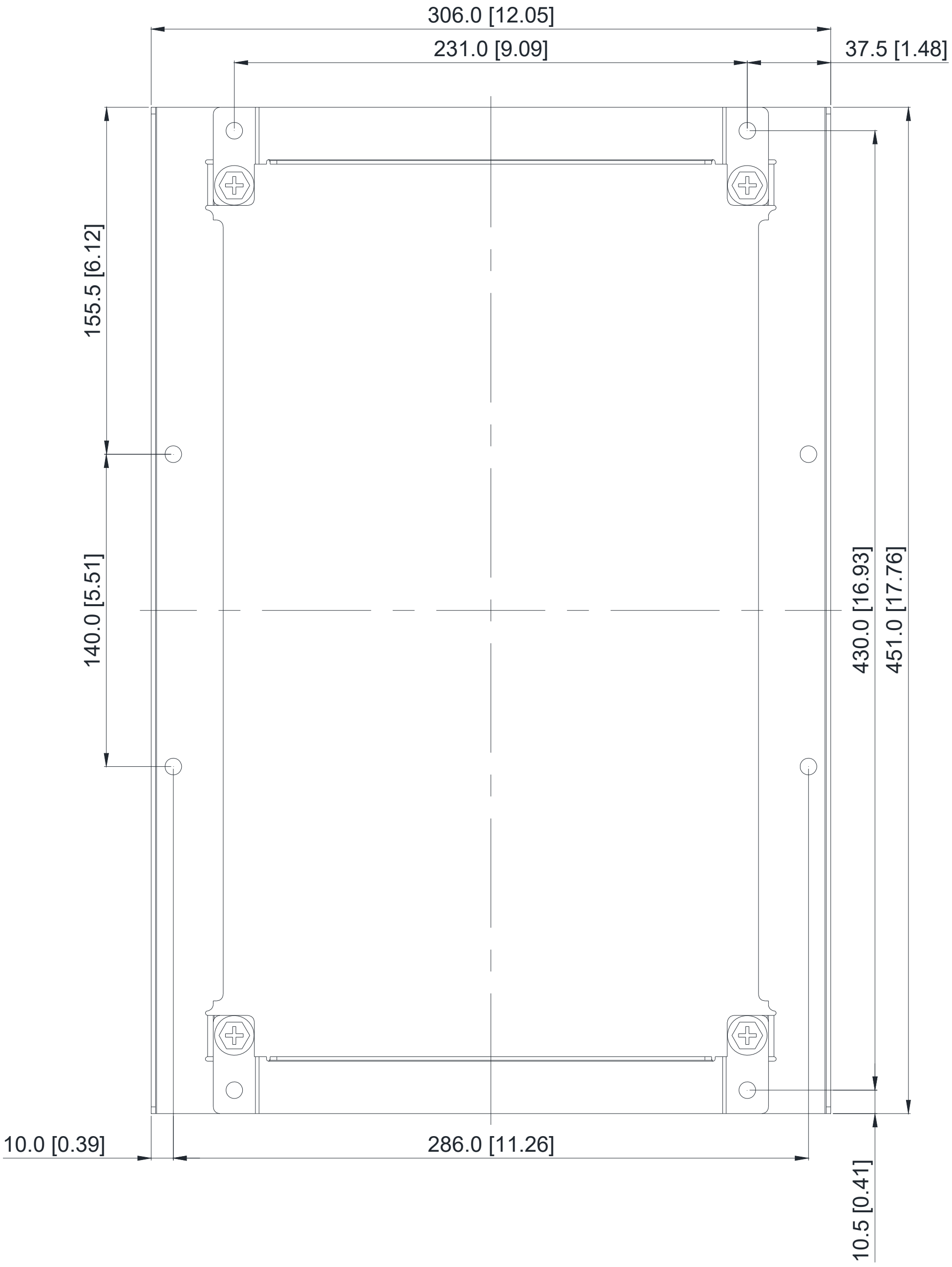
Accessory 2*2

Screw 1*4 ~ M8*P 1.25;
Screw 2*8 ~ M6*P 1.0

Cut out dimension

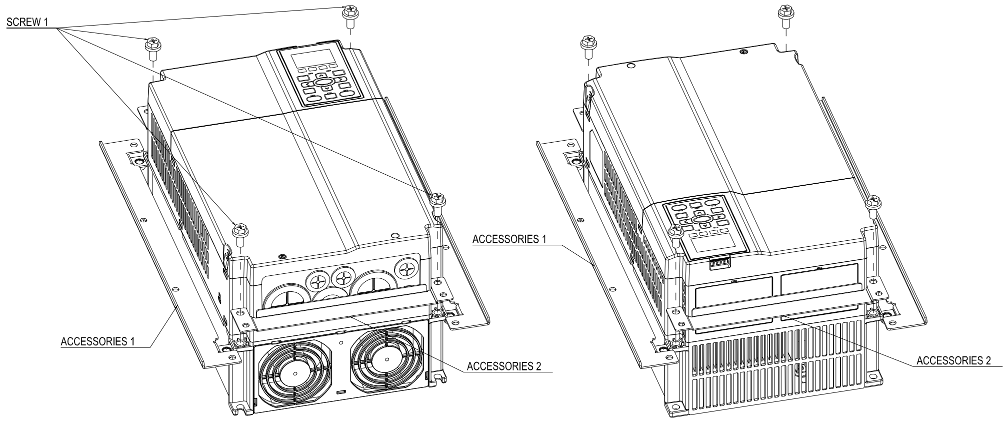
Unit : mm [inch]



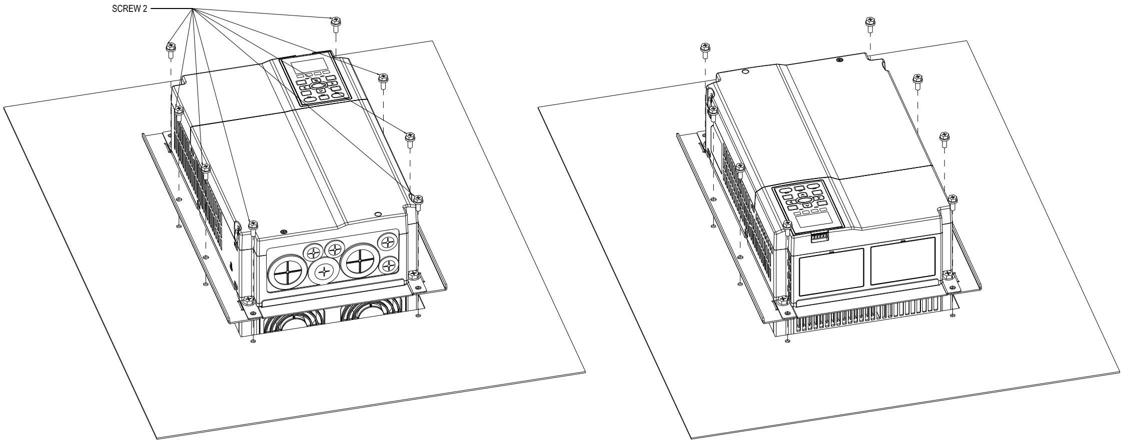

306.0 [12.05]
231.0 [9.09]
37.5 [1.48]
155.5 [6.12]
140.0 [5.51]
430.0 [16.93]
451.0 [17.76]
10.0 [0.39]
286.0 [11.26]
10.5 [0.41]

『MKC-CFM』Installation

1. Install accessory 1 & 2 by fastening 4 of the screw 1 (M8). Screw torque: 50–55 kg-cm / [43.4–47.7 Ib-in.] / [4.9–5.4 Nm] (As shown in the following figure)



2. Plate installation, place 8 of the screw 2 (M6) through Accessory 1&2 and the plate, then fasten the screws. Screw torque: 25–30 kg-cm / [21.7–26 Ib-in.] / [2.5–2.9 Nm] (As shown in the following figure)

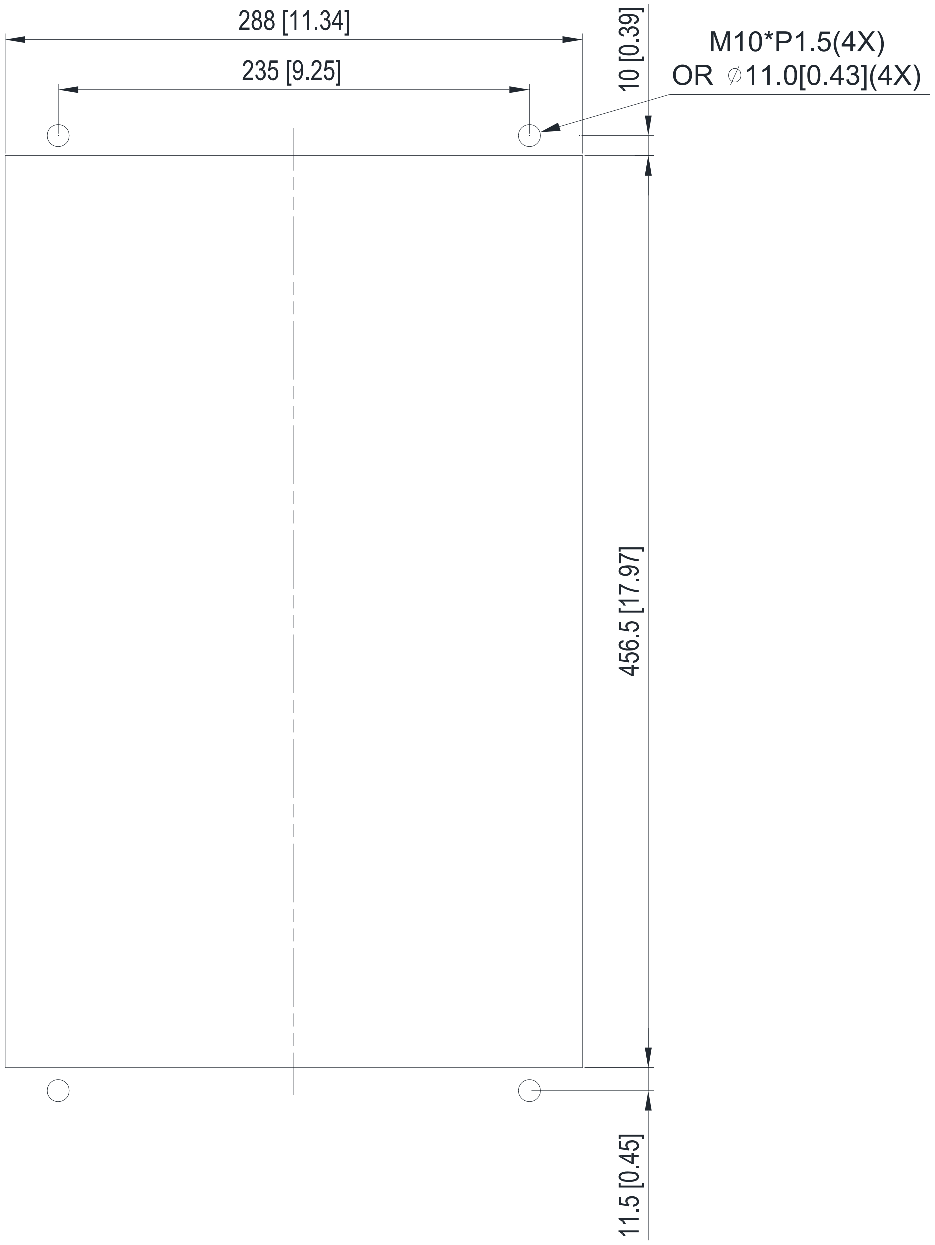


Frame D0

Applicable model

VFD450CP43S-00; VFD450CP43S-21; VFD550CP43S-00; VFD550CP43S-21

Cutout dimension Unit: mm [inch]

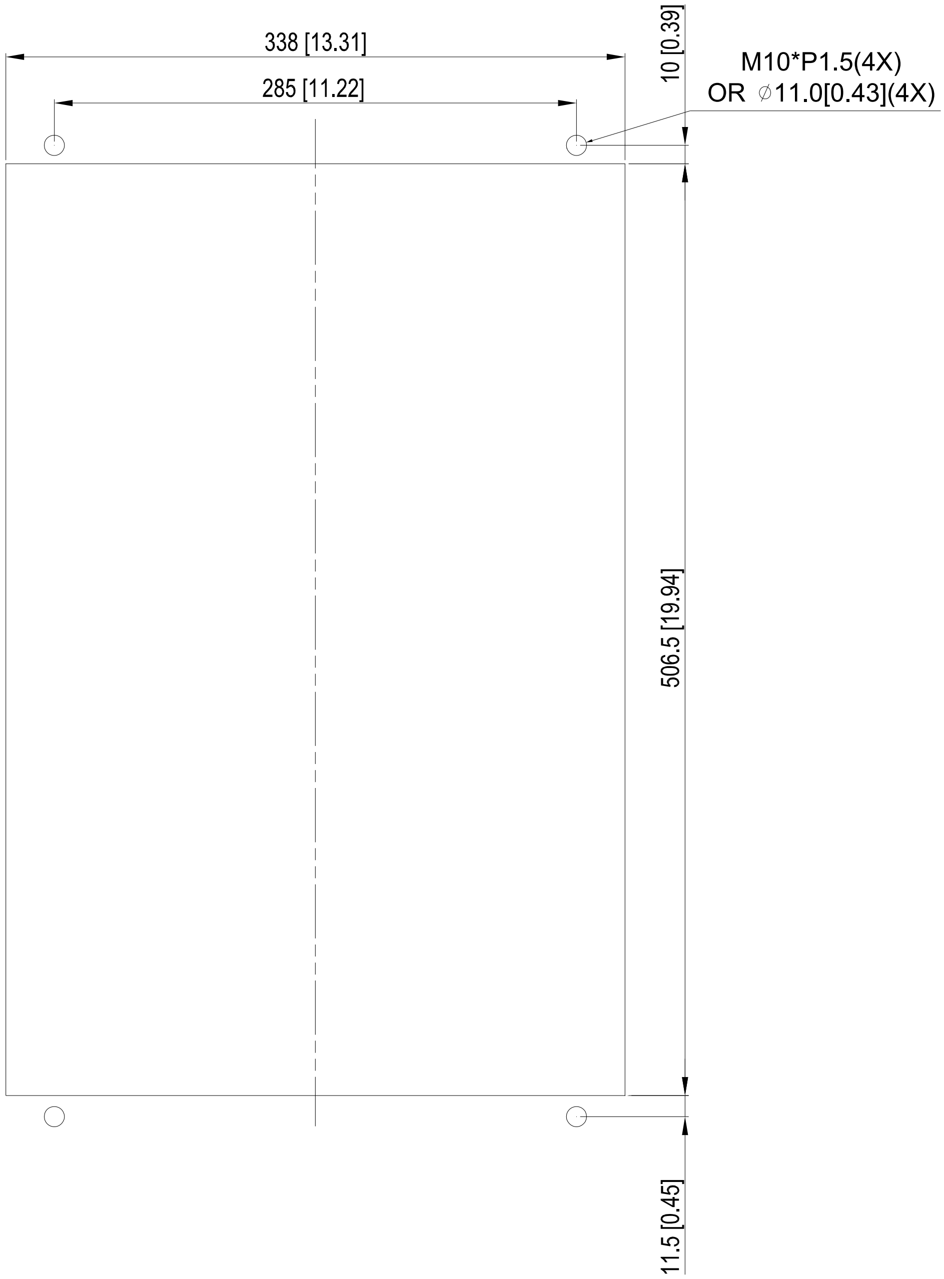


Frame D

Applicable model

VFD370CP23A-00; VFD370CP23A-21; VFD450CP23A-00; VFD450CP23A-21; VFD750CP43B-00; VFD750CP43B-21; VFD900CP43A-00; VFD900CP43A-21; VFD450CP63A-00; VFD450CP63A-21; VFD550CP63A-00; VFD550CP63A-21

Cutout dimension Unit: mm [inch]

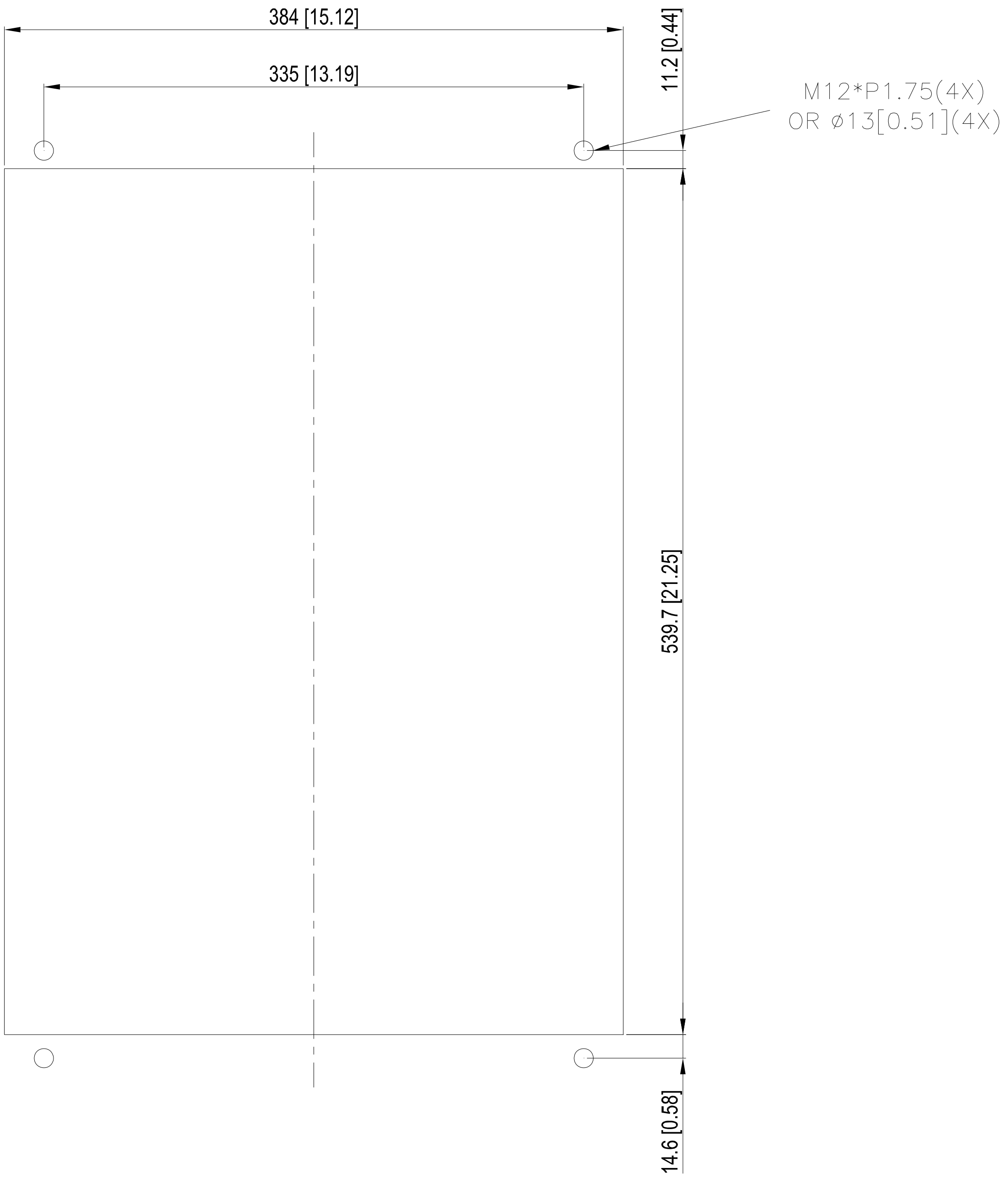


Frame E

Applicable model

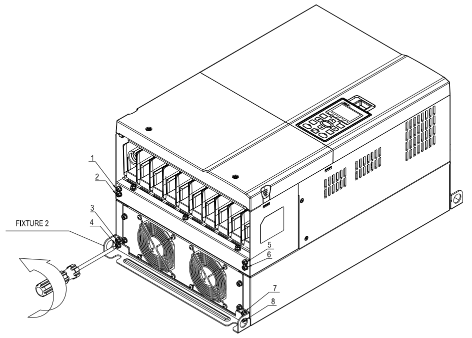
VFD550CP23A-00; VFD550CP23A-21; VFD750CP23A-00; VFD750CP23A-21; VFD900CP23A-00; VFD900CP23A-21; VFD1100CP43A-00; VFD1100CP43A-21; VFD1320CP43B-00; VFD1320CP43B-21; VFD750CP63A-00; VFD750CP63A-21; VFD900CP63A-00; VFD900CP63A-21; VFD1100CP63A-00; VFD1100CP63A-21; VFD1320CP63A-00

Cutout dimension Unit: mm [inch]

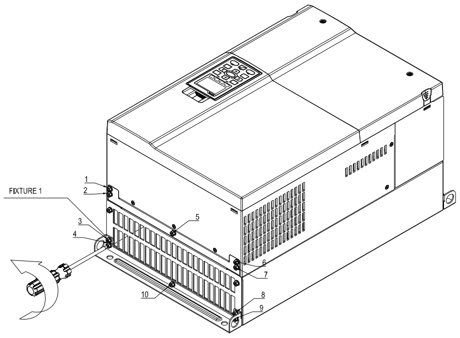


Frame D0 & D & E Installation

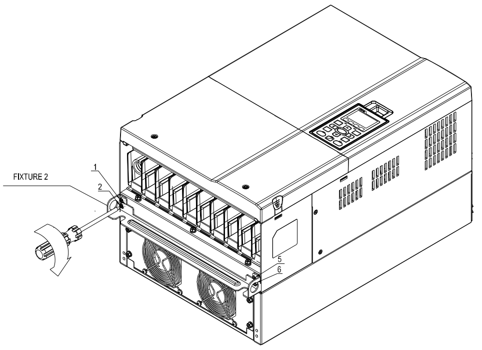
1. Loosen 8 screws and remove Fixture 2 (as shown in the following figure).



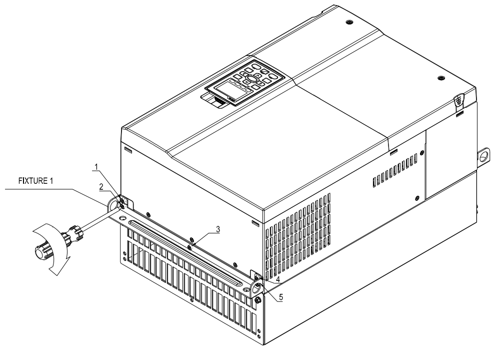
2. Loosen 10 screws and remove Fixture 1 (as shown in the following figure).



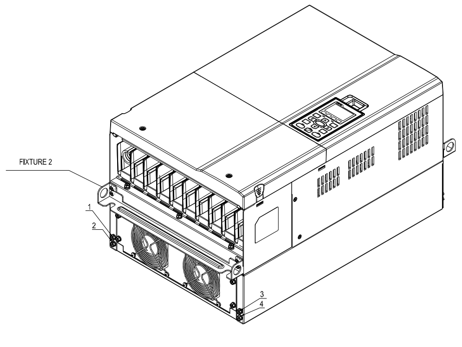
3. Fasten 4 screws (as shown in the following figure). Screw torque: 30–32 kg-cm / [26.0–27.8 Ib-in.] / [2.9–3.1 Nm]



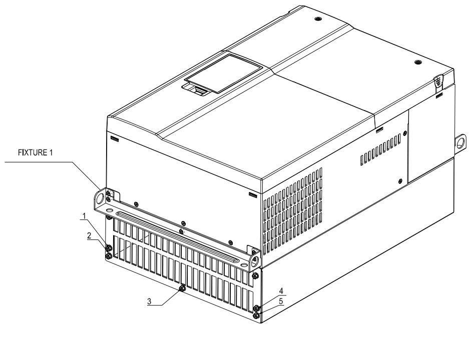
4. Fasten 5 screws (as shown in the following figure). Screw torque: 30–32 kg-cm / [26.0–27.8 Ib-in.] / [2.9–3.1 Nm]



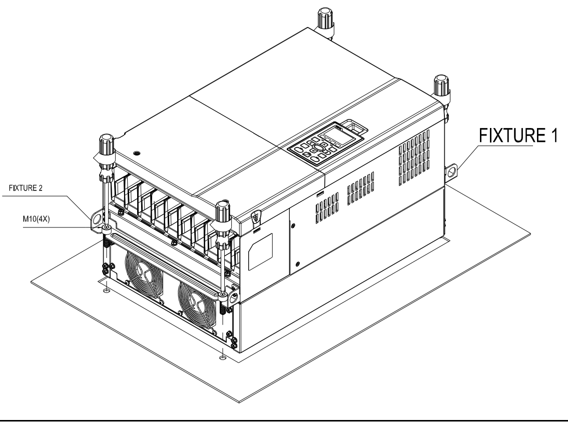
5. Fasten 4 screws (as shown in the following figure). Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



6. Fasten 5 screws (as shown in the following figure). Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



7. Place 4 screws (M10) through Fixture 1&2 and the plate then fasten the screws. (as shown in the following figure)
   Frame D0/D M10*4 Screw torque: 200–240 kg-cm / [173.6–208.3 Ib-in.] / [19.6–23.5 Nm]
   Frame E M12*4 Screw torque: 300–400 kg-cm / [260–347 Ib-in.] / [29.4–39.2 Nm]

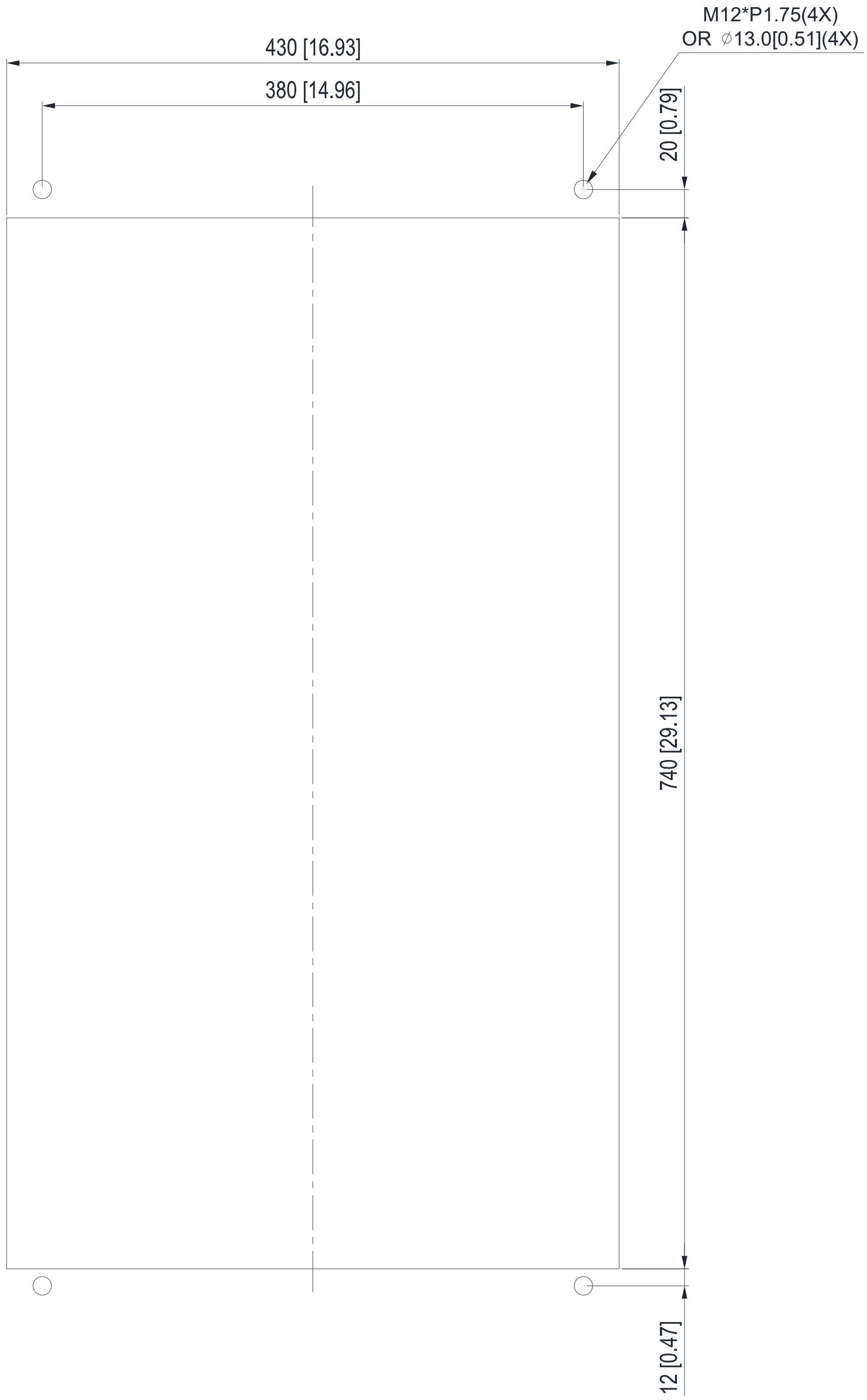


Frame F Installation

Applicable model

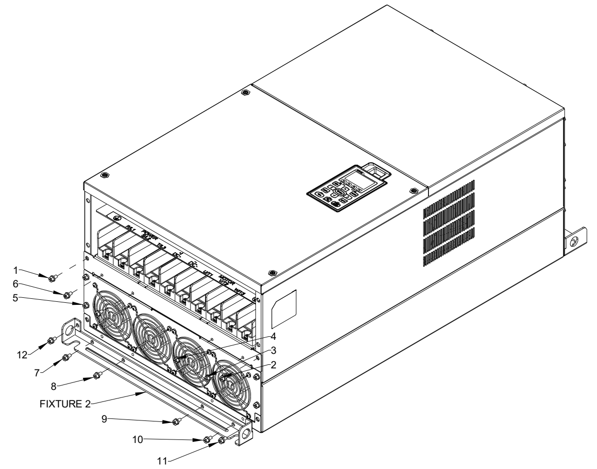
VFD1600CP43A-00; VFD1600CP43A-21; VFD1850CP43B-00; VFD1850CP43B-21; VFD1600CP63A-00; VFD1600CP63A-21; VFD2000CP63A-00; VFD2000CP63A-21

Cutout dimension Unit : mm [inch]

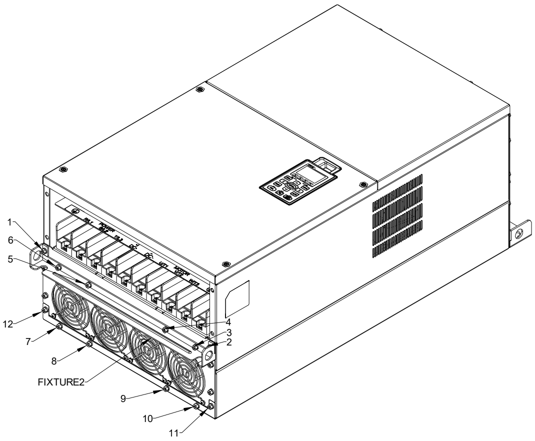


Frame F

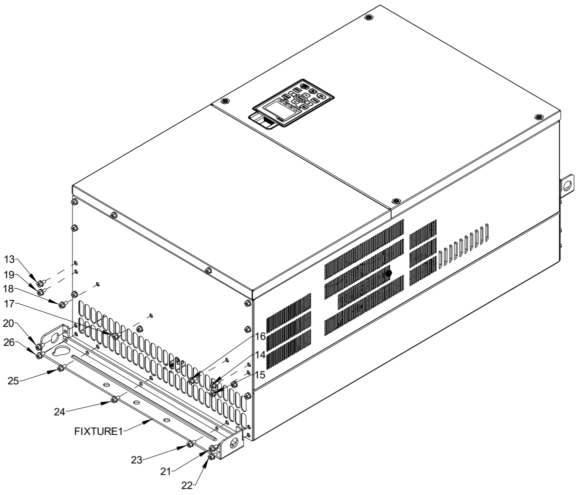
1. Loosen 12 screws and remove Fixture 2.



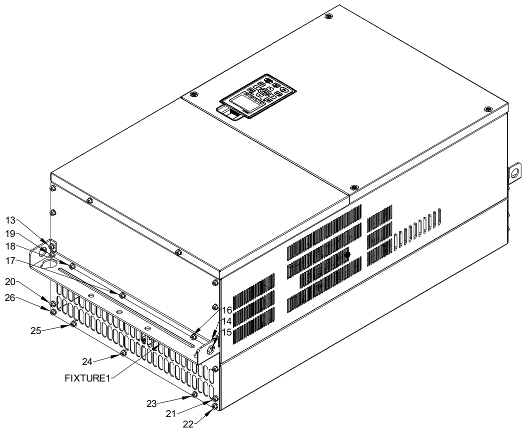
2. Loosen 12 screws and remove Fixture 2.
   Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



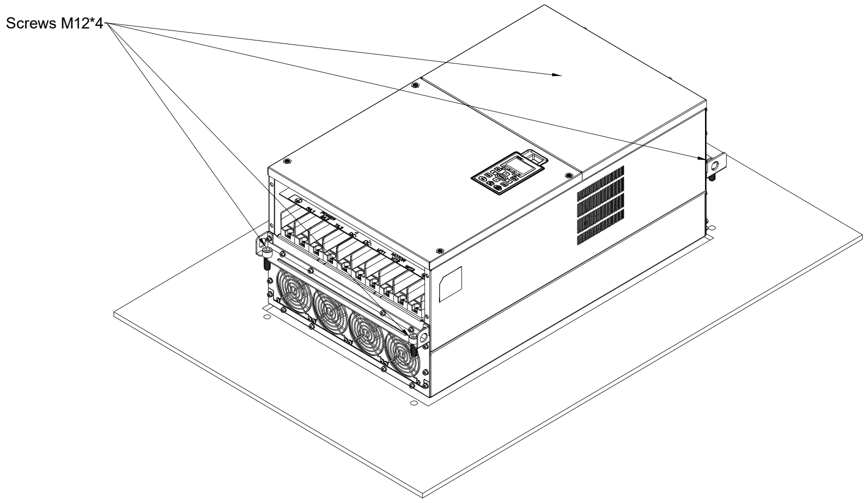
3. Loosen screw 13–26 and remove Fixture 1.



4. Install Fixture 1 by fasten screw 13–26
   Screw torque: 24–26 kg-cm / [20.8–22.6 Ib-in.] / [2.4–2.5 Nm]



5. Place 4 of the M12 screws through Fixture 1&2 and plate then fasten the screws.
   Screw torque: 300–400 kg-cm / [260–347 Ib-in.] / [29.4–39.2 Nm]



7-11 Power Terminal Kit

『MKC-PTCG』 (Applicable for Frame G models-VFDXXXCPXXA)

Applicable model
VFD2000CP43A-00/-21; VFD2200CP43A-00/-21; VFD2500CP43A-00/-21; VFD2800CP43A-00/-21; VFD2500CP63A-00/-21; VFD3150CP63A-00/-21
(The MKC-PTCG is optional for the above models, after installation, the 12 pulse will be 6 pulse.)

Accessories

Item	Description	Q'ty
1	Copper Assy.	3
1.1	Copper	3
1.2	Screw M12*25L	6
1.3	Spring	6
1.4	Washer	6
1.5	Nuts	6

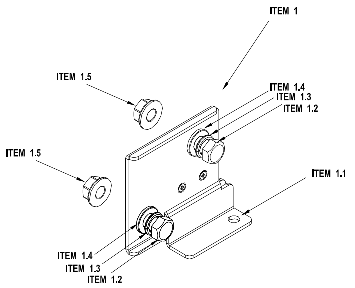
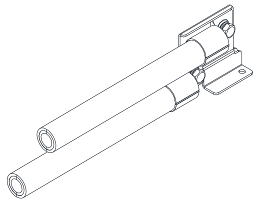
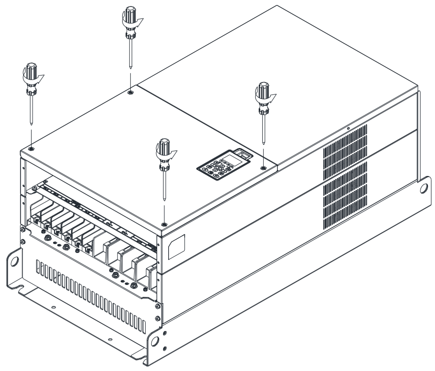


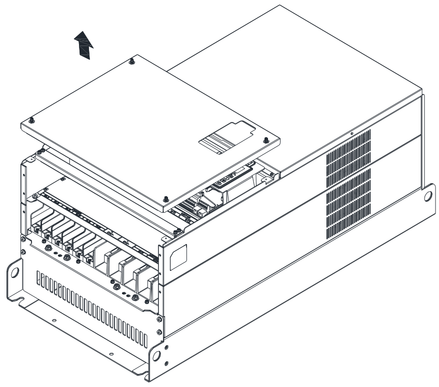
Diagram of power terminal connection
M12 Torque: 408 kg-cm / [354.1 lb-in] / [39.98 Nm]



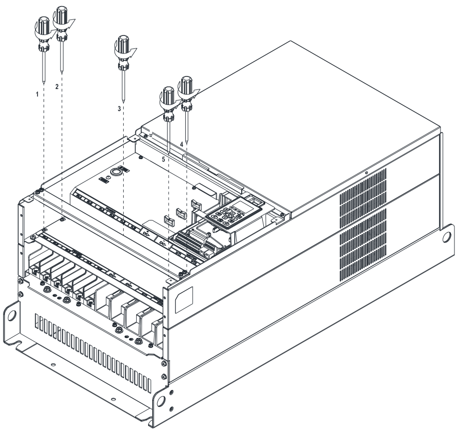
『MKC-PTCG』Installation

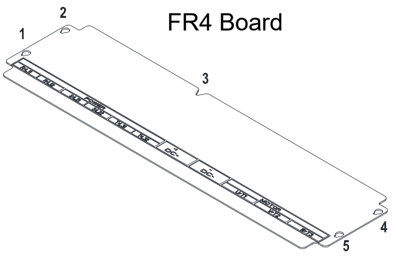
1. Loosen the 4 screws on the cover, as shown in the following figure. Screw Torque: 12–15 kg-cm / [10.4–13 lb-in] / [1.2–1.5 Nm]



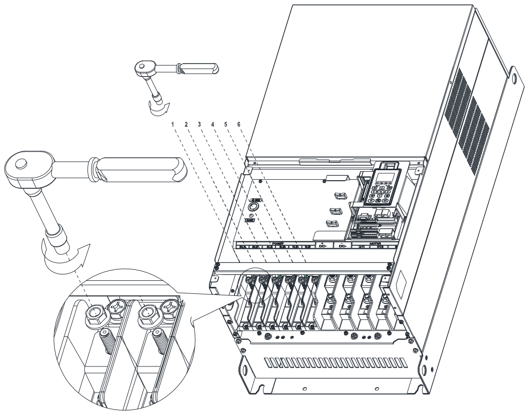


2. Remove the 5 screws from the FR4 board, as shown in the following figure. (The FR4 board is not needed after the installation of the power terminal kit). Screw Torque: 12–15 kg-cm / [10.4–13 lb-in] / [1.2–1.5 Nm]





3. Loosen the upper M8 nuts (1–6) with a sleeve wrench (12mm of the sleeve). M8 Torque: 90 kg / [78.1 lb-in] / [8.8 Nm]



4. Install the 3pcs copper assy., as shown in the following figure 1. Fasten the upper M8 nuts (1–6) with a sleeve wrench (12 mm of the sleeve), as shown in the figure 2 below.
   M8 Torque: 180 kg-cm / [156.2 lb-in] / [17.65 Nm]

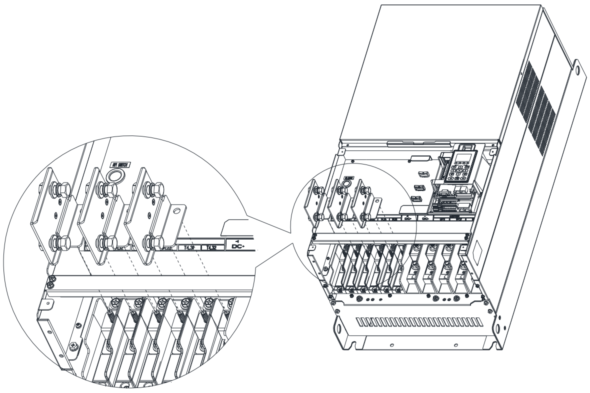


Figure 1

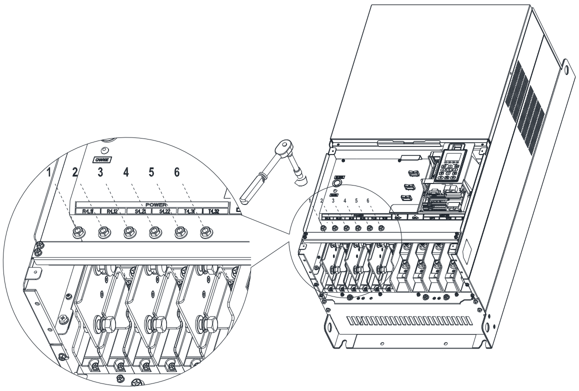
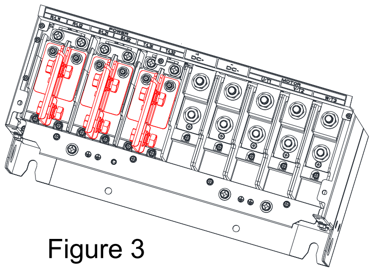


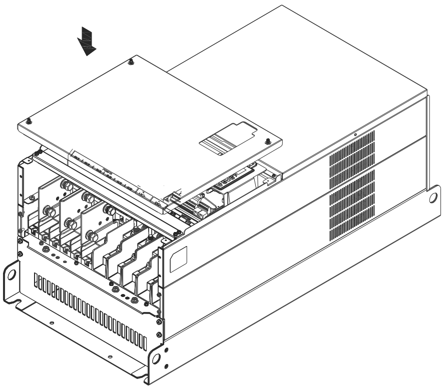
Figure 2

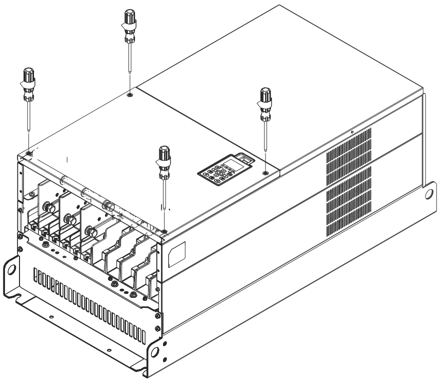


Copper Assy. Installation complete

Figure 3

5. Put the cover back and fasten the screws as shown in the figure below. Screw Torque: 12–15 kg-cm / [10.4–13 lb-in] / [1.2–1.5 Nm]





7-12 USB/RS-485 Communication Interface IFD6530

⚠ Warning

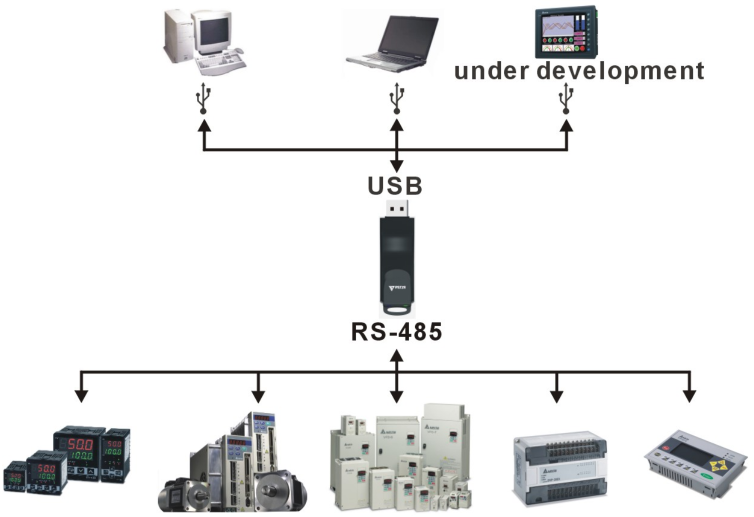
- ✓ *Please thoroughly read this instruction sheet before installation and putting it into use.*
- ✓ *The content of this instruction sheet and the driver file may be revised without prior notice. Please consult our distributors or download the most updated instruction/driver version.*

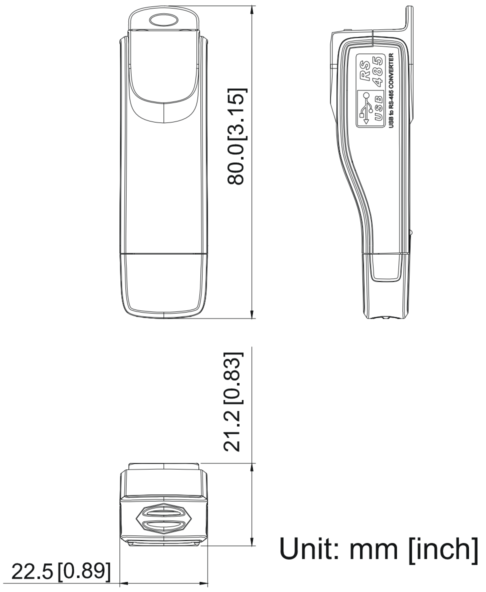
Introduction

IFD6530 is a convenient RS-485-to-USB converter, which does not require external power-supply and complex setting process. It supports baud rate from 75 to 115.2 kbps and auto switching direction of data transmission. In addition, it adopts RJ45 in RS-485 connector for users to wire conveniently. And its tiny dimension, handy use of plug-and-play and hot-swap provide more conveniences for connecting all DELTA IABG products to your PC.

Applicable Models: All DELTA IABG products.

(Application & Dimension)



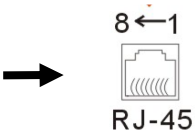


Specifications

Power supply	No external power is needed
Power consumption	1.5 W
Isolated voltage	2,500 V_{DC}
Baud rate	75 Kbps, 150 Kbps, 300 Kbps, 600 Kbps, 1,200 Kbps, 2,400 Kbps, 4,800 Kbps, 9,600 Kbps, 19,200 Kbps, 38,400 Kbps, 57,600 Kbps, 115,200 Kbps
RS-485 connector	RJ45
USB connector	A type (plug)
Compatibility	Full compliance with USB V2.0 specification
Max. cable length	RS-485 Communication Port: 100 m
Support RS-485 half-duplex transmission	

Figure 7-88

- **RJ45**



PIN	Description
1	Reserved
2	Reserved
3	GND
4	SG-

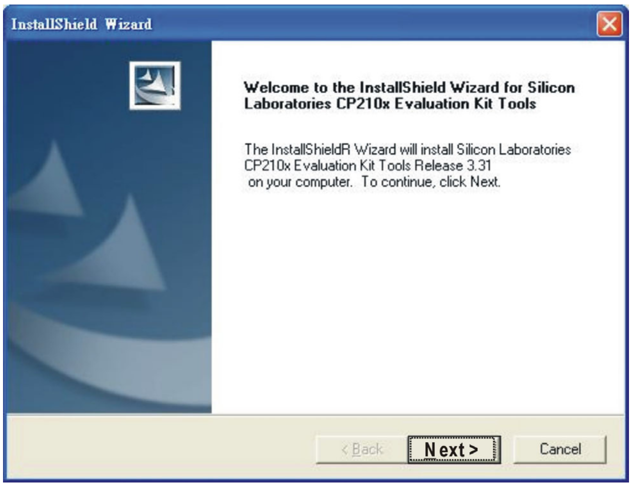
PIN	Description
5	SG+
6	GND
7	Reserved
8	+9V

Preparations before Driver Installation

Extract the driver file (IFD6530_Drivers.exe) by following steps. Download the driver file (IFD6530_Drivers.exe) at www.deltaww.com/iadownload_acmotordrive/IFD6530_Drivers.

NOTE DO NOT connect IFD6530 to PC before extracting the driver file.

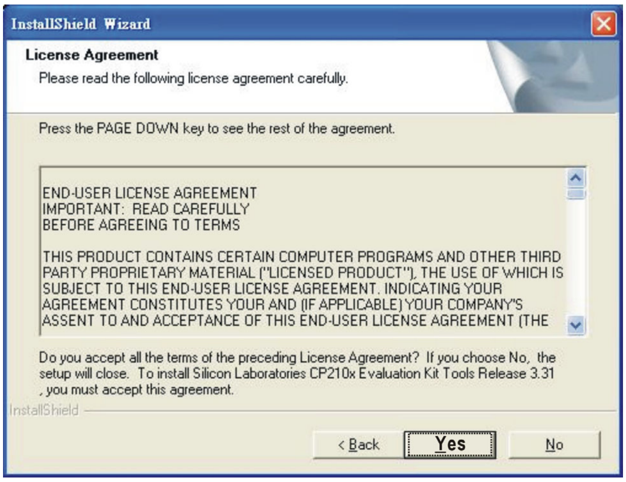
STEP 1



Welcome to the InstallShield Wizard for Silicon Laboratories CP210x Evaluation Kit Tools

The InstallShieldR Wizard will install Silicon Laboratories CP210x Evaluation Kit Tools Release 3.31 on your computer. To continue, click Next.

STEP 2



License Agreement

Please read the following license agreement carefully.

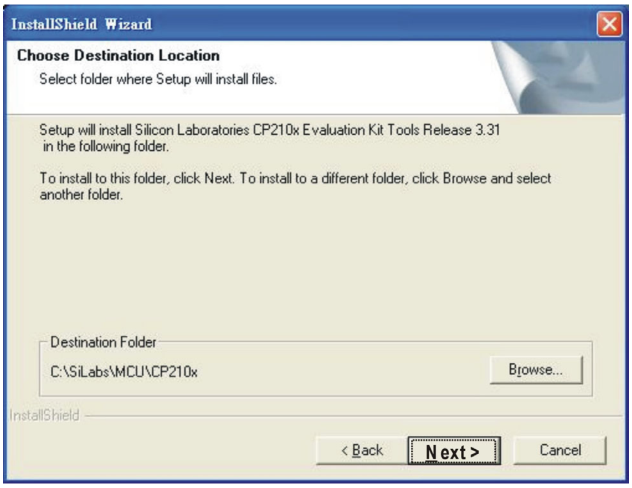
Press the PAGE DOWN key to see the rest of the agreement.

END-USER LICENSE AGREEMENT
IMPORTANT: READ CAREFULLY
BEFORE AGREEING TO TERMS

THIS PRODUCT CONTAINS CERTAIN COMPUTER PROGRAMS AND OTHER THIRD PARTY PROPRIETARY MATERIAL ("LICENSED PRODUCT"), THE USE OF WHICH IS SUBJECT TO THIS END-USER LICENSE AGREEMENT. INDICATING YOUR AGREEMENT CONSTITUTES YOUR AND (IF APPLICABLE) YOUR COMPANY'S ASSENT TO AND ACCEPTANCE OF THIS END-USER LICENSE AGREEMENT (THE

Do you accept all the terms of the preceding License Agreement? If you choose No, the setup will close. To install Silicon Laboratories CP210x Evaluation Kit Tools Release 3.31 , you must accept this agreement.

STEP 3



Choose Destination Location

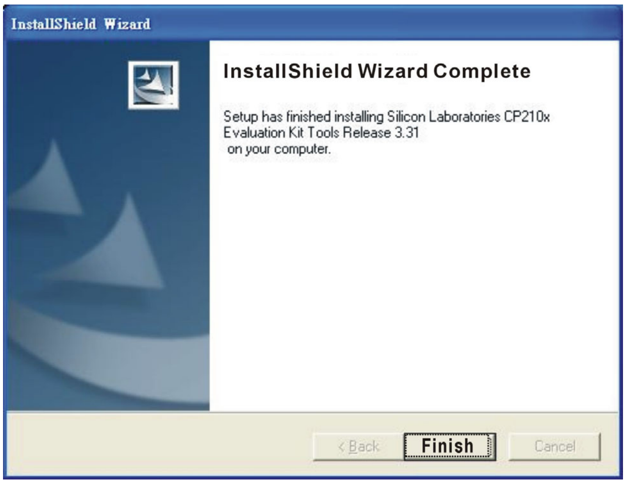
Select folder where Setup will install files.

Setup will install Silicon Laboratories CP210x Evaluation Kit Tools Release 3.31 in the following folder.

To install to this folder, click Next. To install to a different folder, click Browse and select another folder.

Destination Folder: C:\SiLabs\MCU\CP210x

STEP 4



InstallShield Wizard Complete

Setup has finished installing Silicon Laboratories CP210x Evaluation Kit Tools Release 3.31 on your computer.

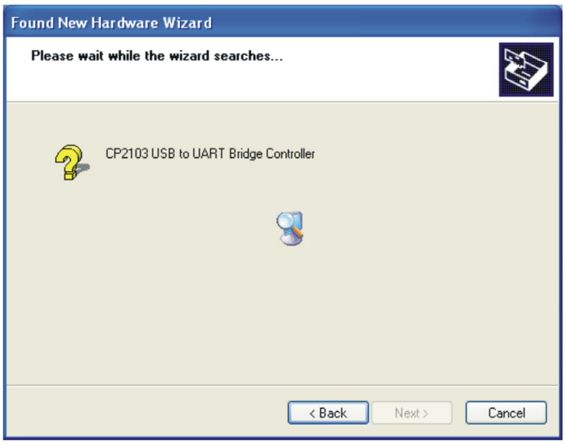
STEP 5

You should have a folder marked SiLabs under drive C. c:\ SiLabs

Driver Installation

After connecting IFD6530 to PC, please install driver by following steps.

STEP 3

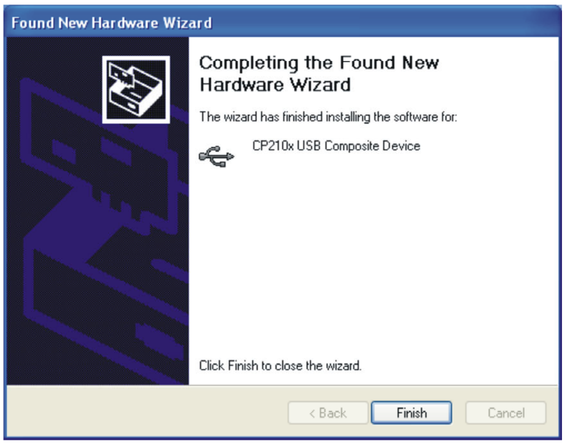


Found New Hardware Wizard

Please wait while the wizard searches...

CP2103 USB to UART Bridge Controller

STEP 4



Found New Hardware Wizard

Completing the Found New Hardware Wizard

The wizard has finished installing the software for:

CP210x USB Composite Device

Click Finish to close the wizard.

STEP 5
Repeat Step 1 to Step 4 to complete COM PORT setting.

LED Display

1. Steady Green LED ON: power is ON.
2. Blinking orange LED: data is transmitting.

Revision Record

If you need to contact the technical engineer of this product, please let them know the version of this user manual and firmware

Issue Edition: V02
Firmware Version: V2.03
Issue date:

Date	Page	Adding Content
2017/07/14	7-52	Table of Descriptions of LED Functions: Operation Direction LED under Torque Model
2017/07/14	7-67	Table of Appearance of the fan kit: Frame E_MKC-EFKM3 drawing and applicable model

Date	Page	Modify Content
2017/07/14	7-2	1. Modify the Min. Resistor Value and Max. Total Braking Current in 230V Brake Resistors and Brake Units Selection Chart 2. Adjust table format of the chart of 460V
2017/07/14	7-3	Modify unit presentation of the selection chart
2017/07/14	7-4	Modify Note 3 of 690V selection chart: Change the surface temperature of 400W resistor from 50℃ to 250℃
2017/07/14	7-6	1. Modify contents of point 2: Thermal Relay
2017/07/14	7-8	Complete the model number of 3-phase 690V chart
2017/07/14	7-9	Modify contents of the table: 1. 460V Model number: from VFD450CP43S-00/S-21 to VFD450CP43S-00/43S-21 2. Bussmann P/N of 460V Model VFD550CP43S-00/43S-21 (from JJS-225 to JJS-250)
2017/07/14	7-11~13, 25, 27, 29~31, 33~34, 36~37, 51~52, 55~58, 63~66, 69~81, 83, 86, 90, 91, 93 & 94	1. Adjust table format 2. Modify contents in the table
2017/07/14	7-18	Modify content of Column G1-DR006A0405: from 805mm to 80.5mm
2017/07/14	7-41	EMC Filter: change the Applicable EMC Filter of Model VFD6300CP63A-00 / VFD6300CP63A-21 (from B84143B0600S021 to B84143B1000S021)
2017/07/14	7-71	Update Fan Kit drawing of Frame B&C
2017/7/28	7-11~12	Chapter 7-4: 1. Update diagram of AC input reactor installation 2. Update 3% & 5% reactor spec. of 200V~230V and 380V~460V models. 3. Add notes in above spec. chart.
	7-23~24	Update the DC reactor spec. of 200V~230V and 380C~460V models Add notes in above spec. chart.
	7-26	Remove column “Built-in DC reactor, and without adding input AC/DC reactor” from chart of Spec. of THDi
	7-27~28	AC output reactor: Update the reactor spec. and corresponded Delta part number of 200V~230V & 380V~460V models
2017/8/17	7-2~7-3	Update resistor spec. of 230V and 460V models
2017/8/24	7-65	Revise fan kit model for Frame A, applicable model VFD075CP43B/4EB-21, from MKC-AFKM2 to MKCB-AFKM2
	7-69	Revise fan kit model for Frame A, applicable model VFD075CP43B/4EB-21, from MKC-AFKM2 to MKCB-AFKM2

2017/8/31	7-2	Update the Brake Resistors and Brake Units Selection Chart
	7-4	Update note 3 and note 4
	7-6	Update diagram of Thermal Relay
	7-23	DC reactor, update installation terminal: change from “terminal +1 and +2” to “terminal +2/DC+ and +1/DC+” Update diagram of “Wiring of DC reactor”
	7-32	Update diagram of “tr definition”
	7-40	Update the EMC filter spec. chart.
2017/9/5	7-29	Remove heavy load from 575V/690V spec.
	7-67	Update fan drawing of Frame A MKC-AFKM Add new column for Frame A MKC-AFKM2, add new fan drawing Adjust format of Frame B
	7-68	Update applicable model for Frame D, change VFD750CP43A-00/21 to VFD750CP43B-00/21
	7-69	Update applicable model for Frame E, add VFD550CP23A-00/21 and VFD750CP23A-00/21
	7-70	Add explanation for applicable models of Frame H: Below models use two MKC-HFKM fans
	7-82	Update drawing of Frame A
	7-86	Update drawing of Frame B
	7-88	Update/add drawing of Frame C
2017/9/7	7-31	Suggested motor shielding cable length, model 007, normal load of rated current, change the cable length from 2.8 to 1.7
2017/9/10	7-10	Add note 3: Short-circuit current rating (SCCR): Per UL508C, the drive is suitable for use on a circuit capable of delivering not more than 100kA symmetrical amperes (rms) when protected by fuses given in the fuse table.
2017/11/23	7-67~72	Add installation description to the Frame H conduit box.

Issue Edition: V03
Firmware Version: V2.06

日期	頁碼	修正資訊
2019/6/5	7-3	註記*2 工作時間與 ED vs.煞車電流之關係，改成參考 “台達官網應用手冊”制動模組與制動電阻”章節。”；煞車電流改為制動電流
		註記*3 與*4 順序對調，原*4 中 1000W 以上之電阻，表面溫度需低於 600°C 改為 350°C
	7-5	更新圖 7-5（調整 XY 軸單位字型及位置）
	7-6	說明”無熔絲開關的電流額定必須介於 1.6~2.6 倍”後面加註（575V/690V 機種為 2~4 倍）
	7-8	刪除說明”短路電流額定值(SCCR)：依據 UL508C，搭配保險絲適用於短路容量 100kA 以下之電源系統。”
	7-10	更新輸入 AC 電抗器安裝示意圖（圖 7-6）
	7-xx	刪除章節 7-7 數位操作器
	7-49	適用於數位操作器（KPC-CC01 與 KPC-CE01），刪除 KPC-CE01 更新平盤安裝示意圖（刪除 KPC-CE01）
	7-50	更新凸盤安裝及平盤安裝示意圖（刪除 KPC-CE01）
	7-53	框號 H 適用機種增加 VFD5600CP43A-00; VFD6300CP43A-00; VFD5600CP43C-21; VFD6300CP43C-21
	7-70	框號 C 風扇增加”散熱片風扇型號 MKC-CFKM1”、”電容風扇型號

日期	頁碼	修正資訊
		MKC-CFKB3”及其適用機種
	7-72	更新框號G風扇MKC-GFKM圖面
		框號H風扇MKC-HFKM適用機種增加VFD5600CP43A-00；VFD5600CP43C-21；VFD6300CP43A-00；VFD6300CP43C-21
	7-71	更正框號E適用機種VFD1320CP43A-00, VFD1320CP43A-21為VFD1320CP43B-00, VFD1320CP43B-21
	7-73	框號H風扇MKC-HFKM1適用機種分列為使用兩顆風扇及使用三顆風扇
	7-80	更新風扇MKC-FFKB拆裝說明步驟2~4圖示
	7-81	更新風扇MKC-GFKM拆裝說明步驟2~5圖示，增加步驟6~7
	7-82	更新風扇MKC-HFKM拆裝說明及步驟2~4圖示
		適用機種增加VFD5600CP43A-00; VFD5600CP43C-21; VFD6300CP43A-00; VFD6300CP43C-21
	7-83	新增使用兩顆風扇MKC-HFKM1拆裝說明
	7-84	新增使用三顆風扇MKC-HFKM1拆裝說明
	7-95	刪除框號D適用機種VFD450CP43A-00; VFD450CP43A-21; VFD550CP43A-00; VFD550CP43A-21
	7-100~101	新增章節7-11 電源端子轉接板安裝說明
	7-102	將RS485改為RS-485；RJ-45改為RJ45；單位VDC改為V_{DC}
	7-1	目錄刪除7-7數位操作器，並新增7-11電源端子轉接板安裝；調整章節編碼
	7-6	新增VFD5600CP43A-00/43C-21及VFD6300CP43A-00/43C-21之無熔絲開關建議使用電流
	7-8	新增VFD5600CP43A-00/43C-21及VFD6300CP43A-00/43C-21之保險絲規格
	7-11	新增VFD5600CP43A-00/43C-21及VFD6300CP43A-00/43C-21之AC輸入電抗器規格-額定電流
	7-29	新增560, 630kW機種之馬達配線長度限制規格-額定電流
	7-26	新增VFD5600CP43A-00/43C-21及VFD6300CP43A-00/43C-21之AC輸出電抗器規格-額定電流
	7-33	新增560, 630kW機種之正弦波濾波器建議規格-額定電流
	7-35	零相電抗器增加新型號尺寸圖及尺寸資訊
		適用變頻器機種列表中，增加零相電抗器之型號
	7-37	460V增加VFD5600CP43A-00, VFD5600CP43C-21, VFD6300CP43A-00, VFD6300CP43C-21之EMC濾波器型號及資訊
	7-46	增加EMC濾波器B84143B1600S020圖面
	7-11~12	增加560, 630kW機種搭配之電抗器規格 註2增加“建議增加風冷”
	7-13	更新AC輸入電抗器外觀圖示與規格

日期	頁碼	修正資訊
	7-13~29	更新 AC 輸入電抗器外觀圖示與規格（宗男 2019/4/19 提供）
	7-31	更新 DC 電抗器外觀圖示與規格（宗男 2019/4/19 提供）
	7-33	THDi 規格表增加”無加裝輸入 AC 電抗器”欄位
		更新 AC 輸出電抗器安裝方式示意圖
	7-35	新增 460V 560, 630kW 機種之 AC 輸出電抗器型號及規格（宗男 2019/4/19 提供）
	7-37~45	新增 AC 輸出電抗器外觀圖示及規格（宗男 2019/4/19 提供）
	7-47	新增 460V 560, 630kW 機種之馬達配線長度（宗男 2019/4/29 提供）
	7-51	新增 460V 560, 630kW 機種之正弦波濾波器建議規格(宗男 2019/4/29 提供）
	7-56	新增 460V EMC 濾波器評價表格（紀宏 2019/4/26 提供）
	7-xx	調整圖片及表格編碼
	7-2	補上新增 560, 630kW 機種對應之制動電阻規格
	7-6~7	新增電磁接觸器/空氣斷路器選型表
2019/6/20	7-6~7-7	230V 系列新增框號 A~C 的 MC/ACB 選型；460V 系列新增框號 A~D0 的 MC/ACB 選型
	7-10~11	調整表格欄寬
2019/6/24	7-37	更新 AC 輸出電抗器之說明（Ref. mail C2000 使用手冊_章節 7-4_AC / DC 電抗器 Aly 20190401）
2019/06/25	7-35~36	新增 575V/690V DC 電抗器規格表
2019/6/26	7-122	新增下載驅動程式之超連結，並刪除原本所列網址
	7-123	將驅動程式安裝說明中的 “隨機所附 CD” 改為官網下載短網址
	7-5	加上 Braking Modules Instruction Sheet 下載連結
2019/7/11	7-80	更新框號 E 管線盒拆裝示意圖（移除通風孔）
	7-82~83	更新框號 G 管線盒拆裝示意圖（移除通風孔）
	7-101	更新框號 E 風扇拆裝示意圖（移除通風孔）
	7-102	更新風扇 MKC-FFKM 拆裝步驟 1 螺絲扭力值
		更新風扇 MKC-FFKB 拆裝步驟 3 螺絲扭力值
	7-103	更新框號 G 風扇拆裝示意圖（移除通風孔）
2020/7/14	7-12	保險絲規格 KYU-1000 改為 KTU-1000（mail: 【手冊校稿】CP2000_V2.07_手冊 V01_Mario_20200713）
2020/7/23	7-43~46	輸出電抗器規格表中，電抗器料號欄位名稱 “Input AC reactor” 更正為 “Output AC reactor”
2020/7/29	7-63~65	更新零相電抗器型號（mail: 【手冊校稿】CP2000_V2.07_手冊 V01_20200729）

Chapter 8 Option Cards

8-1 Option Card Installation

8-2 EMC-D42A -- Extension card for 4-point digital input / 2-point digital input

8-3 EMC-D611A -- Extension card for 6-point digital input (110V_{AC} input voltage)

8-4 EMC-R6AA -- Relay output extension card (6-point N.O. output contact)

8-5 EMC-BPS01 -- +24V power card

8-6 EMC-A22A -- Extension card for 2-point analog input / 2-point analog output

8-7 CMC-PD01 -- Communication card, PROFIBUS DP

8-8 CMC-DN01 -- Communication card, DeviceNet

8-9 CMC-EIP01 -- Communication card, EtherNet/IP

8-10 CMC-PN01 -- Communication card, PROFINET

8-11 eZVFD-CC -- Communication card, BACnet Ethernet / BACnet IP

8-12 EMC-COP01 -- Communication card, CANopen

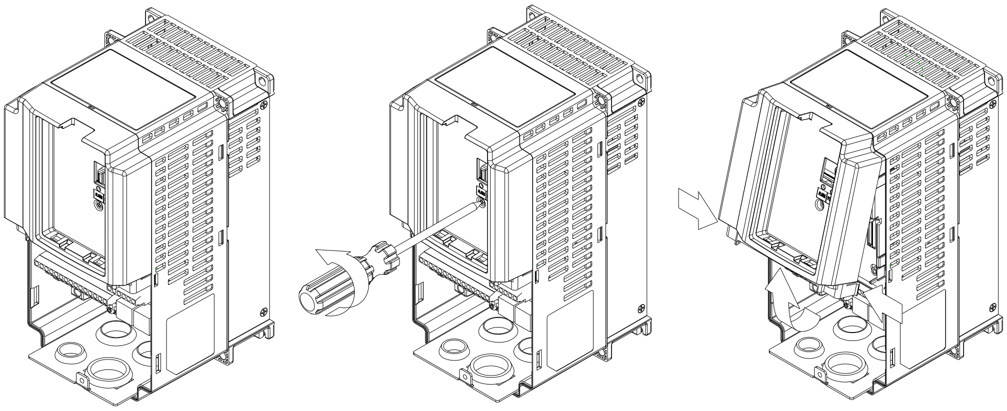
8-13 Delta Standard Fieldbus Cables

- Select applicable option cards for your drive or contact local distributor for suggestion.
- To prevent damage to the drive during installation, remove the digital keypad and the cover before wiring. Refer to the following instruction.
- The option card does not support hot swap function. Turn the power off before installing or removing the option card.

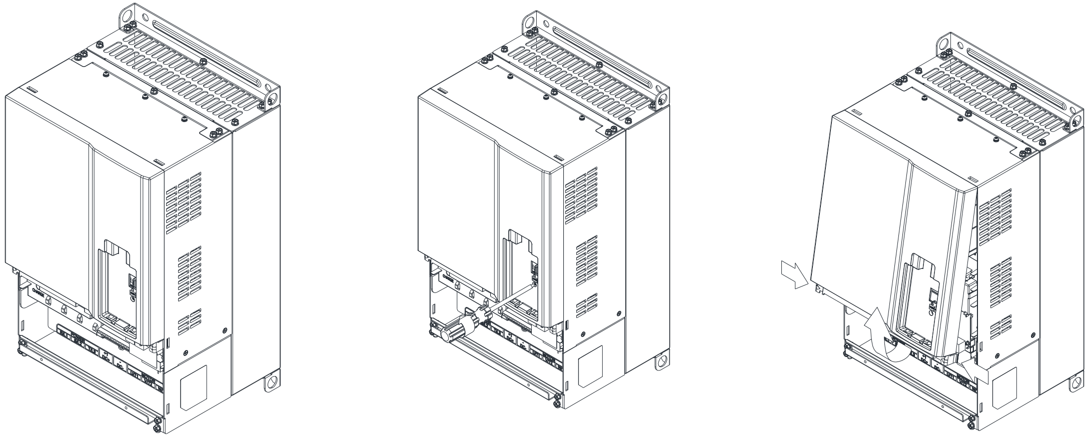
8-1 Option Card Installation

8-1-1 Remove the top cover

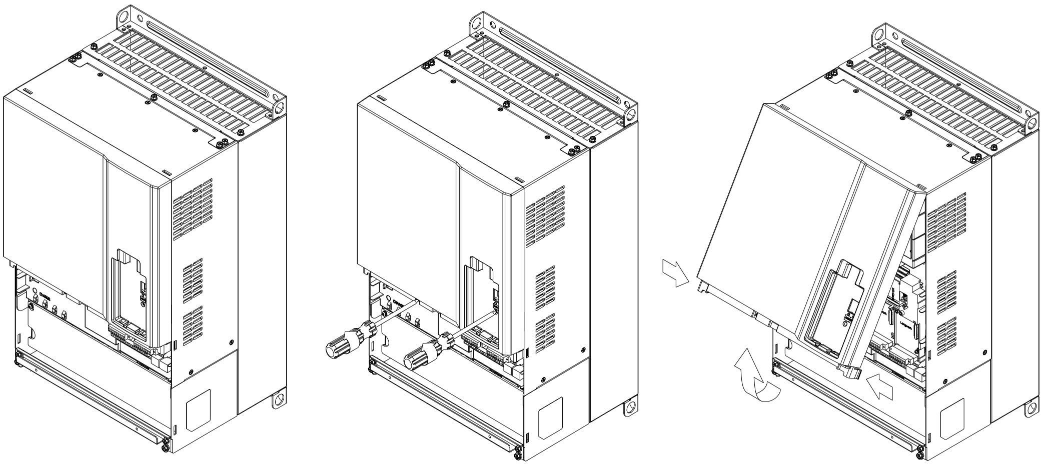
Frame A–C
Screw Torque: 8–10 kg-cm / [6.9–8.7 lb-in.] / [0.8–1.0 Nm]



Frame D0
Screw Torque: 8–10 kg-cm / [6.9–8.7 lb-in.] / [0.8–1.0 Nm]

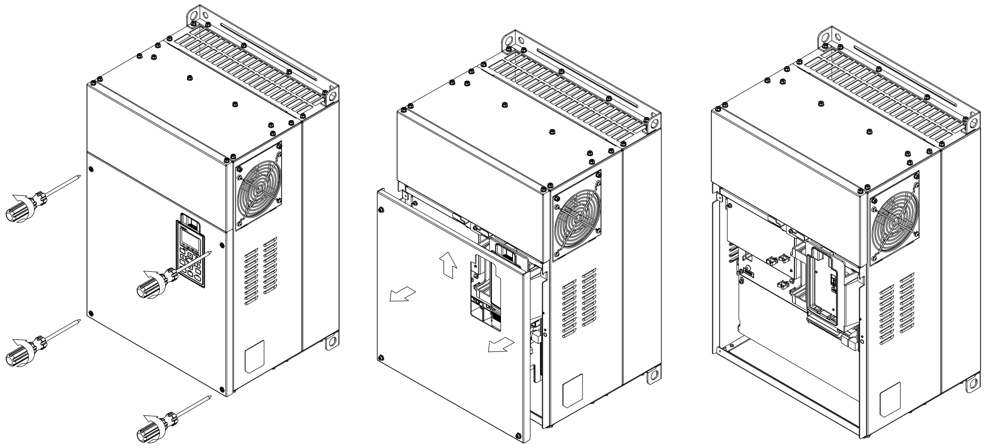


Frame D
Screw Torque: 8–10 kg-cm / [6.9–8.7 lb-in.] / [0.8–1.0 Nm]



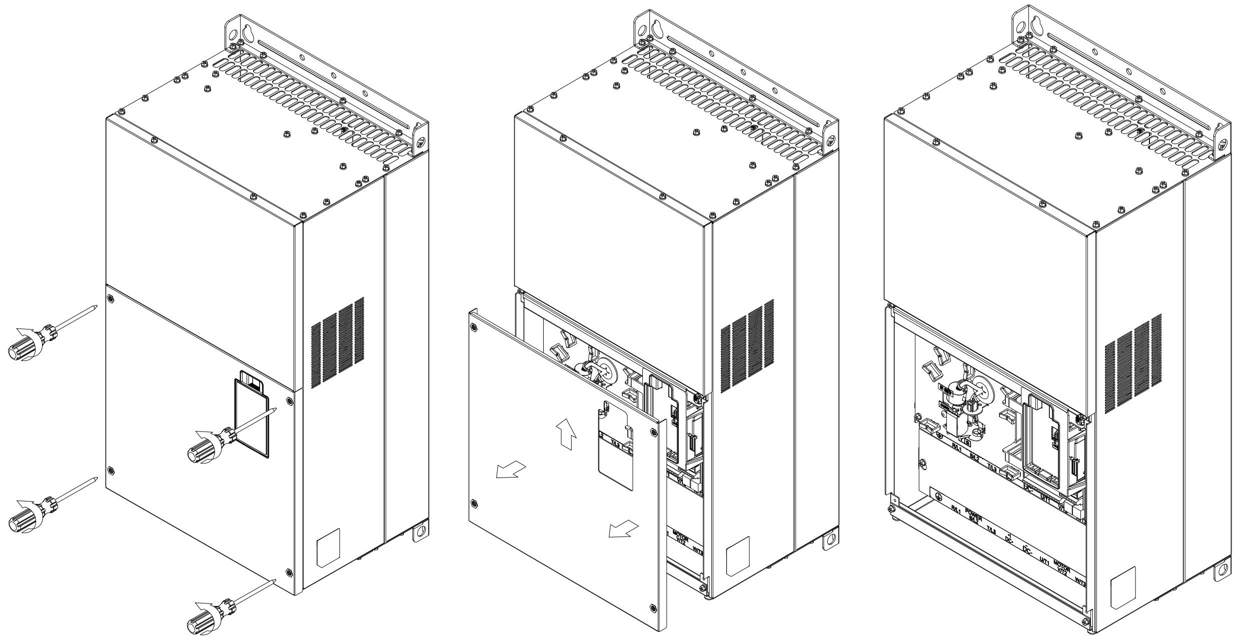
Frame E

Screw Torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



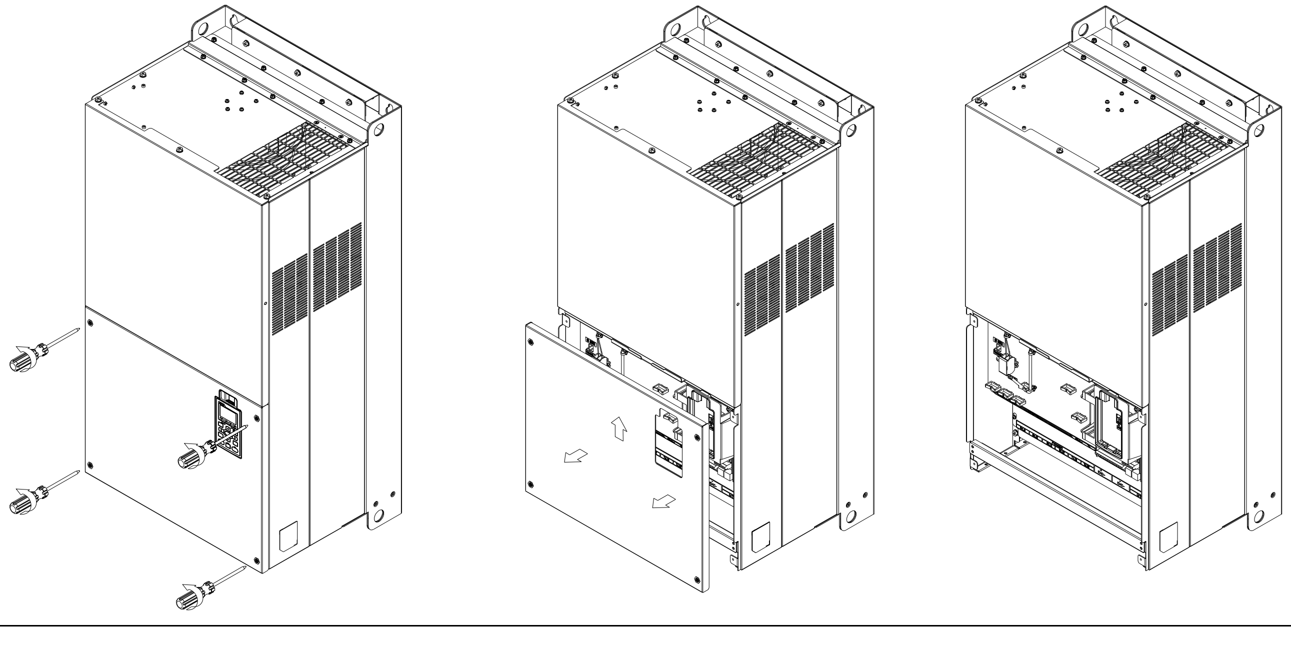
Frame F

Screw Torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]

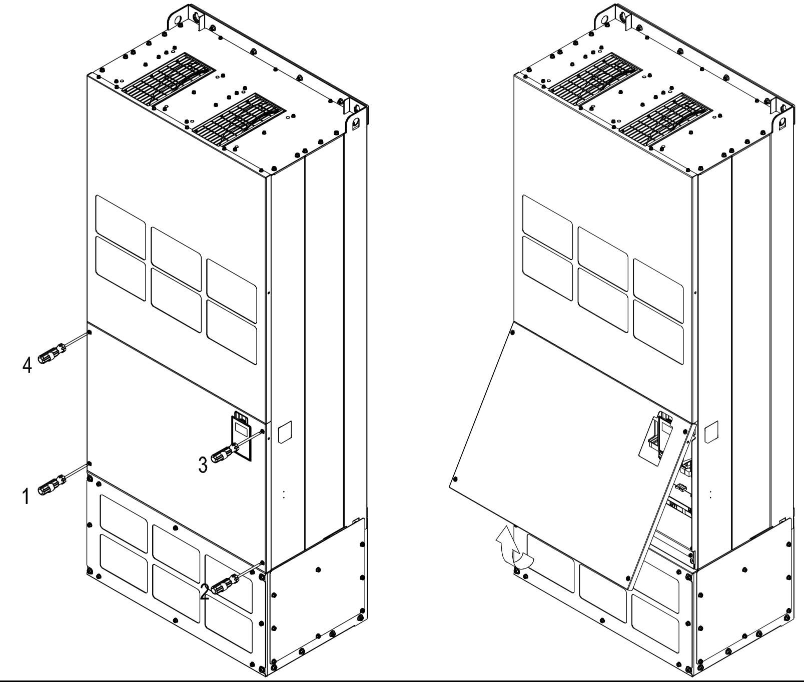


Frame G

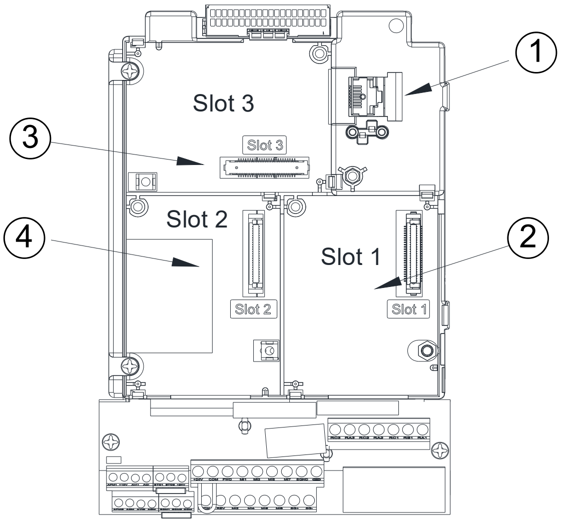
Screw Torque: 12–15 kg-cm / [10.4–13 Ib-in.] / [1.2–1.5 Nm]



Frame H
Screw Torque: 14–16 kg-cm / [12.15–13.89 lb-in.] / [1.4–1.6 Nm]



8-1-2 Option Card Installation Location



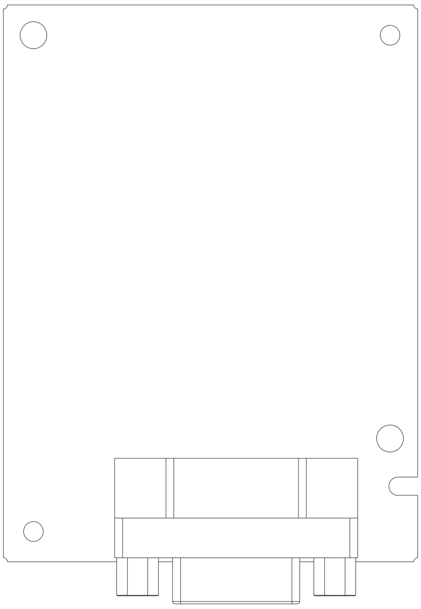
1	RJ45 (Socket) for digital keypad KPC-CC01 Refer to Section 10 for more details on digital keypad. Refer to Section 10 for more details on optional accessory RJ45 extension cable.
2	Communication extension card (Slot 1) CMC-PD01; CMC-DN01; CMC-EIP01; EMC-COP01; CMC-PN01
3	I/O & Relay extension card (Slot 3) EMC-D42A; EMC-D611A; EMC-A22A; EMC-R6AA; EMC-BPS01
4	PG Card (Slot 2) ※CP2000 do not support PG card.

Screws Specification for optional card terminals:

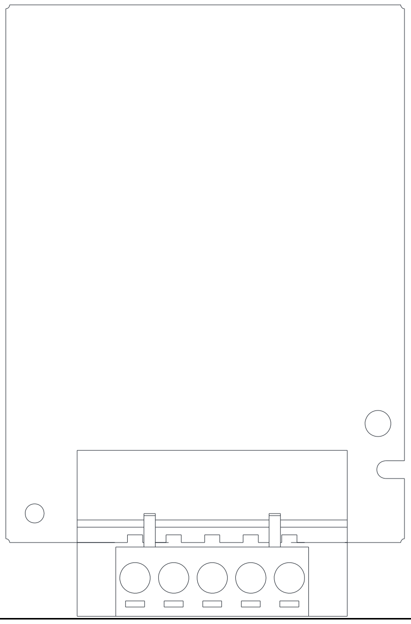
EMC-D42A; EMC-D611A; EMC-BPS01	Wire gauge	0.2–0.5 mm^2 [26–20 AWG]
	Torque	5 kg-cm / [4.4 lb-in.] / [0.5 Nm]
EMC-R6AA	Wire gauge	0.2–0.5 mm^2 [26–20 AWG]
	Torque	8 kg-cm / [7 lb-in.] / [0.8 Nm]
EMC-A22A	Wire gauge	0.2–4 mm^2 [24–12 AWG]
	Torque	5 kg-cm / [4.4 lb-in] / [0.5 Nm]

Communication extension card (Slot 1)

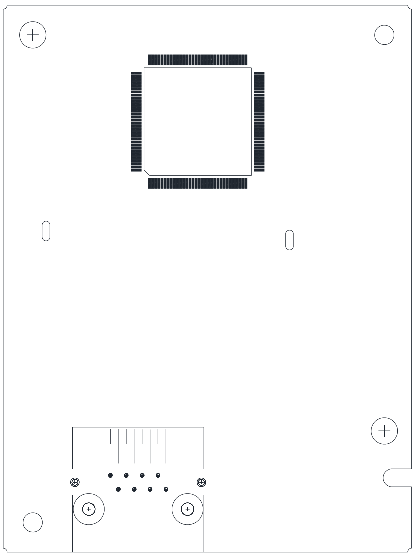
CMC-PD01



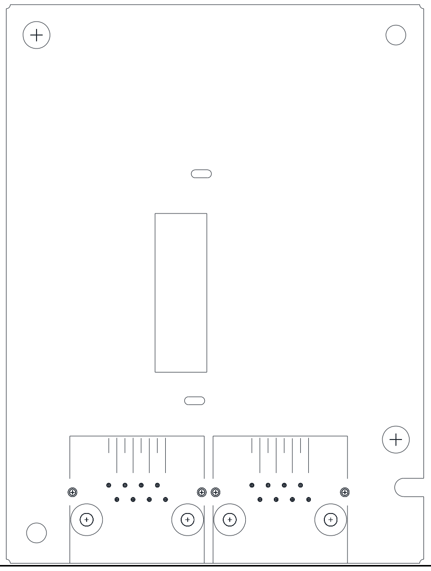
CMC-DN01



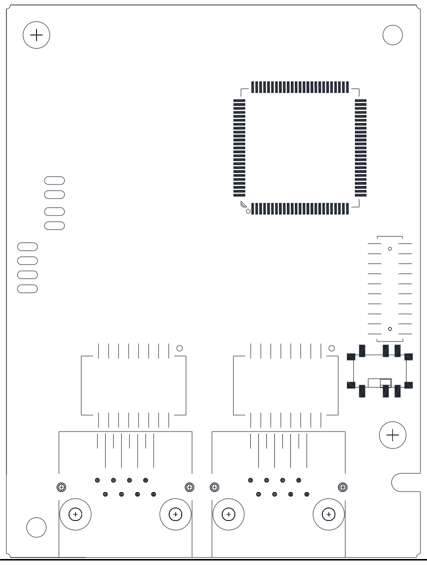
CMC-EIP01



EMC-COP01

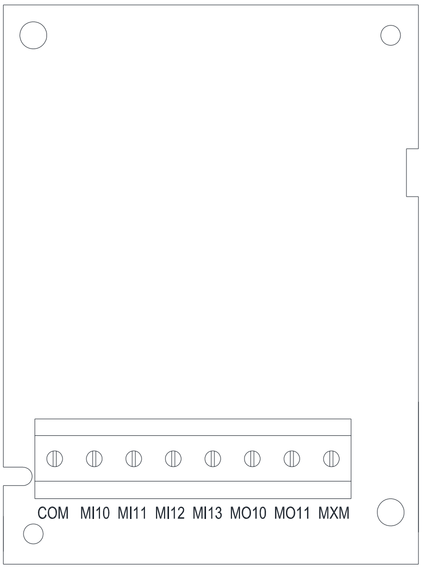


CMC-PN01

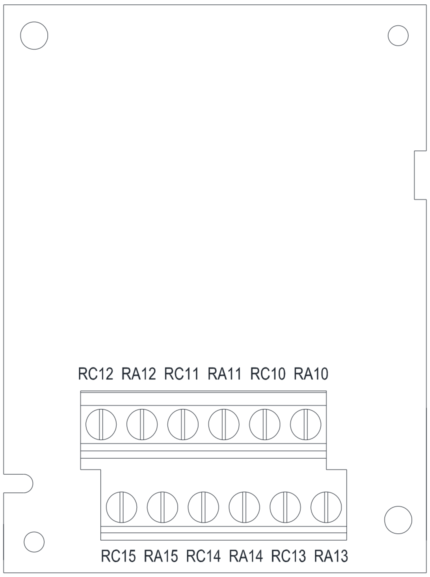


I/O / Relay extension card & 24V Power extension card (Slot 3)

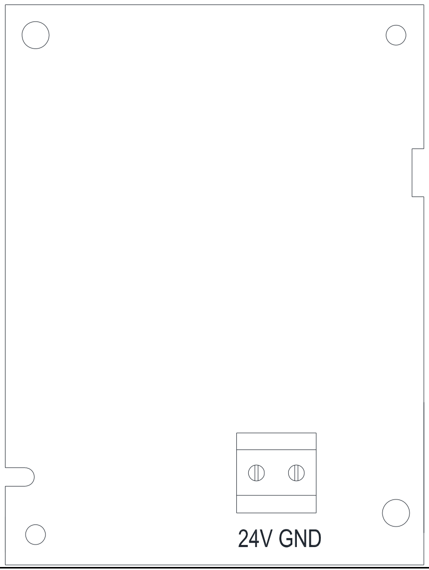
EMC-D42A



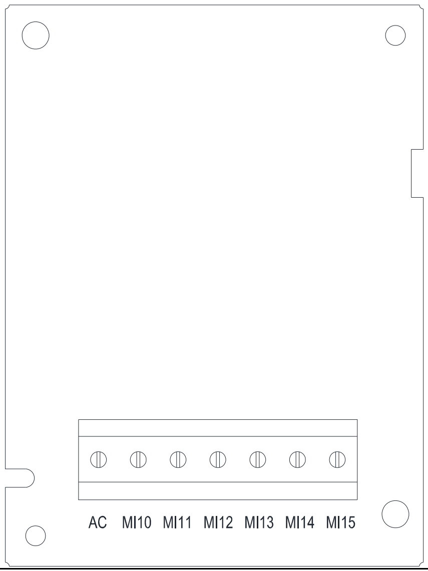
EMC-R6AA



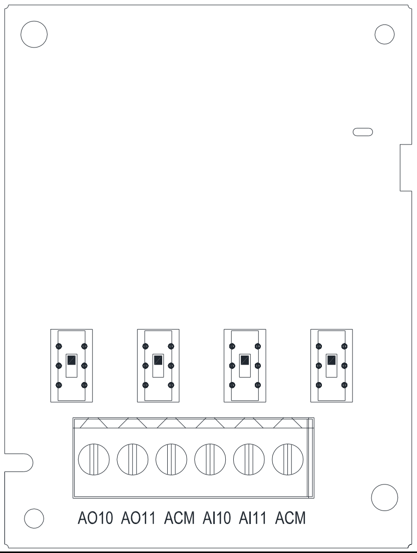
EMC-BPS01



EMC-D611A



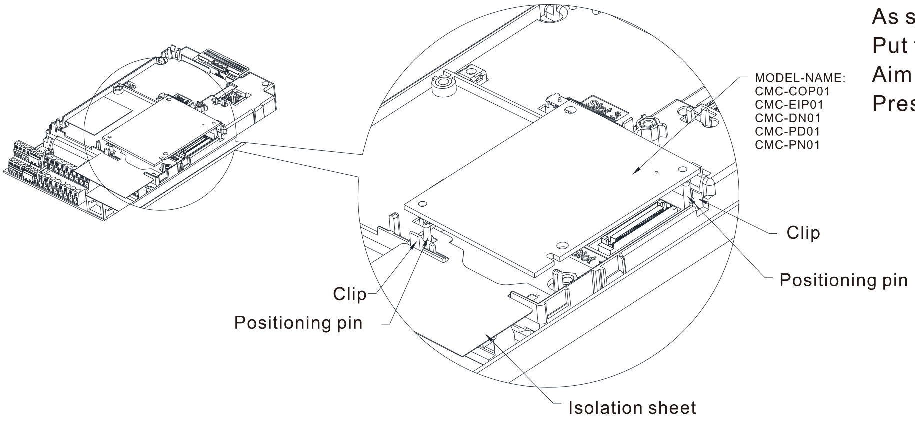
EMC-A22A



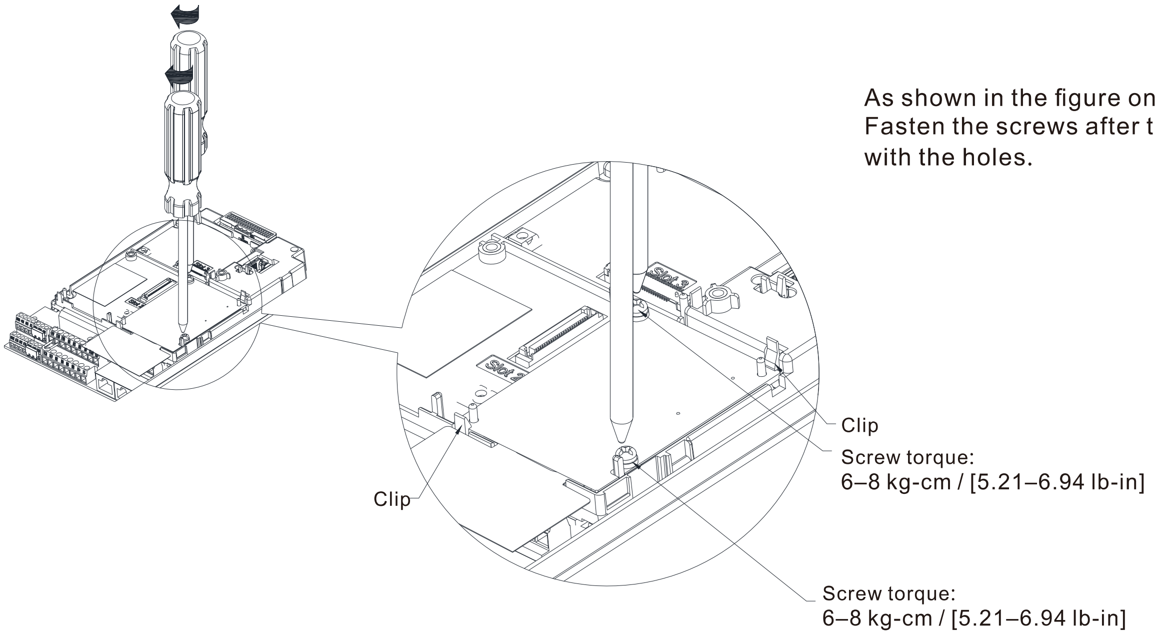
8-1-3 Install and Uninstall of Extension Cards

8-1-3-1 Installation

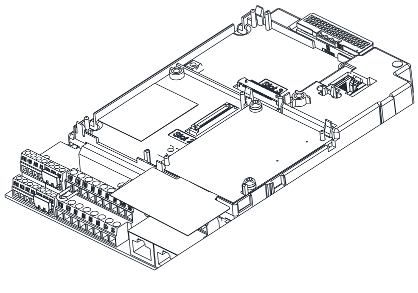
Communication card: EMC-COP01, CMC-EIP01, CMC-DN01, CMC-PD01, CMC-PN01

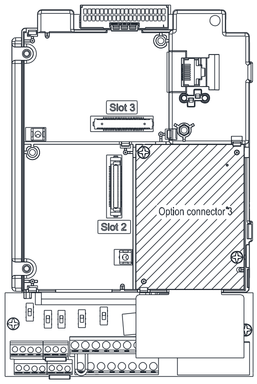


As shown in the figure on the left.
Put the isolation sheet into the positioning pin.
Aim the two holes at the positioning pin.
Press the pin to clip the holes with the PCB.



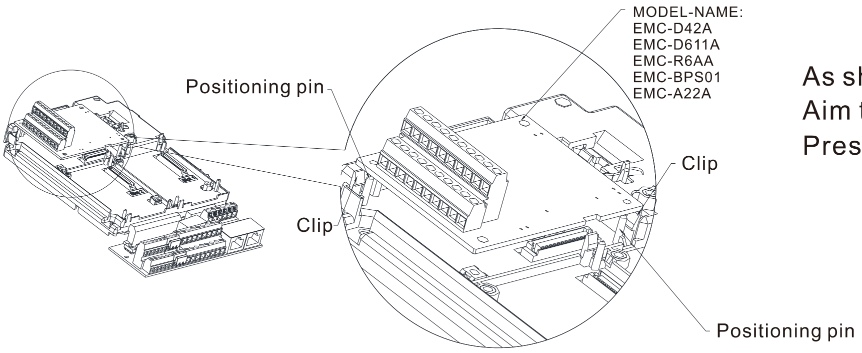
As shown in the figure on the left.
Fasten the screws after the PCB is clipped with the holes.



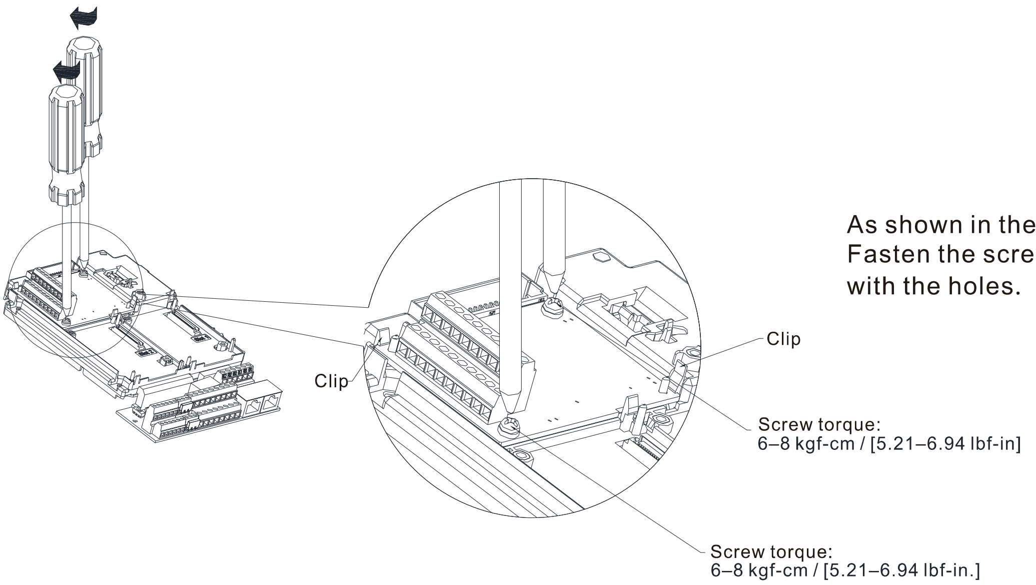


As shown in the figure on the left, installation is completed.

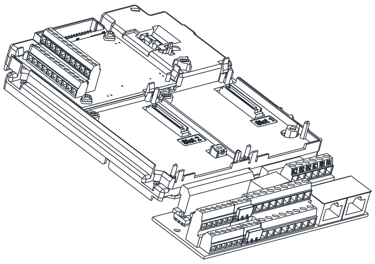
I/O & Relay Card: EMC-D42A, EMC-D611A, EMC-R6AA, EMC-BPS01, EMC-A22A

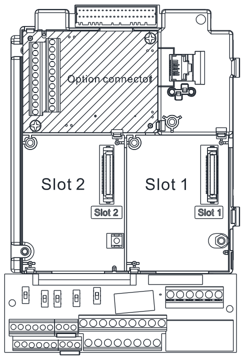


As shown in the figure on the left.
Aim the two holes at the positioning pin.
Press the pin to clip the holes with the PCB.


Clip
Clip
Screw torque:
6–8 kgf-cm / [5.21–6.94 lbf-in]
Screw torque:
6–8 kgf-cm / [5.21–6.94 lbf-in.]

As shown in the figure on the left.
Fasten the screws after the PCB is clipped with the holes.

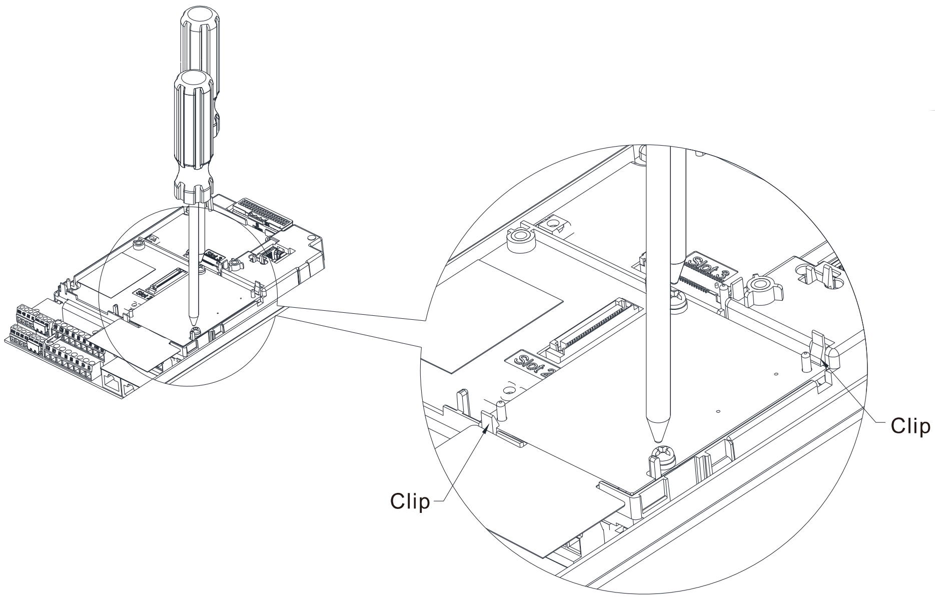




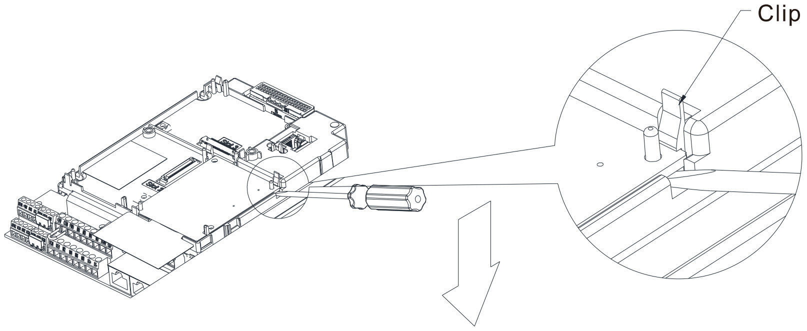
As shown in the figure on the left, installation is completed.

8-1-3-2 Disconnect the extension card

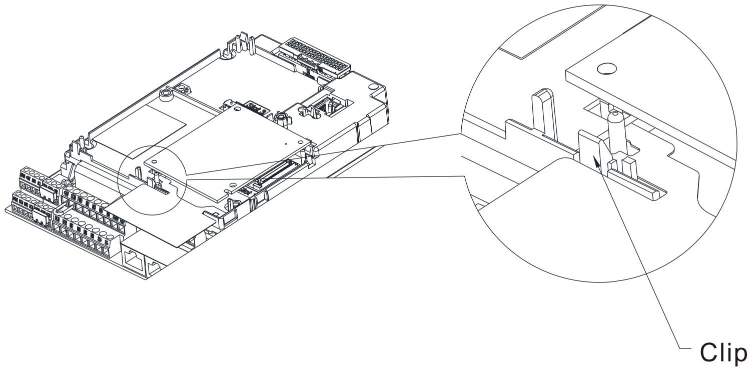
Communication Card: EMC-COP01, CMC-EIP01, CMC-DN01, CMC-PD01, CMC-PN01



Remove the two screws as shown in the figure on the left.

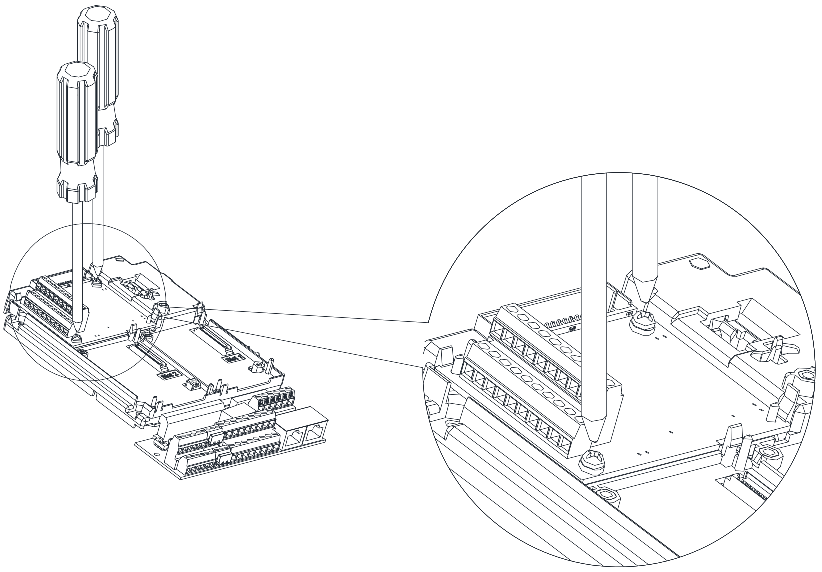


As shown in the figure on the left.
Twist to open the clip.
Insert a slot type screwdriver into the hollow to prize the PCB off the clip.

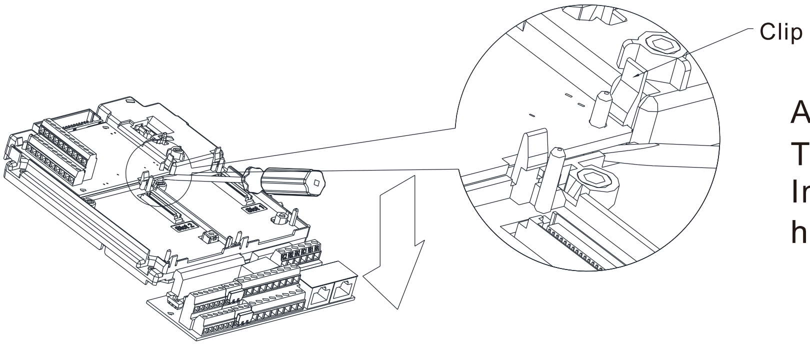


Twist to open the other clip to remove the PCB.

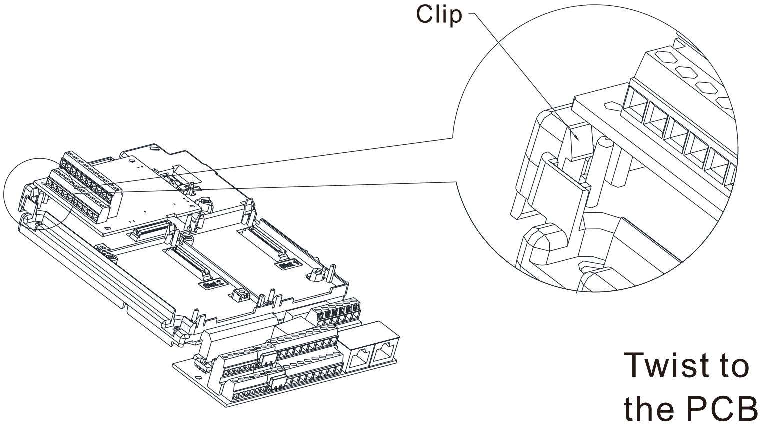
I/O & Relay Card: EMC-D42A, EMC-D611A, EMC-R6AA, EMC-BPS01, EMC-A22A



Remove the two screws as shown in the figure on the left.

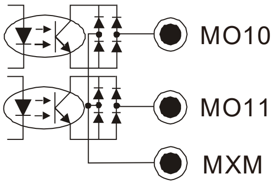


As shown in the figure on the left.
Twist to open the clip.
Insert a slot type screwdriver into the hollow to prize the PCB off the clip.



Twist to open the other clip to remove the PCB, as shown in the figure on the left.

8-2 EMC-D42A -- Extension card for 4-point digital input / 2-point digital input

	Terminals	Descriptions
I/O Extension Card	COM	Common for Multi-function input terminals Select SINK (NPN) / SOURCE (PNP) in J1 jumper / external power supply
	MI10–MI13	Refer to Pr.02-26–Pr.02-29 to program the multi-function inputs MI10–MI13. Internal power is applied from terminal E24: +24 V_{DC} ± 5% 200 mA, 5 W External power +24 V_{DC}: max. voltage 30 V_{DC}, min. voltage 19 V_{DC} ON: the activation current is 6.0 mA OFF: leakage current tolerance is 10 μA
	MO10–MO11	Multi-function output terminals (photocoupler) The AC motor drive releases various monitor signals, such as drive in operation, frequency attained and overload indication, via transistor (open collector). 
	MXM	Common for multi-function output terminals MO10, MO11 (photo coupler) Max 48 V_{DC} 50 mA

8-3 EMC-D611A -- Extension card for 6-point digital input (110V_{AC} input voltage)

	Terminals	Descriptions
I/O Extension Card	AC	AC power Common for multi-function input terminal (Neutral)
	MI10–MI15	Refer to Pr.02-26–Pr.02-31 for multi-function input selection Input voltage: 100–130 V_{AC} Input frequency: 47–63 Hz Input impedance: 27 kΩ Terminal response time: ON: 10 ms OFF: 20 ms

8-4 EMC-R6AA

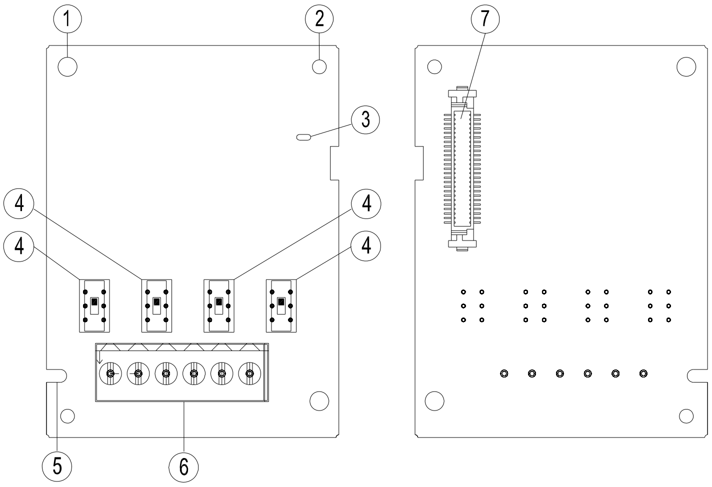
	Terminals	Descriptions
Relay Extension Card	RA10–RA15 RC10–RC15	Refer to Pr.02-36–Pr.02-41 for multi-function relay selection Resistive load: 3 A (N.O.) / 250 V_{AC} 5 A (N.O.) / 30 V_{DC} Inductive load (COS 0.4) 1.2 A (N.O.) / 250 V_{AC} 2.0 A (N.O.) / 30 V_{DC} It is used to output each monitor signal, such as drive is in operation, frequency attained or overload indication.

8-5 EMC-BPS01 -- +24V power card

	Terminals	Descriptions
External Power Supply	24V GND	Input power: 24 V ± 5% Maximum input current: 0.5 A Note: Do not connect drive control terminal GND directly to the EMC-BPS01 input terminal GND.
		Function: When the drive is only powered by EMC-BPS01, the communication can be assured and support all communication cards and following functions: Parameters read and write Keypad can be displayed Keypad button can be operated (except RUN) Analog input is effective Multi-input (FWD, REV, MI1–MI8) needs external power supply to operate Following functions are not supported： Relay output (including extension card), PG card, PLC function

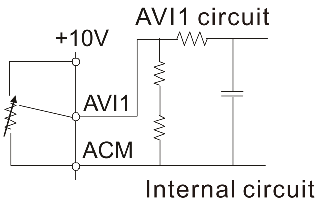
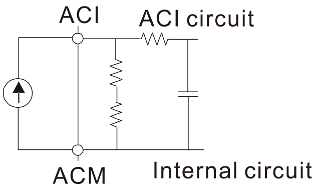
8-6 EMC-A22A -- Extension card for 2-point analog input / 2-point analog output

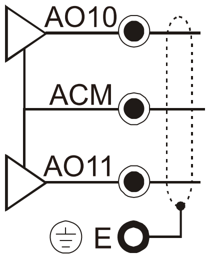
8-6-1 Product File



1. Screw fixing hole
2. Positioning hole
3. POWER indicator
4. Switch
5. Fool-proof groove
6. Terminal block
7. AC motor drive connection port

8-6-2 Terminal Specification

<table>
<tr><td rowspan="5">Analog I/O
Extension Card</td><td>Terminals</td><td colspan="2">Descriptions</td></tr>
<tr><td rowspan="3">AI10, AI11</td><td colspan="2">Refer to Pr.14-00–Pr.14-01 for function selection (input), and Pr.14-18–Pr.14-19 for mode selection.
There are two sets of AI port, SSW3 (AI10) and SSW4 (AI11), which can be switched to Voltage or Current mode.
Voltage mode: Input 0–10 V
Current mode: Input 0–20 mA / 4–20 mA</td></tr>
<tr><td>Analog voltage frequency command
 </td><td>Impedance: 20 kΩ
Range: 0–10 V = 0–Max. Output Frequency (Pr.01-00)
Switch: AI10 / AI11 Switch, default 0–10 V</td></tr>
<tr><td>Analog current frequency command
 </td><td>Impedance: 250 Ω
Range: 0–20 mA / 4–20 mA = 0–Max. Output Frequency (Pr.01-00)
Switch: AI10 / AI11 Switch, default 0–10 V</td></tr>
<tr><td>AO10, AO11</td><td colspan="2">Refer to Pr.14-12–Pr.14-13 for function selection (output), and Pr.14-36–Pr.14-37 for mode selection.
There are two sets of AO port, SSW1 (AO10) and SSW2 (AO11), which can be switched to Voltage or Current mode.
Voltage mode: Output 0–10 V
Current mode: Output 0–20 mA / 4–20 mA</td></tr>
</table>

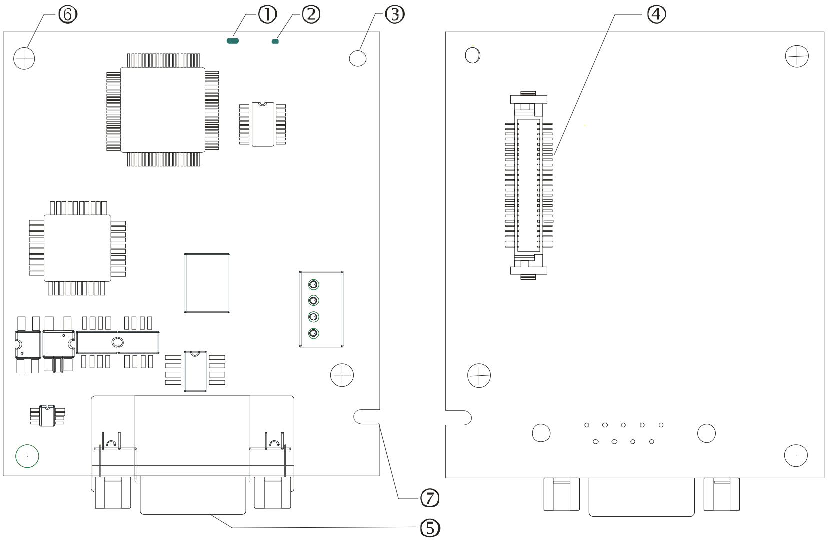
		Multi-function analog output 	AVO: 0–10 V Max. output current 2 mA, Max. load 5 kΩ Output current: 2 mA max Resolution: 0–10 V corresponds to Max. operation frequency Switch: AO10 / AO11 Switch, default 0–10 V
			ACO: 0–20 mA Max. Load 500 Ω Output current: 20 mA max Resolution: 0–20 mA / 4–20 mA corresponds to Max. operation frequency Switch: AO10 / AO11 Switch, default 0–10 V
	ACM	Analog Signal Common	Common for analog terminals

8-7 CMC-PD01 -- Communication card, PROFIBUS DP

8-7-1 Features

1. Supports PZD control data exchange.
2. Supports PKW polling AC motor drive parameters.
3. Supports user diagnosis function.
4. Auto-detects baud rates; supports Max. 12 Mbps.

8-7-2 Product Profile



1. NET indicator
2. POWER indicator
3. Positioning hole
4. AC motor drive connection port
5. PROFIBUS DP connection port
6. Screw fixing hole
7. Fool-proof groove

8-7-3 Specifications

PROFIBUS DP Connector

Interface	DB9 connector
Transmission method	High-speed RS-485
Transmission cable	Shielded twisted pair cable
Electrical isolation	500 V_{DC}

Communication

Message type	Cyclic data exchange
Module name	CMC-PD01
GSD document	DELA08DB.GSD
Company ID	08DB (HEX)
Serial transmission speed supported (auto-detection)	9.6 Kbps; 19.2 Kbps; 93.75 Kbps; 187.5 Kbps; 500 Kbps; 1.5 Mbps; 3 Mbps; 6 Mbps; 12 Mbps (bit /per second)

Electrical Specification

Power supply voltage	5 V_{DC} (supplied by AC motor drive)
Insulation voltage	500 V_{DC}
Power consumption	1 W
Weight	28 g

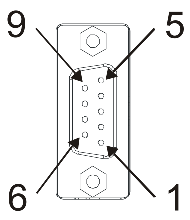
Environment

Noise immunity	ESD (IEC 61800-5-1, IEC 61000-4-2) EFT (IEC 61800-5-1, IEC 61000-4-4) Surge Teat (IEC 61800-5-1, IEC 61000-4-5) Conducted Susceptibility Test (IEC 61800-5-1, IEC 61000-4-6)
Operation /storage	Operation: -10ºC–50ºC (temperature), 90% (humidity) Storage: -25ºC–70ºC (temperature), 95% (humidity)
Shock / vibration resistance	International standards: IEC61131-2, IEC60068-2-6 (TEST Fc) / IEC61131-2 & IEC60068-2-27 (TEST Ea)

8-7-4 Installation

PROFIBUS DP Connector

PIN	PIN name	Definition
1	-	Not defined
2	-	Not defined
3	Rxd/Txd-P	Sending/receiving data P(B)
4	-	Not defined
5	DGND	Data reference ground
6	VP	Power voltage – positive
7	-	Not defined
8	Rxd/Txd-N	Sending/receiving data N(A)
9	-	Not defined



8-7-5 LED Indicator & Troubleshooting

There are 2 LED indicators on CMC-PD01: POWER LED and NET LED. POWER LED displays the status of the working power. NET LED displays the connection status of the communication.

POWER LED

LED status	Indication	How to correct it
Green light ON	Power supply in normal status.	--
OFF	No power	Check if the connection between CMC-PD01 and AC motor drive is normal.

NET LED

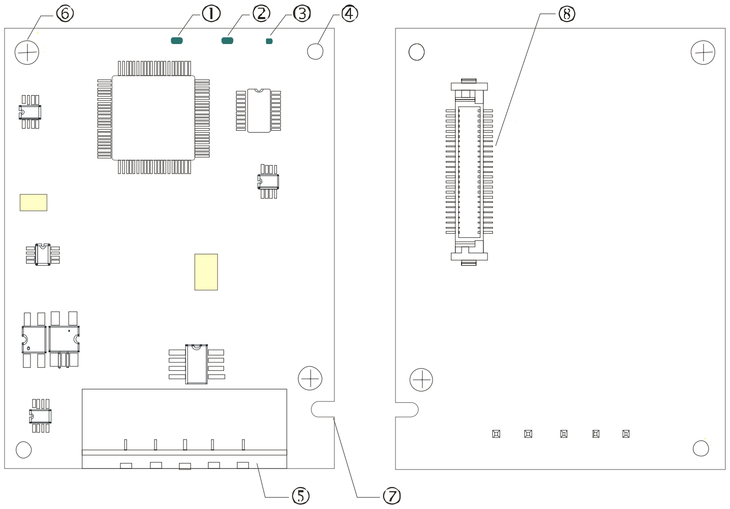
LED status	Indication	How to correct it
Green light ON	Normal status	--
Red light ON	CMC-PD01 is not connected to PROFIBUS DP bus.	Connect CMC-PD01 to PROFIBUS DP bus.
Red light flashes	Invalid PROFIBUS communication address	Set the PROFIBUS address of CMC-PD01 between 1–125 (decimal)
Orange light flashes	CMC-PD01 fails to communicate with AC motor drive.	Switch off the power and check whether CMC-PD01 is correctly and normally connected to AC motor drive.

8-8 CMC-DN01 -- Communication card, DeviceNet

8-8-1 Functions

1. Based on the high-speed communication interface of Delta HSSP protocol, able to conduct immediate control to AC motor drive.
2. Supports Group 2 only connection and polling I/O data exchange.
3. For I/O mapping, supports Max. 32 words of input and 32 words of output.
4. Supports EDS file configuration in DeviceNet configuration software.
5. Supports all baud rates on DeviceNet bus: 125 Kbps, 250 Kbps, 500 Kbps and extendable serial transmission speed mode.
6. Node address and serial transmission speed can be set up on AC motor drive.
7. Power supplied from AC motor drive.

8-8-2 Product Profile



1. NS indicator
2. MS indicator
3. POWER indicator
4. Positioning hole
5. DeviceNet connection port
6. Screw fixing hole
7. Fool-proof groove
8. AC motor drive connection port

8-8-3 Specifications

DeviceNet Connector

Interface	5-PIN open removable connector of 5.08 mm PIN interval
Transmission method	CAN
Transmission cable	Shielded twisted pair cable (with 2 power cables)
Transmission speed	125 Kbps, 250 Kbps, 500 Kbps and extendable serial transmission speed mode
Network protocol	DeviceNet protocol

AC Motor Drive Connection Port

Interface	50 PIN communication terminal
Transmission method	SPI communication
Terminal function	1. Communicating with AC motor drive 2. Transmitting power supply from AC motor drive
Communication protocol	Delta HSSP protocol

Electrical Specification

Power supply voltage	5 V_{DC} (supplied by AC motor drive)
Insulation voltage	500 V_{DC}
Communication wire power consumption	0.85 W
Power consumption	1 W
Weight	23 g

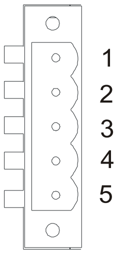
Environment

Noise immunity	ESD (IEC 61800-5-1,IEC 61000-4-2) EFT (IEC 61800-5-1,IEC 61000-4-4) Surge Test (IEC 61800-5-1,IEC 61000-4-5) Conducted Susceptibility Test (IEC 61800-5-1,IEC 61000-4-6)
Operation /storage	Operation: -10ºC–50ºC (temperature), 90% (humidity) Storage: -25ºC–70ºC (temperature), 95% (humidity)
Shock / vibration resistance	International standards: IEC 61800-5-1, IEC 60068-2-6 / IEC 61800-5-1, IEC 60068-2-27

8-8-4 Installation

DeviceNet Connector

PIN	Signal	Color	Definition
1	V+	Red	DC24V
2	H	White	Signal+
3	S	-	Earth
4	L	Blue	Signal-
5	V-	Black	0V



8-8-5 LED Indicator & Troubleshooting

There are 3 LED indicators on CMC-DN01: POWER LED, MS LED and NS LED. POWER LED displays the status of power supply. MS LED and NS LED are dual-color LED, displaying the connection status of the communication and error messages.

POWER LED

LED status	Indication	How to correct it
OFF	Power supply in abnormal status.	Check the power supply of CMC-DN01.
Green light ON	Power supply in normal status	--

NS LED

LED status	Indication	How to correct it
OFF	No power supply or CMC-DN01 has not completed MAC ID test yet.	1. Check the power of CMC-DN01 and see if the connection is normal. 2. Make sure at least one or more nodes are on the bus. 3. Check if the serial transmission speed of CMC-DN01 is the same as that of other nodes.
Green light flashes	CMC-DN01 is on-line but has not established connection to the master.	1. Configure CMC-DN01 to the scan list of the master. 2. Re-download the configured data to the master.
Green light ON	CMC-DN01 is on-line and is normally connected to the master	--
Red light flashes	CMC-DN01 is on-line, but I/O connection is timed-out.	1. Check if the network connection is normal. 2. Check if the master operates normally.
Red light ON	1. The communication is down. 2. MAC ID test failure. 3. No network power supply. 4. CMC-DN01 is off-line.	1. Make sure all the MAC IDs on the network are not repeated. 2. Check if the network installation is normal. 3. Check if the baud rate of CMC-DN01 is consistent with that of other nodes. 4. Check if the node address of CMC-DN01 is illegal. 5. Check if the network power supply is normal.

MS LED

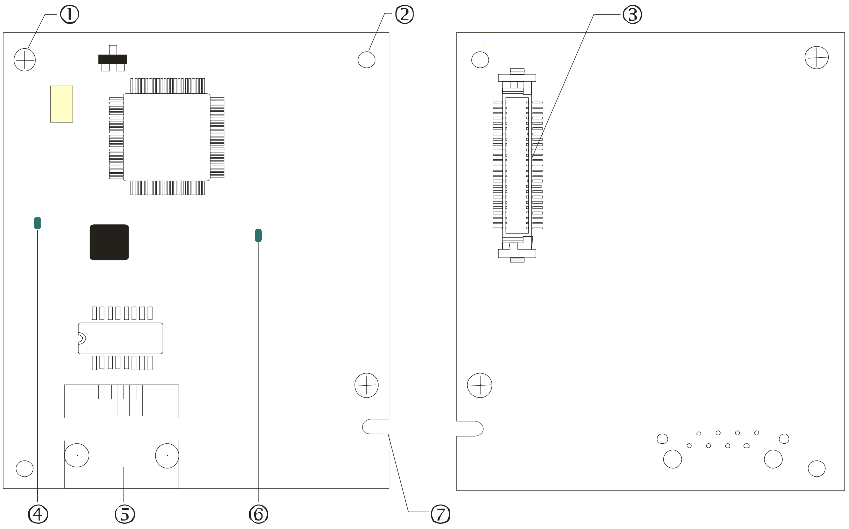
LED status	Indication	How to correct it
OFF	No power supply or being off-line	Check the power supply of CMC-DN01 and see if the connection is normal.
Green light flashes	Waiting for I/O data	Switch the master PLC to RUN status
Green light ON	I/O data are normal	--
Red light flashes	Mapping error	1. Reconfigure CMC-DN01 2. Re-power AC motor drive
Red light ON	Hardware error	1. See the error code displayed on AC motor drive. 2. Send back to the factory for repair if necessary.
Orange light flashes	CMC-DN01 is establishing connection with AC motor drive.	If the flashing lasts for a long time, turn off the power and check if CMC-DN01 and AC motor drive are correctly installed and normally connected to each other.

8-9 CMC-EIP01 -- Communication card, EtherNet/IP

8-9-1 Features

1. Supports Ethernet/IP and Modbus TCP protocol
2. User-defined corresponding parameters (EIP V1.06 and above)
3. Simple firewall function for IP Filter
4. MDI/MDI-X auto-detect
5. Baud rate: 10/100 Mbps auto-detect mail alarm

8-9-2 Product Profile



[Figure1]

1. Screw fixing hole
2. Positioning hole
3. AC motor drive connection port
4. LINK indicator
5. RJ45 connection port
6. POWER indicator
7. Fool-proof groove

8-9-3 Specifications

Network Interface

Interface	RJ45 with Auto MDI/MDIX
Number of ports	1 Port
Transmission method	IEEE 802.3, IEEE 802.3u
Transmission cable	Category 5e shielding 100M
Transmission speed	10/100 Mbps Auto-Detect
Network protocol	ICMP, IP, TCP, UDP, DHCP, BOOTP, SMTP, EtherNet/IP, Modbus TCP

Electrical Specification

Weight	25 g
Insulation voltage	500 V_{DC}
Power consumption	0.8 W
Power supply voltage	5 V_{DC}

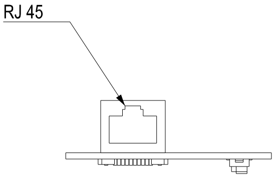
Environment

Noise immunity	ESD (IEC 61800-5-1, IEC 61000-4-2) EFT (IEC 61800-5-1, IEC 61000-4-4) Surge Test (IEC 61800-5-1, IEC 61000-4-5) Conducted Susceptibility Test (IEC 61800-5-1, IEC 61000-4-6)
Operation/storage	Operation: -10°C–50°C (temperature), 90% (humidity) Storage: -25°C–70°C (temperature), 95% (humidity)
Vibration/shock immunity	International standard: IEC 61800-5-1, IEC 60068-2-6/IEC 61800-5-1, IEC 60068-2-27

8-9-4 Installation

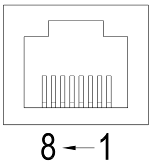
Connecting CMC-EIP01 to Network

1. Turn off the power of AC motor drive.
2. Open the cover of AC motor drive.
3. Connect CAT-5e network cable to RJ45 port on CMC-EIP01 (See the figure on the right).



RJ45 PIN Definition

PIN	Signal	Definition	PIN	Signal	Definition
1	Tx+	Positive pole for data transmission	5	--	N/C
2	Tx-	Negative pole for data transmission	6	Rx-	Negative pole for data receiving
3	Rx+	Positive pole for data receiving	7	--	N/C
4	--	N/C	8	--	N/C



8-9-5 Communication Parameters for CP2000 Connected to Ethernet

When the CP2000 is connected to an Ethernet network, set up the communication parameters for it according to the table below. The Ethernet master is only able to read/write the frequency word and control word of CP2000 after the communication parameters are set.

Parameter	Function	Set value (Dec)	Explanation
Pr.00-20	Source of frequency command setting	8	The frequency command is controlled by communication card.
Pr.00-21	Source of operation command setting	5	The operation command is controlled by communication card.
Pr.09-30	Decoding method for communication	0	The decoding method for Delta AC motor drive
Pr.09-75	IP setting	0	Static IP(0) / Dynamic distribution IP(1)
Pr.09-76	IP address -1	192	IP address 192.168.1.5
Pr.09-77	IP address -2	168	IP address 192.168.1.5
Pr.09-78	IP address -3	1	IP address 192.168.1.5
Pr.09-79	IP address -4	5	IP address 192.168.1.5

Parameter	Function	Set value (Dec)	Explanation
Pr.09-80	Netmask -1	255	Netmask 255.255.255.0
Pr.09-81	Netmask -2	255	Netmask 255.255.255.0
Pr.09-82	Netmask -3	255	Netmask 255.255.255.0
Pr.09-83	Netmask -4	0	Netmask 255.255.255.0
Pr.09-84	Default gateway -1	192	Default gateway 192.168.1.1
Pr.09-85	Default gateway -2	168	Default gateway 192.168.1.1
Pr.09-86	Default gateway -3	1	Default gateway 192.168.1.1
Pr.09-87	Default gateway -4	1	Default gateway 192.168.1.1

8-9-6 LED Indicator & Troubleshooting

There are 2 LED indicators on CMC-EIP01: POWER LED and LINK LED. The POWER LED displays the status of power supply, and the LINK LED displays the connection status of the communication.

LED Indicators

LED	Status		Indication	How to correct it
POWER	Green	ON	Power supply in normal status	--
		OFF	No power supply	Check the power supply.
LINK	Green	ON	Network connection in normal status	--
		Flashes	Network in operation	--
		OFF	Network not connected	Check if the network cable is connected.

Troubleshooting

Abnormality	Cause	How to correct it
POWER LED OFF	AC motor drive not powered	Check if AC motor drive is powered, and if the power supply is normal.
	CMC-EIP01 not connected to AC motor drive	Make sure CMC-EIP01 is connected to AC motor drive.
LINK LED OFF	CMC-EIP01 not connected to network	Make sure the network cable is correctly connected to network.
	Poor contact to RJ45 connector	Make sure RJ45 connector is connected to Ethernet port.
No communication card found	CMC-EIP01 not connected to network	Make sure CMC-EIP01 is connected to network.
	PC and CMC-EIP01 in different networks and blocked by network firewall.	Search by IP or set up relevant settings by AC motor drive keypad.
Fail to open CMC-EIP01 setup page	CMC-EIP01 not connected to network	Make sure CMC-EIP01 is connected to the network.
	Incorrect communication setting in DCISoft	Make sure the communication setting in DCISoft is set to Ethernet.
	PC and CMC-EIP01 in different networks and blocked by network firewall.	Conduct the setup by AC motor drive keypad.

Abnormality	Cause	How to correct it
Able to open CMC-EIP01 setup page but fail to utilize webpage monitoring	Incorrect network setting in CMC-EIP01	Check if the network setting for CMC-EIP01 is correct. For the Intranet setting in your company, consult your IT staff. For the Internet setting in your home, refer to the network setting instruction provided by your ISP.
Fail to send e-mail	Incorrect network setting in CMC-EIP01	Check if the network setting for CMC-EIP01 is correct.
	Incorrect mail server setting	Confirm the IP address for SMTP-Server.

8-10 CMC-PN01 – Communication card, PROFINET

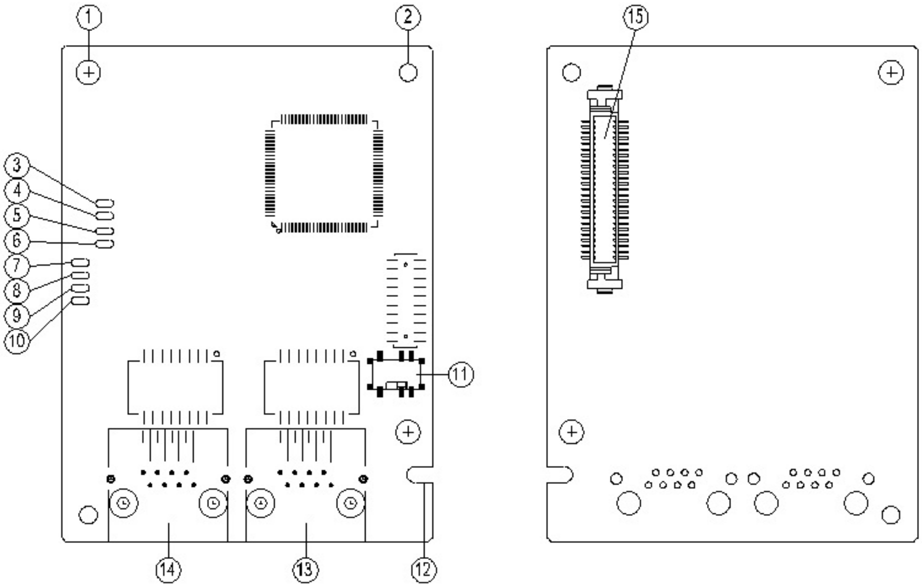
8-10-1 Features

CMC-PN01 connects CP2000 to PROFINET, so the drive is able to exchange data with the upper unit. It is a simple NET solution, which can reduce the cost and time of connection/ installing factory automation, also provide compatibility of similar components from multiple suppliers.

Connect CMC-PN01 to CP2000 via PROFINET device:

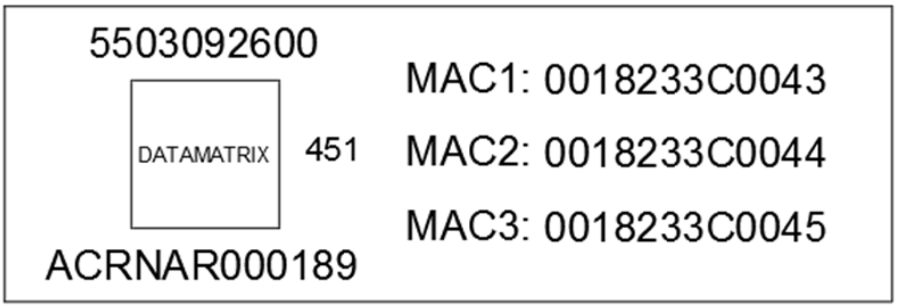
1. Control the AC motor drive via PROFINET
2. Change the drive parameters via PROFINET
3. Monitor the drive status via PROFINET

8-10-2 Product Profile



1. Screw fixing hole
2. Positioning hole
3. Ready out indicator
4. MT out indicator
5. SD indicator
6. BF out indicator
7. ACT PHY2 indicator
8. Link PHY2 indicator
9. ACT PHY1 indicator
10. Link PHY1 indicator
11. Switch
12. Fool-proof groove
13. RJ45 connection port (Port 2)
14. RJ45 connection port (Port 1)
15. Connection port of control board

MAC Address label definition



5503092600

DATAMATRIX

451

ACRNAR000189

MAC1: 0018233C0043

MAC2: 0018233C0044

MAC3: 0018233C0045

Def.	Explanation
MAC1	Port 1 MAC Address
MAC2	Port 2 MAC Address
MAC3	Interface MAC Address

8-10-3 Specifications

Network Interface

Interface	RJ45
Number of ports	2 ports
Transmission method	IEEE 802.3
Transmission cable	Category 5e shielding 100 M
Transmission speed	10/100 Mbps auto-negotiate
Network protocol	PROFINET

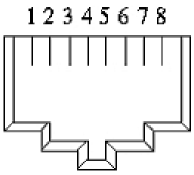
Electrical Specification

Power supply voltage	5 V_{DC}
Power consumption	0.8 W
Insulation voltage	500 V_{DC}
Weight (g)	27

Environment

Noise immunity	ESD (IEC 61800-5-1, IEC 61000-4-2) EFT (IEC 61800-5-1, IEC 61000-4-4) Surge Test (IEC 61800-5-1, IEC 61000-4-5) Conducted Susceptibility Test (IEC 61800-5-1, IEC 61000-4-6)
Operation	-10°C–50°C (temperature), 90% (humidity)
Storage	-25°C–70°C (temperature), 95% (humidity)
Vibration / Shock immunity	International standard: IEC 61800-5-1, IEC 60068-2-6 / IEC 61800-5-1, IEC 60068-2-27

8-10-4 RJ45 PIN Definition

RJ45	PIN No.	Signal	Definition
	1	Tx+	Positive pole for data transmission
	2	Tx-	Negative pole for data transmission
	3	Rx+	Positive pole for data receiving
	4	--	N/C
	5	--	N/C
	6	Rx-	Negative pole for data receiving
	7	--	N/C
	8	--	N/C

8-10-5 Communication Parameters for CP2000 Conneted to PROFINET

When operating CP2000 via CMC-PN01, set the control and operation command as controlled by communication card. When CP2000 is connected to PROFINET network, set up the communication parameters according to the table below.

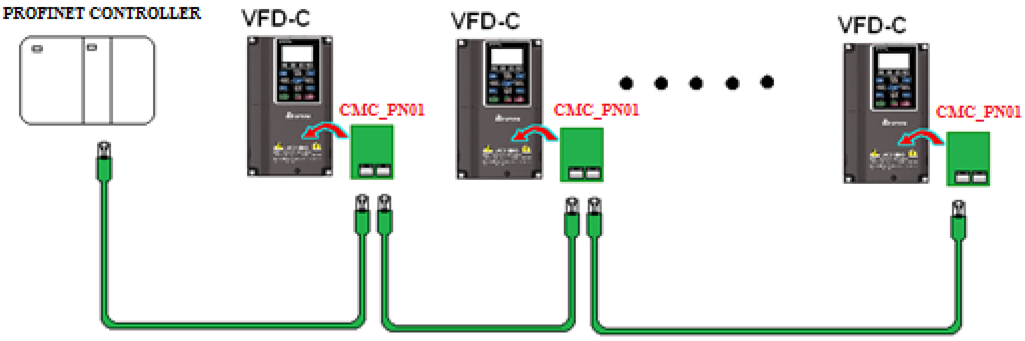
Parameter	Set value (Dec)	Explanation
Pr.00-20	8	The frequency command is controlled by communication card.
Pr.00-21	5	The operation command is controlled by communication card.
Pr.09-30	1	Set Pr.09-30 to 60xx or 20xx as the decoding method.
Pr.09-60	12	Identification: when CMC-PN01 is connected, Pr.09-60 will show value 12.

8-10-6 LED Indicator

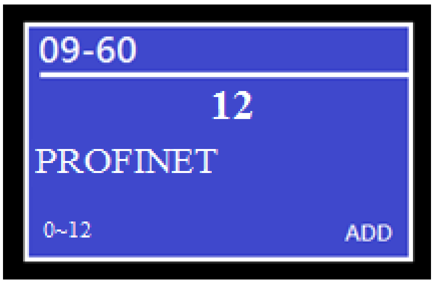
LED	Status		Indication
Ready out	Yellow	ON	PN Stack operates in normal status
		Flashes	PN Stack operates in normal status, and waiting to sync with MCU
		OFF	PN Stack operates with error
MT out	Green	-	-
SD	Red	-	-
BF out	Red	ON	Connection with PROFINET Controller breaks off
		Flashes	Connection is normal, but an error occurs to the communication with PROFINET Controller
		OFF	Connection with PROFINET Controller is normal
ACT PHY1	Orange	ON	Online, exchanging data with the master
		Flashes	Off line, but handshaking data with the master
		OFF	Initial status
LINK PHY1	Green	ON	Network connection is normal
		OFF	Network is not connected
ACT PHY2	Orange	ON	On line, exchanging data with the master
		Flashes	Off line, but handshaking data with the master
		OFF	Initial status
LINK PHY2	Green	ON	Network connection is normal
		OFF	Network is not connected

8-10-7 Network Connection

Wiring of CMC-PN01 is as following:



When the hardware is installed and power on, the current set value of Pr.09-60 will be 12, and shows “PROFINET” on the display. If the above information does not show on the display, check the version of CP2000 and the connection of the card.


09-60

12

PROFINET

0~12 ADD

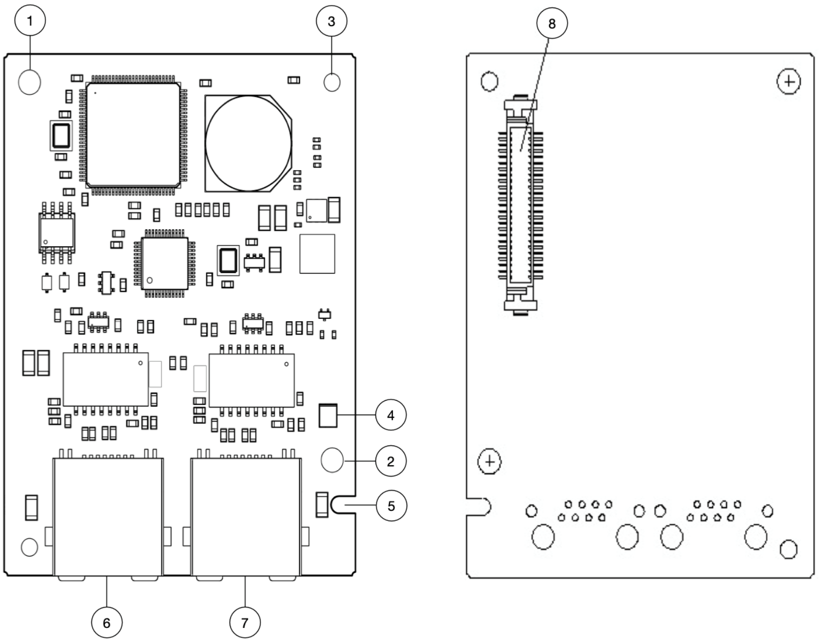
8-11 eZVFD-CC – Communication card, BACnet Ethernet/BACnet IP

8-11-1 Features

The eZVFD-CC Integration Module provides BACnet/IP and BACnet over Ethernet communication to BACnet compliant devices. When used with a Delta Controls system, you can use the module's GCL+ programs and Delta Controls internal control loops to directly control pumps and fan motors. Quickly configure and save drive parameters in enteliWEB and load the saved configuration onto other CP2000 AC motor drives over the BACnet network. Features include:

- Native BACnet firmware
- BACnet/IP, BACnet over Ethernet communication protocols
- Fully programmable in GCL+ (Delta Controls General Control Language)
- Dual port ethernet to support daisy-chaining multiple CP2000 devices
- Monitor and utilize CP2000 AC motor drive I/O terminals as BACnet I/O
- Set up and configure using enteliWEB. Use enteliWEB to read, write, save and load CP2000 AC motor drive parameters.

8-11-2 Product Profile



1. Screw fixing hole 1
2. Screw fixing hole 2
3. Positioning hole
4. Status and Power LED
5. Fool-proof groove
6. RJ45 Ethernet Port 1
7. RJ45 Ethernet Port 2
8. AC motor drive connection port

MAC address is displayed in the IPS object in entelliWEB.

8-11-3 Specifications

Network Interface

Interface	RJ45
Number of ports	2 ports
Daisy chaining	Up to 30 devices (daisy chain is discontinued if drive is not powered)
Transmission method	IEEE 802.3
Transmission cable	10/100BaseT CAT5E/CAT6
Maximum length	100m (port-to-port)
Transmission speed	10/100 Mbps auto-negotiate
Network protocol	BACnet/IP or BACnet/Ethernet

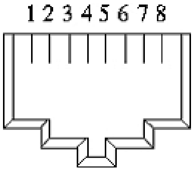
Electrical Specification

Power supply voltage	5 V_{DC} (supplied by AC Motor Drive)
Power consumption	< 2 W
Insulation voltage	500 V_{DC}
Weight (g)	2.6g
Technology	32-bit CPU, field upgradeable firmware, real-time clock with supercapacitor backup

Environment

Compliance	CE IEC 61800-3, EMC Standard for Variable Speed Drives LVD IEC 61800-5-1 Safety Requirements for Electrical Power Drive Systems
Operation	0°C to 55°C (temperature), 10% to 95% RH (non-condensing)
Storage	-25°C–70°C (temperature), 95% RH

8-11-4 RJ45 PIN Definition

RJ45	PIN No.	Signal	Definition
	1	Tx+	Positive pole for data transmission
	2	Tx-	Negative pole for data transmission
	3	Rx+	Positive pole for data receiving
	4	--	N/C
	5	--	N/C
	6	Rx-	Negative pole for data receiving
	7	--	N/C
	8	--	N/C

8-11-5 Communication Parameters for CP2000 Connected to eZVFD-CC BACnet Controller

When operating the CP2000 using the eZVFD-CC card you must set the parameters according to the table below:

Parameter	Function	Set value (Dec)	Explanation
Pr.00-20	Source of frequency command setting	8	The frequency command is controlled by communication card.
Pr.00-21	Source of operation command setting	5	The operation command is controlled by communication card.
Pr.09-30	Decoding method for communication	1	Decoding method 2 (Refer to address: 6000h – 60FFh)
Pr.09-60	Identification for Communication Card	Read-only	When eZVFD-CC is connected, Pr.09-60 will show value 8 (BACnet IP)

The following parameters should be set according to your desired network configuration. The table below shows default values:

Parameter	Function	Default value (Dec)	Explanation
Pr.04-50	UDP port number	47808	UDP/IP communication port
Pr.04-51	BACnet network number	BACnet/Ethernet: 19999 BACnet/IP: 49999	Depends on setting of Pr.09-91
Pr.09-52	BACnet device address, low word (range 0-65535)	4100000 + (last 4 hex in MAC address in decimal)	This value is added to the value of Pr.09-53 * 65536
Pr.09-53	BACnet device address, high word (range 0-63)	-	This value is multiplied by 65536 and added to the value of Pr.09-52
Pr.09-75	IP setting	0	0: Static IP 1: Dynamic Distribution IP (DHCP)
Pr.09-91	BACnet IP or Ethernet	1	0: BACnet/ Ethernet 1: BACnet/IP

If static IP is chosen (Pr.09-75 = 0), then the following parameters must be set according to your local network configuration:

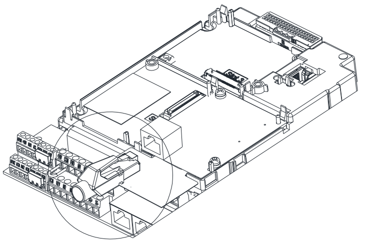
Parameter	Function	Set value (Dec)	Explanation
Pr.09-76	IP address -1	192	IP address 192.168.1.5
Pr.09-77	IP address -2	168	IP address 192.168.1.5
Pr.09-78	IP address -3	1	IP address 192.168.1.5
Pr.09-79	IP address -4	5	IP address 192.168.1.5
Pr.09-80	Netmask -1	255	Netmask 255.255.255.0
Pr.09-81	Netmask -2	255	Netmask 255.255.255.0
Pr.09-82	Netmask -3	255	Netmask 255.255.255.0
Pr.09-83	Netmask -4	0	Netmask 255.255.255.0
Pr.09-84	Default gateway -1	192	Default gateway 192.168.1.1
Pr.09-85	Default gateway -2	168	Default gateway 192.168.1.1
Pr.09-86	Default gateway -3	1	Default gateway 192.168.1.1
Pr.09-87	Default gateway -4	1	Default gateway 192.168.1.1

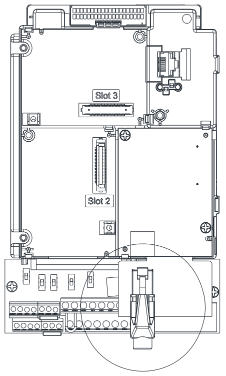
8-11-6 LED Indicator

Color	LED Pattern	Indication
Red	On	Hardware startup before system is running
Red	Blinks in a regular repeating pattern 1 second on, 1 second off.	Hardware failure
Green	Blinks in a regular repeating pattern 1 second on, 1 second off.	OK
Amber	Blinks at approx. 100 Hz	Flash loading Main from Boot
Amber	On	Database saving or restoring from Flash

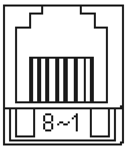
8-12 EMC-COP01 -- Communication card, CANopen

8-12-1 Terminal Resistor Position





8-12-2 RJ45 PIN Definition



RS-485 socket

Pin	Pin name	Definition
1	CAN_H	CAN_H bus line (dominant high)
2	CAN_L	CAN_L bus line (dominant low)
3	CAN_GND	Ground/0V/V-
7	CAN_GND	Ground/0V/V-

8-12-3 Specifications

Interface	RJ45
Number of ports	1 Port
Transmission method	CAN
Transmission cable	CAN standard cable
Transmission speed	1 Mbps, 500 Kbps, 250 Kbps, 125 Kbps, 100 Kbps, 50 Kbps
Communication protocol	CANopen

8-13 Delta Standard Fieldbus Cables

Delta Cables	Part Number	Description	Length
CANopen Cable	UC-CMC003-01A	CANopen Cable, RJ45 Connector	0.3 m
	UC-CMC005-01A	CANopen Cable, RJ45 Connector	0.5 m
	UC-CMC010-01A	CANopen Cable, RJ45 Connector	1 m
	UC-CMC015-01A	CANopen Cable, RJ45 Connector	1.5 m
	UC-CMC020-01A	CANopen Cable, RJ45 Connector	2 m
	UC-CMC030-01A	CANopen Cable, RJ45 Connector	3 m
	UC-CMC050-01A	CANopen Cable, RJ45 Connector	5 m
	UC-CMC100-01A	CANopen Cable, RJ45 Connector	10 m
	UC-CMC200-01A	CANopen Cable, RJ45 Connector	20 m
DeviceNet Cable	UC-DN01Z-01A	DeviceNet Cable	305 m
	UC-DN01Z-02A	DeviceNet Cable	305 m
Ethernet / EtherCAT Cable	UC-EMC003-02A	Ethernet/EtherCAT cable, Shielding	0.3 m
	UC-EMC005-02A	Ethernet/EtherCAT cable, Shielding	0.5 m
	UC-EMC010-02A	Ethernet/EtherCAT cable, Shielding	1 m
	UC-EMC020-02A	Ethernet/EtherCAT cable, Shielding	2 m
	UC-EMC050-02A	Ethernet/EtherCAT cable, Shielding	5 m
	UC-EMC100-02A	Ethernet/EtherCAT cable, Shielding	10 m
	UC-EMC200-02A	Ethernet/EtherCAT cable, Shielding	20 m
CANopen / DeviceNet TAP	TAP-CN01	1 in 2 out, built-in 121Ω terminal resistor	1 in 2 out
	TAP-CN02	1 in 4 out, built-in 121Ω terminal resistor	1 in 4 out
	TAP-CN03	1 in 4 out, RJ45 connector, built-in 121Ω terminal resistor	1 in 4 out
PROFIBUS Cable	UC-PF01Z-01A	PROFIBUS DP Cable	305 m

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Chapter 9 Specifications

9-1 230V Models

9-2 460V Models

9-3 575V Models

9-4 690V Models

9-5 Environment for Operation, Storage and Transportation

9-6 Specification for Operation Temperature and Protection Level

9-7 Derating Curve for Ambient Temperature, Altitude and Carrier Frequency

9-8 Efficiency Curve

9-1 230V Models

Frame			A					B			C			D		E		
Model: VFD_ _ _CP23_-_			007	015	022	037	055	075	110	150	185	220	300	370	450	550	750	900
*Output Rating	Light Duty	Rated output capacity [kVA]	2	3	4	6	8.4	12	18	24	30	36	42	58	72	86	110	128
		Rated output current [A]	5	7.5	10	15	21	31	46	61	75	90	105	146	180	215	276	322
		Applicable motor output [kW]	0.75	1.5	2.2	3.7	5.5	7.5	11	15	18.5	22	30	37	45	55	75	90
		Applicable motor output [HP]	1	2	3	5	7.5	10	15	20	25	30	40	50	60	75	100	125
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes															
		Max. output frequency [Hz]	599.00													400.00		
		Carrier frequency [kHz]	2–15 (Default: 8)								2–10 (Default: 6)					2–9 (Default: 4)		
	Normal Duty	Rated output capacity [kVA]	1.2	2	3.2	4.4	6.8	10	13	20	26	30	36	48	58	72	86	102
		Rated output current [A]	3	5	8	11	17	25	33	49	65	75	90	120	146	180	215	255
		Applicable motor output [kW]	0.4	0.75	1.5	2.2	3.7	5.5	7.5	11	15	19	22	30	37	45	55	75
		Applicable motor output [HP]	0.5	1	2	3	5	7.5	10	15	20	25	30	40	50	60	75	100
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes; 160% of rated current for 3 seconds during every 25 seconds															
		Max. output frequency [Hz]	599.00													400.00		
		Carrier frequency [kHz]	2–15 (Default: 8)								2–10 (Default: 6)					2–9 (Default: 4)		
Input Rating	Input current [A]	Light duty	6.4	9.6	15	22	25	35	50	65	83	100	116	146	180	215	276	322
		Normal duty	3.9	6.4	12	16	20	28	36	52	72	83	99	124	143	171	206	245
	Rated voltage / Frequency		3 phase, 200–240 V_{AC} [-15%– +10%], 50/60 Hz															
	Operating voltage range		170–264 V_{AC}															
	Frequency tolerance		47–63 Hz															
Efficiency [%]			97.8												98.2			
Power Factor			> 0.98															
Weight [Kg]			2.6 ± 0.3					5.4 ± 1			9.8 ± 1.5			38.5 ± 1.5		64.8 ± 1.5		
Cooling method			Natural cooling		Fan cooling													
Braking chopper			Frame A, B, C: Built-in											Frame D above: Optional				
DC choke			Frame A, B, C: Optional											Frame D above: Built-in 3%				
EMC Filter			Optional															

NOTE

Table 9-1

- ■ The carrier frequency is default. Increasing the carrier frequency requires a reduction in current. Refer to Chapter 9-7 Derating Curve of Ambient Temperature.
- ■ Select the AC motor drive with capacity one grade larger for the impact load application.
- ■ Refer to Chapter 9-6 Specification for Operation Temperature and Protection Level for the protection level of each model.
- ■ *The default setting is Light Duty, you can select Normal Duty and Light Duty by setting Pr.00-16.

9-2 460V Models

Frame			A							B			C			D0	
Model VFD_ _ _CP43_-_ _ Model VFD_ _ _CP4E_-_ _			007	015	022	037	040	055	075	110	150	185	220	300	370	450	550
*1 Output rating	Light duty	Rated output capacity [kVA]	2.4	3.3	4.4	6.8	8.4	10.4	14.3	19	25	30	36	48	58	73	88
		Rated output current [A]	3	4.2*2	5.5*2	8.5*2	10.5	13*2	18*2	24*2	32*2	38*2	45	60*2	73*2	91	110
		Applicable motor output [kW]	0.75	1.5	2.2	3.7	4	5.5	7.5	11	15	18.5	22	30	37	45	55
		Applicable motor output [HP]	1	2	3	5	5	7.5	10	15	20	25	30	40	50	60	75
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes														
		Max.output frequency [Hz]	599.00														
		Carrier frequency [kHz]	2–15 (Default: 8)										2–10 (Default: 6)				
	Normal duty	Rated output capacity [kVA]	2.2	2.4	3.2	4.8	7.2	8.4	10.4	14.3	19	25	30	36	48	58	73
		Rated output current [A]	1.7	3.0	4.0	6.0	9.0	10.5	12	18	24	32	38	45	60	73	91
		Applicable motor output [kW]	0.4	0.75	1.5	2.2	3.7	4	5.5	7.5	11	15	18.5	22	30	37	45
		Applicable motor output [HP]	0.5	1	2	3	5	5	7.5	10	15	20	25	30	40	53	60
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes; 160% of rated current for 3 seconds during every 25 seconds														
		Max.output frequency [Hz]	599.00														
		Carrier frequency [kHz]	2–15 (Default: 8)										2–10 (Default: 6)				
Input rating	Input current [A]	Light duty	4.3	6	8.1	12.4	16	20	22	26	35	42	50	66	80	91	110
		Normal duty	3.5	4.3	5.9	8.7	14	15.5	17	20	26	35	40	47	63	74	101
	Rated voltage / Frequency		3 phase, 380–480 V_{AC} [-15%– +10%), 50/60 Hz														
	Operating voltage range		323–528 V_{AC}														
	Frequency tolerance		47–63 Hz														
Efficiency [%]			97.8														
Power factor			> 0.98														
Weight [Kg]			2.6 ± 0.3							5.4 ± 1			9.8 ± 1.5			27 ± 1	
Cooling method			Natural cooling	Fan cooling													
Braking chopper			Frame A, B, C: Built-in; Frame D0 above: Optional														
DC choke			Frame A, B, C: Optional; Frame D0 above: Built-in 3%														
EMC Filter			Frame A, B, C of VFD_ _ _ _CP4EA-_ _: Built-in; Frame A, B, C of VFD_ _ _ _CP43A-_ _: no built-in; Frame D0 above: Optional														

NOTE

Table 9-2

- The carrier frequency is default. Increasing the carrier frequency requires a reduction in current. Refer to Chapter 9-7 Derating Curve of Ambient Temperature.
- Select the AC motor drive with capacity one grade larger for the impact load application.
- Refer to Chapter 9-6 Specification for Operation Temperature and Protection Level for the protection level of each model.
- *1 The default setting is Light Duty, you can select Normal Duty and Light Duty by setting Pr.00-16.
- *2 It means the rated output current is for the models of Version B. (e.g. VFD015CP43**B**-21)

460V Models

Frame			D		E		F		G				H					
Model VFD_ _ _ _CP43_-_ _			750	900	1100	1320	1600	1850	2000	2200	2500	2800	3150	3550	4000	5000	5600	6300
^{*1}Output rating	Light duty	Rated output capacity [kVA]	120	143	175	207	247	295	315	367	383	422	491	544	613	741	872	966
		Rated output current [A]	150^{*2}	180	220	260^{*2}	310	370^{*2}	395	460	481	530	616	683	770	930	1094	1212
		Applicable motor output [kW]	75	90	110	132	160	185	200	220	250	280	315	355	400	500	560	630
		Applicable motor output [HP]	100	125	150	175	215	250	270	300	340	375	425	475	530	675	750	850
		Overload capacity	120% of rated output current: 1 minute for every 5 minutes															
		Max. output frequency [Hz]	599.00	400.00														
		Carrier Frequency [kHz]	2–10 (Default: 6)	2–9 (Default: 4)														
	Normal duty	Rated output capacity [kVA]	88	120	143	175	207	247	247	295	315	367	438	491	544	690	741	872
		Rated output current [A]	110	150	180	220	260	310	310	370	395	460	550	616	683	866	930	1094
		Applicable motor output [kW]	55	75	90	110	132	160	160	185	200	220	280	315	355	450	500	560
		Applicable motor output [HP]	75	100	125	150	175	215	215	250	270	300	375	425	475	600	675	850
		Overload capacity	120% of rated output current: 1 minute for every 5 minutes; 160% of rated output current: 3 seconds for every 25 seconds															
		Max. output frequency [Hz]	599	400														
		Carrier frequency [kHz]	2–10 (Default: 6)	2–9 (Default: 4)														
Input rating	Input current [A]	Light duty	150	180	220	260	310	370	395	460	481	530	616	683	770	930	1094	1212
		Normal duty	114	157	167	207	240	300	300	380	390	400	494	555	625	866	930	1094
	Rated voltage / frequency		3-phase 380–480 V_{AC} [-15%– +10%], 50/60 Hz															
	Operating voltage range		323–528 V_{AC}															
	Frequency tolerance		47–63 Hz															
Efficiency [%]			97.8	98.2														
Power factor			> 0.98															
Drive weight [Kg]			38.5 ± 1.5		64.8 ± 1.5		86.5 ± 1.5		134 ± 4				228					
Cooling method			Fan cooling															
Braking chopper			Frame D–H: Optional															
DC choke			Frame D–H: Built-in 3%															
EMC filter			Frame D–H: Optional															

NOTE

Table 9-3

- The carrier frequency is default. Increasing the carrier frequency requires a reduction in current. Refer to Chapter 9-7 Derating Curve of Ambient Temperature.
- Select the AC motor drive with capacity one grade larger for the impact load application.
- Refer to Chapter 9-6 Specification for Operation Temperature and Protection Level for the protection level of each model.
- ^{*1} The default setting is Light Duty, you can select Normal Duty and Light Duty by setting Pr.00-16.
- ^{*2} It means the rated output current is for the models of Version B. (e.g. VFD015CP43**B**-21)
- Model VFD5000CP43A-xx is not UL certified.

9-3 575V Models

Frame			A			B			
Model VFD_ _ _ _CP53A-21			015	022	037	055	075	110	150
*Output rating	Light duty	Rated output capacity [kVA]	3	4.3	6.7	9.9	12.1	18.6	24.1
		Rated output current [A]	3	4.3	6.7	9.9	12.1	18.7	24.2
		Applicable motor output [kW]	1.5	2.2	3.7	5.5	7.5	11	15
		Applicable motor output [HP]	2	3	5	7.5	10	15	20
	Normal duty	Rated output capacity [kVA]	2.5	3.6	5.5	8.2	10	15.4	19.9
		Rated output current [A]	2.5	3.6	5.5	8.2	10	15.4	20
		Applicable motor output [kW]	0.75	1.5	2.2	3.7	5.5	7.5	11
		Applicable motor output [HP]	1	2	3	5	7.5	10	15
	Carrier frequency [kHz]		2–15 (Default: 4)						
Input rating	Input current [A]	Light duty	3.8	5.4	10.4	14.9	16.9	21.3	26.3
		Normal duty	3.1	4.5	7.2	12.3	15	18	22.8
	Rated voltage / Frequency		3-phase, 525–600 V_{AC} [-15%– +10%] · 50/60 Hz						
	Operating voltage range		446–660 V_{AC}						
	Frequency tolerance		47–63 Hz						
Efficiency [%]			97			98			
Power factor			> 0.98						
Weight [Kg]			3 ± 0.3			4.8 ± 1			
Cooling method			Natural cooling		Fan cooling				
Braking chopper			Frame A–B: Built-in						
DC choke			Frame A–B: Optional						

NOTE

Table 9-4

- The carrier frequency is default. Increasing the carrier frequency requires a reduction in current. Refer to Chapter 9-7 Derating Curve of Ambient Temperature.
- Select the AC motor drive with capacity one grade larger for the impact load application.
- Refer to Chapter 9-6 Specification for Operation Temperature and Protection Level for the protection level of each model.
- * The default setting is Light Duty, you can select Normal Duty and Light Duty by setting Pr.00-16.

9-4 690V Models

Frame			C				D		E			
Model VFD_ _ _ _CP63A-_ _			185	220	300	370	450	550	750	900	1100	1320
*Output rating	Light duty	Rated output capacity [kVA]	29	36	43	54	65	80	103	124	149	179
		Applicable motor output 690V [kW]	18.5	22	30	37	45	55	75	90	110	132
		Applicable motor output 690V [HP]	25	30	40	50	60	75	100	125	150	175
		Applicable motor output 575V [HP]	20	25	30	40	50	60	75	100	125	150
		Rated output current [A]	24	30	36	45	54	67	86	104	125	150
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes									
		Max.output frequency [Hz]	599.00									
	Normal duty	Rated output capacity [kVA]	24	29	36	43	54	65	80	103	124	149
		Applicable motor output 690V [kW]	15	18.5	22	30	37	45	55	75	90	110
		Applicable motor output 690V [HP]	20	25	30	40	50	60	75	100	125	150
		Rated output capacity 575V [HP]	15	20	25	30	40	50	60	75	100	125
		Rated output current [A]	20	24	30	36	45	54	67	86	104	125
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes; 160% of rated current for 3 seconds during every 25 seconds									
		Max.output frequency [Hz]	599.00									
	Carrier frequency [kHz]		2–9 (Default: 4)									
Input rating	Input current [A]	Light duty	29	36	43	54	65	81	84	102	122	147
		Normal duty	24	29	36	43	54	65	66	84	102	122
	Rated voltage / Frequency		3-phase, 525–690 V_{AC} (-15%– +10%), 50/60 Hz									
	Operating voltage range		446–759 V_{AC}									
	Frequency tolerance		47–63 Hz									
Efficiency [%]			97									
Power factor			> 0.98									
Weight [Kg]			10 ± 1.5				39 ± 1.5			61 ± 1.5		
Cooling method			Fan cooling									
Braking chopper			Frame C: Built-in				Frame D–E: Optional					
DC choke			Frame C: Optional				Frame D–E: Built-in					

NOTE

Table 9-5

- The carrier frequency is default. Increasing the carrier frequency requires a reduction in current. Refer to Chapter 9-7 Derating Curve of Ambient Temperature.
- Select the AC motor drive with capacity one grade larger for the impact load application.
- Refer to Chapter 9-6 Specification for Operation Temperature and Protection Level for the protection level of each model.
- * The default setting is Light Duty, you can select Normal Duty and Light Duty by setting Pr.00-16.

690V Models

Frame			F		G		H			
Model VFD_ _ _ _CP63A-_ _			1600	2000	2500	3150	4000	4500	5600	6300
*Output rating	Light duty	Rated output capacity [kVA]	215	263	347	418	494.5	534.7	678.5	776
		Applicable motor output 690V [kW]	160	200	250	315	400	450	560	630
		Applicable motor output 690V [HP]	215	270	335	425	530	600	750	850
		Applicable motor output 575V [HP]	150	200	250	350	400	450	500	750
		Rated output current [A]	180	220	290	350	430	465	590	675
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes							
		Max.output frequency [Hz]	599.00							
	Normal duty	Rated output capacity [kVA]	179	215	239	347	402.5	442.7	534.7	776
		Applicable motor output 690V [kW]	132	160	200	250	315	355	450	630
		Applicable motor output 690V [HP]	175	215	270	335	425	475	600	850
		Rated output capacity 575V [HP]	150	150	200	250	350	400	450	750
		Rated output current [A]	150	180	220	290	350	385	465	675
		Overload tolerance	120% of rated current for 1 minute during every 5 minutes; 160% of rated current for 3 seconds during every 25 seconds							
		Max.output frequency [Hz]	599.00							
	Carrier frequency [kHz]		2–9 (Default: 4)							2–9 (Default: 3)
Input rating	Input current [A] Light duty		178	217	292	353	454	469	595	681
	Input current [A] Normal duty		148	178	222	292	353	388	504	681
	Rated voltage / Frequency		3-phase, 525–690 V_{AC} (-15%– +10%), 50/60 Hz							
	Operating voltage range		446–759 V_{AC}							
	Frequency tolerance		47–63 Hz							
Efficiency [%]			97		98					
Power factor			> 0.98							
Weight [Kg]			88 ± 1.5		135 ± 4		243 ± 5			
Cooling method			Fan cooling							
Braking chopper			Frame F–H: Optional							
DC choke			Frame F–H: Built-in							

Table 9-6

NOTE

- The carrier frequency is default. Increasing the carrier frequency requires a reduction in current. Refer to Chapter 9-7 Derating Curve of Ambient Temperature.
- Select the AC motor drive with capacity one grade larger for the impact load application.
- Refer to Chapter 9-6 Specification for Operation Temperature and Protection Level for the protection level of each model.
- * The default setting is Light Duty, you can select Normal Duty and Light Duty by setting Pr.00-16.

General Specifications

Control Characteristics	Control Mode	Pulse-Width Modulation (PWM)
	Control Method	1: V/F, 2: SVC, 3: PM Sensorless, 4: SynRM Sensorless
	Starting Torque	Reach up to 150% above at 0.5 Hz.
	V/F Curve	4 point adjustable V/F curve and square curve
	Speed Response Ability	5 Hz (vector control can reach up to 40 Hz)
	Torque Limit	Light duty: max. 130% torque current Normal duty: max. 160% torque current
	Torque Accuracy	±5%
	Max. output frequency (Hz)	230V models: 599.00 Hz (55 kW and above: 400.00 Hz) 460V models: 599.00 Hz (90 kW and above: 400.00 Hz) 575/690V models: 599.00 Hz
	Frequency Output Accuracy	Digital command: ± 0.01%, -10°C– +40°C, Analog command: ± 0.1%, 25 ± 10°C
	Output Frequency Resolution	Digital command: 0.01 Hz Analog command: 0.03 × max. output frequency/60 Hz (± 11 bit)
	Overload Tolerance	Light duty: 120% of rated current can endure for 1 minute Normal duty: 120% of rated current can endure for 1 minute; 160% of rated current can endure for 3 sec.
	Frequency Setting Signal	0–+10 V, 4–20 mA, 0–20 mA
	Accel./Decel. Time	0.00–600.00/0.0–6000.0 seconds
	Main control function	Momentary power loss ride thru, Speed search, Over-torque detection, Torque limit, 16-step speed (max), Accel./Decel. time switch, S-curve accel./decel., 3-wire sequence, Auto-Tuning, Dwell,-Slip compensation, Torque compensation, JOG frequency, Frequency upper/lower limit settings, DC injection braking at start/stop, High slip braking, Energy saving control, Modbus communication (RS-485 RJ45, max. 5.2 Kbps)
	Fan Control	230V models: Models above VFD185CP23 (including VFD185CP23) are PWM control Models below VFD150CP23 (including VFD150CP23) are ON/OFF switch control. 460V models: Models above VFD220CP43/4E (including VFD220CP43/4E) are PWM control Models below VFD185CP43/4E (including VFD185CP43/4E) are ON/OFF switch control. 575V / 690V models: PWM control
	Motor Protection	Electronic thermal relay protection
Protection Characteristics	Over-current Protection	For drive model 230V/460V: Over-current protection: 185% rated current for light duty; 240% rated current for normal duty Current clamp: 『Light duty: 130–135%』; 『Normal duty: 170–175%』 For drive model 575/690V: Over-current protection: 225% rated current for normal duty Current clamp: 『Light duty: 128–141%』; 『Normal duty: 170–175%』
	Over-voltage Protection	230V models: drive will stop when DC bus voltage exceeds 410 V 460V models: drive will stop when DC bus voltage exceeds 820 V 575V models: drive will stop when DC bus voltage exceeds 1016 V 690V models: drive will stop when DC bus voltage exceeds 1189 V
	Over-temperature Protection	Built-in temperature sensor
	Stall Prevention	Stall prevention during acceleration, deceleration and running independently
	Restart After Instantaneous Power Failure	Parameter setting up to 20 seconds
	Grounding Leakage Current Protection	Leakage current is higher than 50% of rated current of the AC motor drive
	Short-circuit Current Rating (SCCR)	Per UL508C, the drive is suitable for use on a circuit capable of delivering not more than 100 kA symmetrical amperes (rms) when protected by fuses given in the fuse table.
Certifications		CE UL CERTIFIED EAC SEMI F47, GB/T12668.3

Table 9-7

NOTE

- * The setting range of max. output frequency changes as carrier wave and control modes changes. Refer to Pr.01-00 for more information.
- Only 230V/460V models are complied with EAC certification. 575V/690V models are not yet for certified.
- Model VFD5000CP43A-xx is not UL certified.

9-5 Environment for Operation, Storage and Transportation

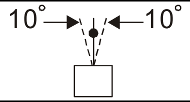
Do NOT expose the AC motor drive in the bad environment, such as dust, direct sunlight, corrosive/inflammable gasses, humidity, liquid and vibration environment. The salt in the air must be less than 0.01mg/cm^2 every year.			
Environment	Installation location	IEC60364-1/IEC60664-1 Pollution degree 2, Indoor use only	
	Surrounding Temperature (ºC)	Storage	-25– +70
		Transportation	-25– +70
		Non-condensation, non-frozen	
	Rated Humidity	Operation	Max. 95%
		Storage/ Transportation	Max. 95%
		No condense water	
	Air Pressure (kPa)	Operation/ Storage	86–106
		Transportation	70–106
	Pollution Level	IEC60721-3-3	
		Operation	Class 3C3; Class 3S2
		Storage	Class 1C2; Class 1S2
		Transportation	Class 2C2; Class 2S2
		If the AC motor drive is to be used under harsh environment with high level of contamination (e.g. dew, water, dust), make sure it is installed in an environment qualified for IP54 such as in a cabinet.	
	Altitude	Operation	If AC motor drive is installed at altitude 0–1000 m, follow normal operation restriction. If it is install at altitude 1000–2000 m, decrease 1% of rated current or lower 0.5ºC of temperature for every 100 m increase in altitude. Maximum altitude for Corner Grounded is 2000 m.Contact Delta for more information, if you need to use this motor drive at an altitude of 2000m or higher.
Package Drop	Storage	ISTA procedure 1A (according to weight) IEC60068-2-31	
	Transportation		
Vibration	1.0mm, peak to peak value range from 2 Hz to 13.2 Hz; 0.7G–1.0G range from 13.2 Hz to 55 Hz; 1.0G range from 55 Hz to 512 Hz. Comply with IEC 60068-2-6		
Impact	IEC/EN 60068-2-27		
Operation Position	Max. allowed offset angle ±10º (under normal installation position)		

Table 9-8

9-6 Specification for Operation Temperature and Protection Level

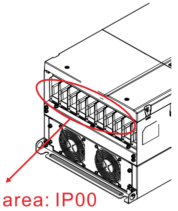
Model	Frame	Top cover	Conduit box	Protection level	Operation temperature
VFDxxxxCP23x-21 VFDxxxxCP43x-21 VFDxxxxCP4Ex-21 VFDxxxxCP53x-21 VFDxxxxCP63x-xx	Frame A–C 230V: 0.75–30 kW 460V: 0.75–37 kW 575V: 1.5–15 kW 690V: 18.5–37 kW	Top cover removed	Standard conduit plate	IP20/UL Open Type	230V&460V: -10°C–50°C *1 575V&690V: -10°C~50°C
		Standard with top cover		IP20/ UL Type1/ NEMA1	-10–40°C
	Frame D–H 230V: 37 kW and above 460V: 45 kW and above 690V: 45 kW and above	N/A	With conduit box	IP20/UL Type1/NEMA1	-10–40°C
VFDxxxxCP23x-00 VFDxxxxCP43x-00 VFDxxxxCP63x-xx	Frame D–H 230V: 37 kW and above 460V: 45 kW and above 690V: 45 kW and above	N/A	No conduit box	IP00 IP20/UL Open Type  The circled area: IP00 Other than the circled area: IP20 Figure 9-1	230V&460V: -10°C–50°C *1 690V: -10°C–50°C

Table 9-9

- *1 When the carrier wave for light duty is 2 kHz, the maximum operation temperature can reach up to 50°C.

9-7 Derating Curve for Ambient Temperature, Altitude and Carrier Frequency

☑ For more information on calculation for derating curve, refer to Pr.06-55.

☑ When choosing the correct model, consider factors such as ambient temperature, altitude, carrier frequency, control mode, and so on. That is,

Actual rated current for application (A) = Rated output current (A) × Ambient temp. rated derating (%) x Altitude rated derating (%) × [Normal / Advanced control] carrier frequency rated derating (%)

Protection Level	Operating Environment
UL Type I / IP20	If the AC motor drive operates at the rated current, the ambient temperature needs to be between -10–40°C. If the temperature is above 40°C, decrease 2% of the rated current for every 1°C increase in temperature. The maximum allowable temperature is 60°C.
UL Open Type / IP20	If the AC motor drive operates at the rated current, the ambient temperature needs to be between -10–50°C. If the temperature is above 50°C, decrease 2% of the rated current for every 1°C increase in temperature. The maximum allowable temperature is 60°C.

Table 9-10

Ambient Temperature Derating Curve

230V / 460V

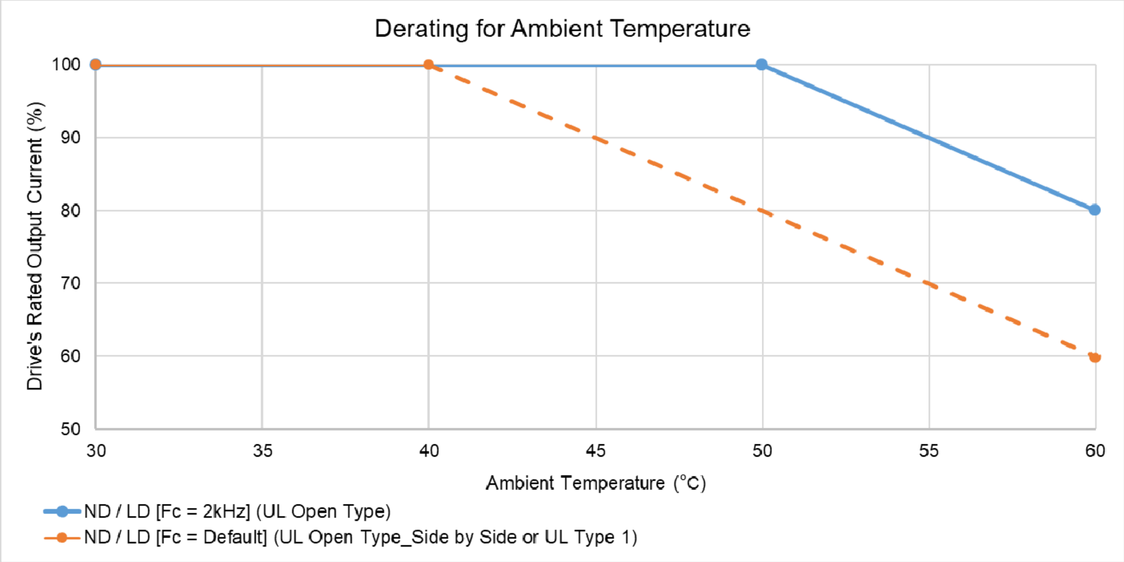


Figure 9-2

UL Open Type:

The rated output current derating (%) in normal duty / light duty when carrier frequency is 2 kHz:

Fc (kHz) \ Ambient Temp. / 100% Load	30°C	50°C	60°C
2	100	100	80

Table 9-11

UL Open Type_Side by Side or UL Type 1:

The rated output current derating (%) in normal duty / light duty when carrier frequency is the default value:

Fc (kHz) \ Ambient Temp. / 100% Load	30°C	40°C	60°C
Default Value	100	100	60

Table 9-12

575V / 690V

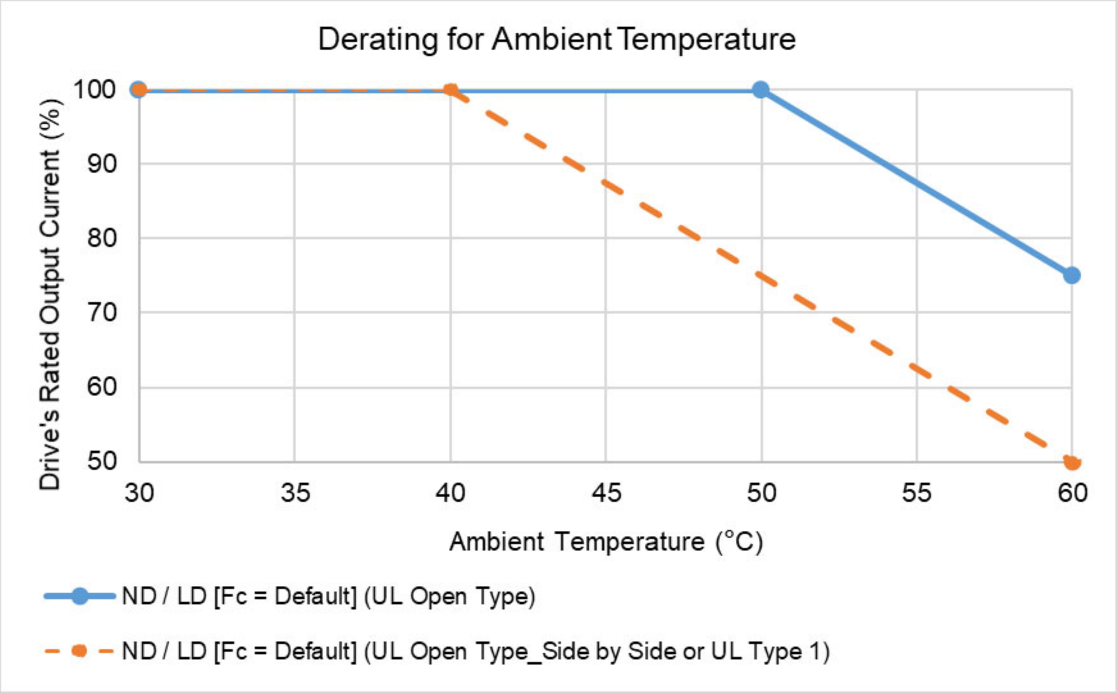


Figure 9-3

UL Open Type:

The rated output current derating (%) in normal duty / light duty when carrier frequency is the default value:

Ambient Temp. / 100% Load Fc (kHz)	30°C	50°C	60°C
Default Value	100	100	75

Table 9-13

UL Open Type_Side by Side or UL Type 1:

The rated output current derating (%) in normal duty / light duty when carrier frequency is the default value:

Ambient Temp. / 100% Load Fc (kHz)	30°C	40°C	60°C
Default Value	100	100	50

Table 9-14

Altitude Derating Curve

Condition	Operating Environment
High Altitude	If the AC motor drive is installed at an altitude of 0–1000 m, follow normal operation restrictions. For altitudes of 1000–2000 m, decrease the drive's rated current by 1% or lower the temperature by 0.5°C for every 100 m increase in altitude. The maximum altitude for corner grounding is 2000 m. If installing at an altitude higher than 2000 m is required, contact Delta for more information.

Table 9-15

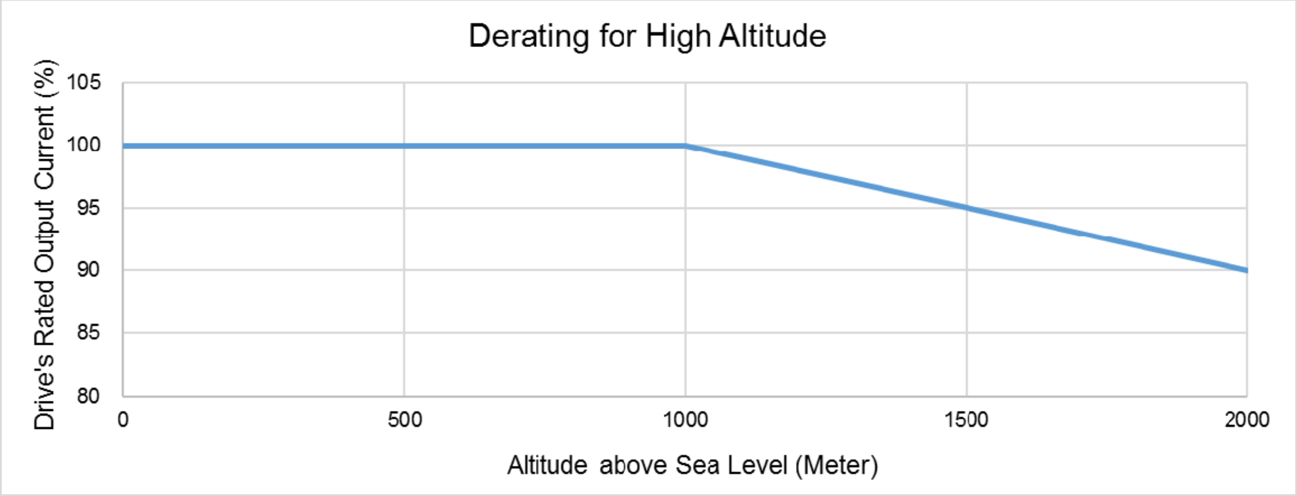


Figure 9-4

The rated output current derating (%) for different altitudes above sea level:

Altitude above Sea Level (Meter)	0	1000	1500	2000
Output Current / Rated Current (%)	100	100	95	90

Table 9-16

Carrier Frequency Derating Curve

- 230V / 460V Normal Control

Pr.00-11 = 0 (IMVF)

= 2 (IM SVC, Pr.05-33 = 0)

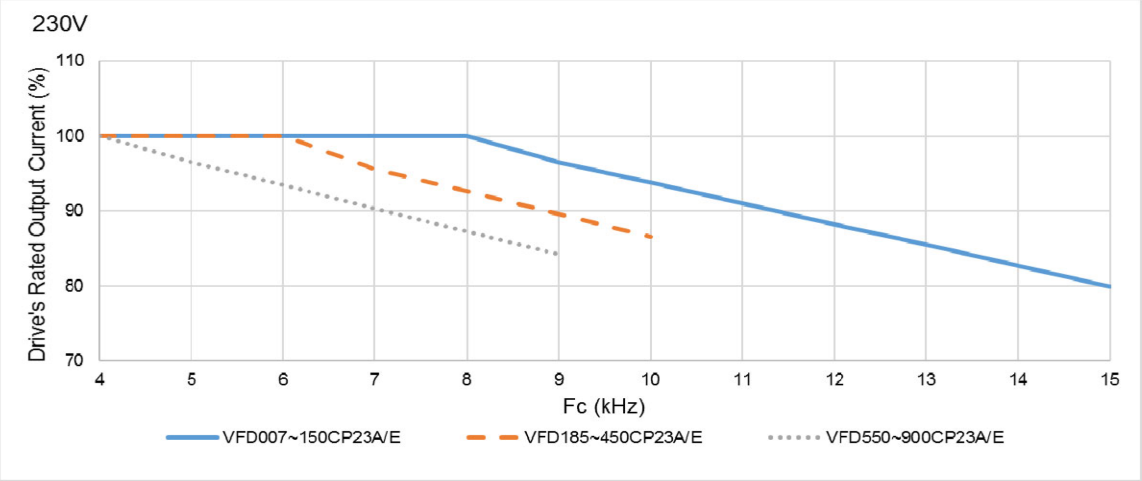


Figure 9-5

The rated output current derating (%) of 230V models in normal control mode for different carrier frequencies:

Fc (kHz) Model No.	4	5	6	7	8	9	10	11	12	13	14	15
VFD007–150CP23A/E	100	100	100	100	100	97	94	91	88	85	83	80
VFD185–450CP23A/E	100	100	100	96	93	90	87	-	-	-	-	-
VFD550–900CP23A/E	100	97	93	90	87	84	-	-	-	-	-	-

Table 9-17

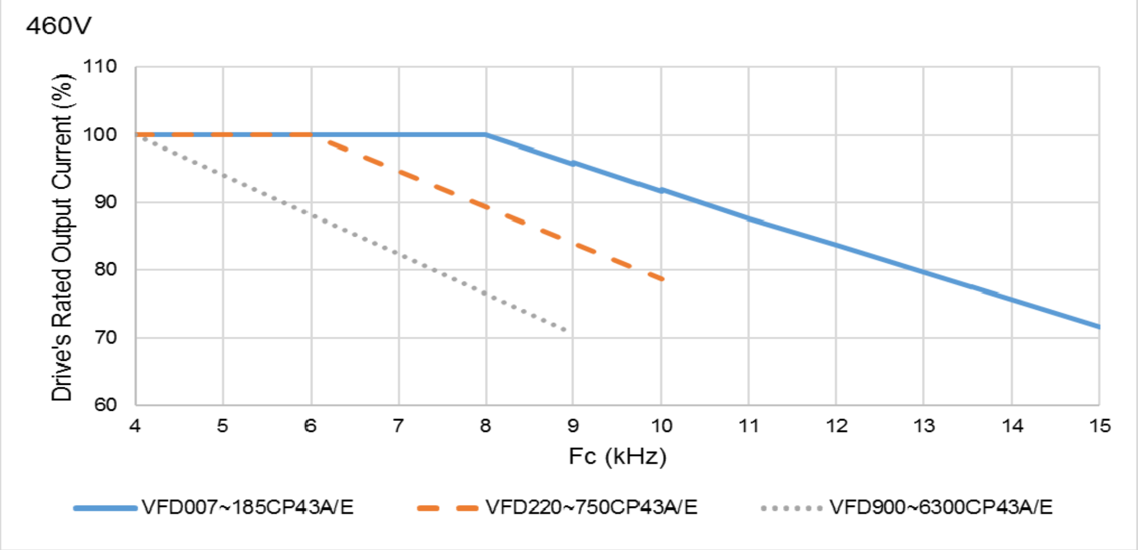


Figure 9-6

The rated output current derating (%) of 460V models in normal control mode for different carrier frequencies:

Fc (kHz) Model No.	4	5	6	7	8	9	10	11	12	13	14	15
VFD007–185CP43A/E	100	100	100	100	100	96	92	88	84	80	76	72
VFD220–750CP43A/E	100	100	100	95	89	84	79	-	-	-	-	-
VFD900–6300CP43A/E	100	94	88	82	76	71	-	-	-	-	-	-

Table 9-18

- 230V / 460V Advanced Control

  Pr.00-11 = 2 (PM SVC, Pr.05-33 = 1, 2)

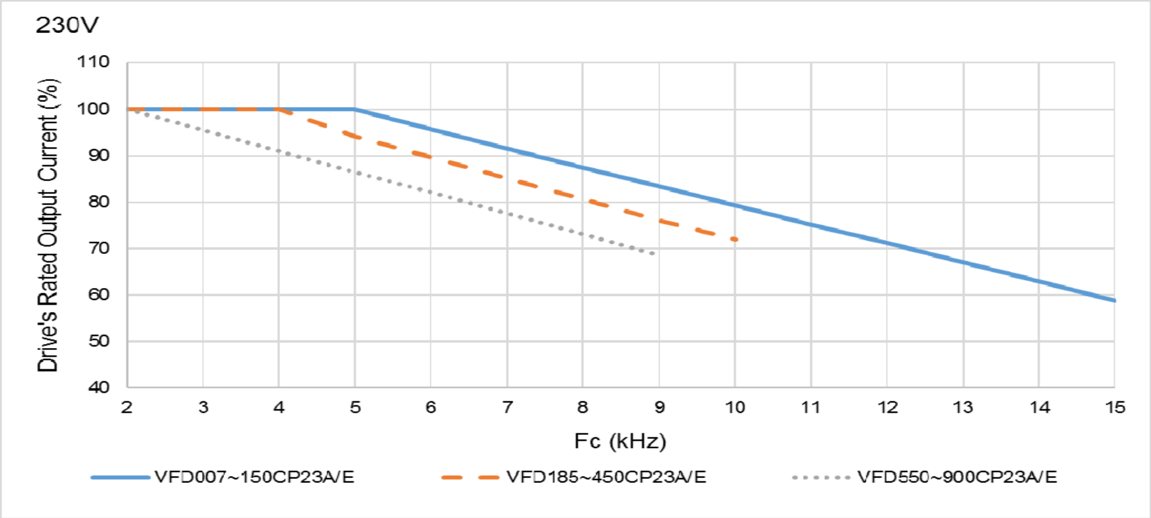


Figure 9-7

The rated output current derating (%) of 230V models in advanced control mode for different carrier frequencies:

Fc (kHz) / Model No.	2	3	4	5	6	7	8	9	10	11	12	13	14	15
VFD007–150CP23A/E	100	100	100	100	96	92	88	83	79	75	71	67	63	59
VFD185–450CP23A/E	100	100	100	94	90	85	81	76	72	-	-	-	-	-
VFD550–900CP23A/E	100	96	91	87	82	78	73	69	-	-	-	-	-	-

Table 9-19

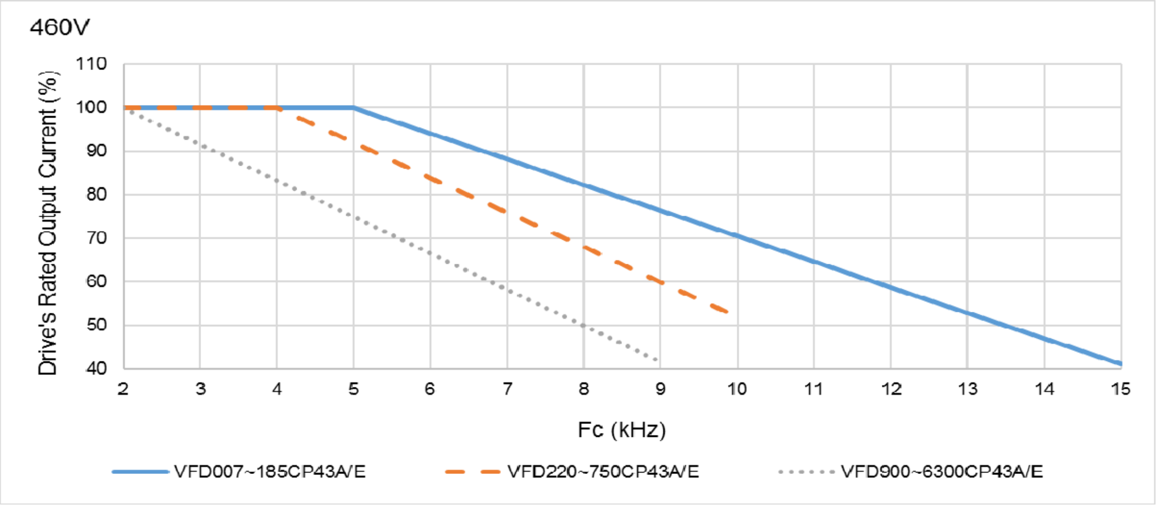


Figure 9-8

The rated output current derating (%) of 460V models in advanced control mode for different carrier frequencies:

Fc (kHz) / Model No.	2	3	4	5	6	7	8	9	10	11	12	13	14	15
VFD007–185CP43A/E	100	100	100	100	94	88	82	76	71	65	59	53	47	41
VFD220–750CP43A/E	100	100	100	92	84	76	68	60	52	-	-	-	-	-
VFD900–6300CP43A/E	100	92	83	75	67	58	50	42	-	-	-	-	-	-

Table 9-20

- 575V / 690V

Pr.00-16 = 2, light duty:

Pr.00-11 = 0 (IMVF)

= 2 (IM SVC, Pr.05-33 = 0)

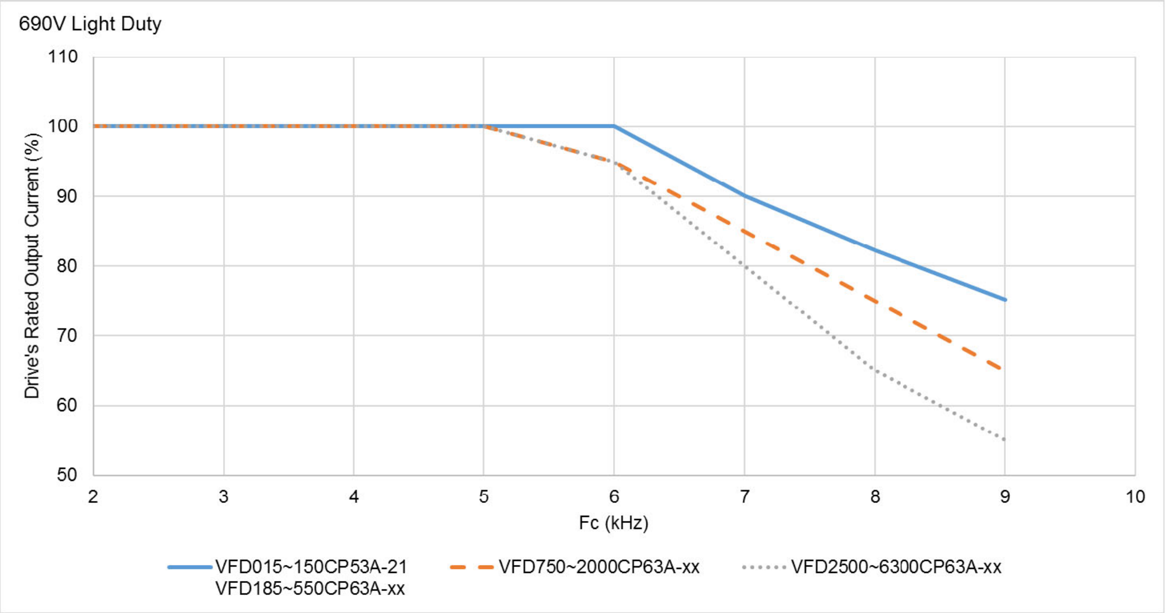


Figure 9-9

The rated output current derating (%) of 575V / 690V models in light duty for different carrier frequencies:

Fc (kHz) / Model No.	2	3	4	5	6	7	8	9
VFD015–150CP53A-21 VFD185–550CP63A-xx	100	100	100	100	100	90	82	75
VFD750–2000CP63A-xx	100	100	100	100	95	85	75	65
VFD2500–6300CP63A-xx	100	100	100	100	95	80	65	55

Table 9-21

Pr.00-16 = 0, normal duty:

Pr.00-11 = 0 (IMVF)

= 2 (IM SVC, Pr.05-33 = 0)

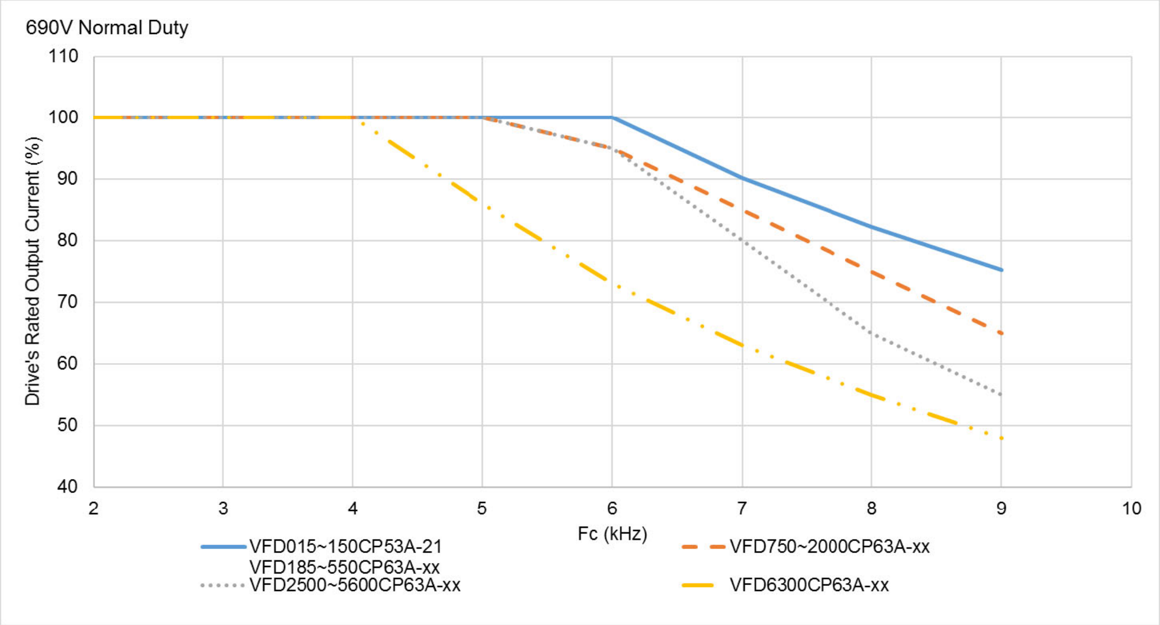


Figure 9-10

The rated output current derating (%) of 575V / 690V models in normal duty for different carrier frequencies:

Fc (kHz) Model No.	2	3	4	5	6	7	8	9
VFD015–150CP53A-21 VFD185–550CP63A-xx	100	100	100	100	100	90	82	75
VFD750–2000CP63A-xx	100	100	100	100	95	85	75	65
VFD2500–6300CP63A-xx	100	100	100	100	95	80	65	55
VFD6300CP63A-xx	100	100	100	86	73	63	55	48

Table 9-22

9-8 Efficiency Curve

- Models:
  VFD007C23A–VFD370C23A
  VFD007C43A–VFD750C43A

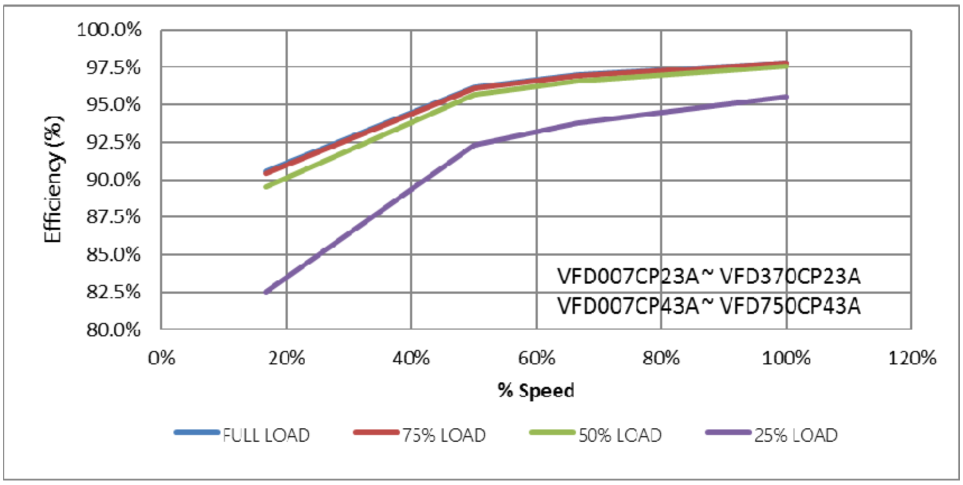


Figure 9-11

Efficiency (%) under different loads:

Speed (%) Load (%)	16.7	50	66.7	100
100% Load	90.6	96.2	97.0	97.8
75% Load	90.4	96.1	96.9	97.8
50% Load	89.5	95.7	96.6	97.6
25% Load	82.5	92.3	93.8	95.5

Table 9-23

- Models:
  VFD450C23A–VFD900C23A
  VFD900C43A–VFD4500C43A

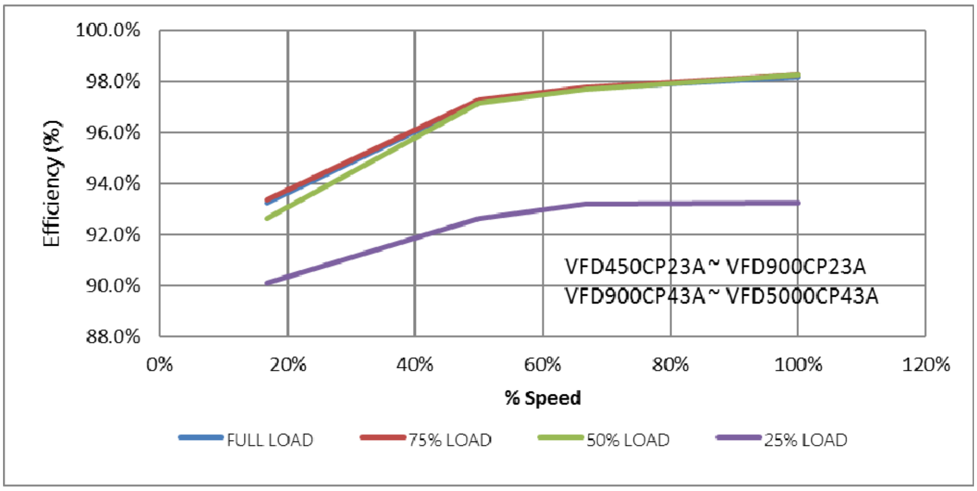


Figure 9-12

Efficiency (%) under different loads:

Speed (%) Load (%)	16.7	50	66.7	100
100% Load	93.2	97.2	97.7	98.2
75% Load	93.4	97.3	97.8	98.3
50% Load	92.6	97.1	97.7	98.2
25% Load	90.1	92.6	93.2	93.2

Table 9-24

Chapter 10 Digital Keypad

10-1 Descriptions of Digital Keypad

10-2 Function of Digital Keypad KPC-CC01

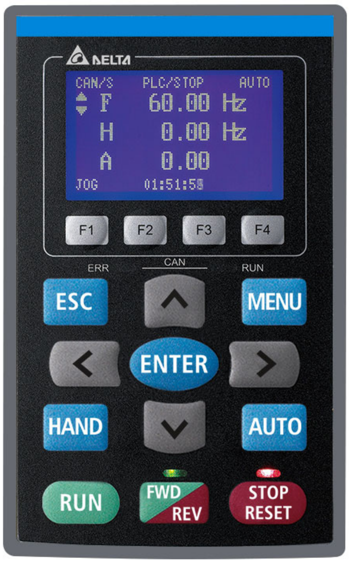
10-3 TPEditor Installation Instruction

10-4 Fault Code Description of Digital Keypad KPC-CC01

10-5 Unsupported Functions when using TPEditor on KPC-CC01 Keypad

10-1 Descriptions of Digital Keypad

KPC-CC01



Communication Interface
RJ45 (socket), RS-485 interface

Communication protocol:
RTU19200, 8, N, 2

Installation Method

1. The embedded type can be installed on the surface of the control box. The front cover is waterproof.
2. Buy a MKC-KPPK model for wall mounting or embedded mounting. Its protection level is IP66.
3. The maximum RJ45 extension lead is 5 m (16ft).
4. This keypad can only be used on Delta's motor drive C2000 series, CH2000 and CP2000 series.

Keypad Functions Description

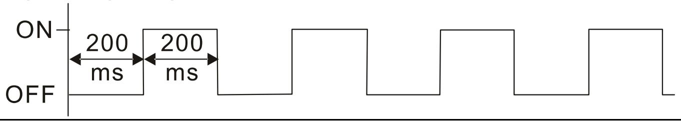
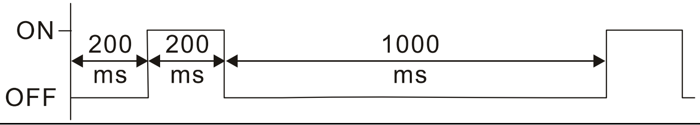
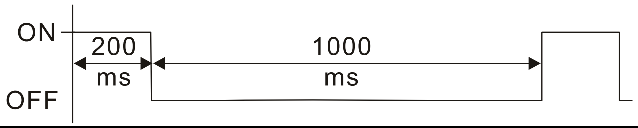
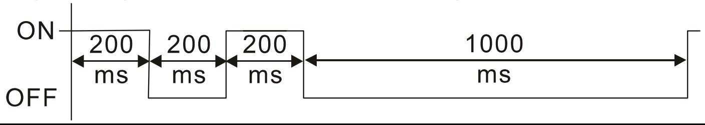
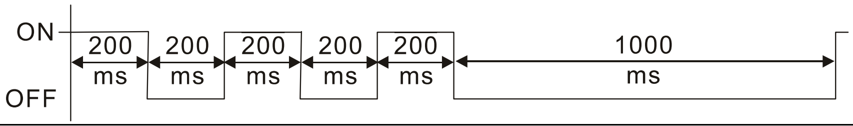
Key	Descriptions
RUN	Start Operation Key 1. Only valid when the source of operation command is the keypad. 2. Operates the AC motor drive by the function setting. The RUN LED will be ON. 3. Can be pressed repeatedly at the stop process.
STOP RESET	Stop Command Key. 1. This key has the highest priority when the command is from the keypad. 2. When it receives the STOP command, regardless of whether the AC motor drive is in operation or stop status, the AC motor drive executes the "STOP" command. 3. Use the RESET key to reset the drive after a fault occurs. 4. If you cannot reset after the error: a. The condition which triggers the fault is not cleared. After you clear the condition, you can then reset the fault. b. The drive is in fault status when powered on. After you clear the condition, restart and then you can reset the fault.
FWD REV	Operation Direction Key 1. Only controls the operation direction, NOT the drive activation. FWD: forward, REV: reverse. 2. Refer to the LED descriptions for more details.
ENTER	ENTER Key Goes to the next menu level. If at the last level, press ENTER to execute the command.
ESC	ESC Key Leaves the current menu and returns to the previous menu; also functions as a return key or cancel key in a sub-menu.
MENU	Returns to the main menu. Menu commands: 1. Parameter Setup 2. Quick Start 3. Application Selection List 4. Changed List 5. Copy Parameter 6. Fault Record 7. Language Setup 8. Time Setup 9. Keypad Locked 10. PLC Function 11. Copy PLC 12. Display Setup 13. Start-up Menu 14. Main Page 15. PC Link 16. Start Wizard

Key	Descriptions
< > ∧ ∨	Direction: Left / Right / Up / Down 1. In the numeric value setting mode, moves the cursor and changes the numeric value. 2. In the menu / text selection mode, selects an item.
F1 F2 F3 F4	Function Key 1. The functions keys have defaults and can also be user-defined. The defaults for F1 and F4 work with the function list below. For example, F1 is the JOG function, and F4 is a speed setting key for adding / deleting user-defined parameters. 2. Other functions must be defined using TPEditor. Download TPEditor software at Delta website. Select TPEditor version 1.60 or above. Refer to the installation instruction for TPEditor in Section 10-3.
HAND	HAND Key 1. Use this key to select HAND mode. In this mode, the drive's parameter settings for frequency command source is Pr.00-30, and that for operation command source is Pr.00-31. 2. Press the HAND key at STOP, then the setting switches to the HAND frequency source and HAND operation source. 3. Press HAND key at RUN, and it stops the AC motor drive first (displays AHSP warning), and switches to HAND frequency source and HAND operation source. 4. Successful mode switching for the KPC-CC01 displays HAND mode on the screen.
AUTO	AUTO Key 1. The default of the drive is AUTO mode. 2. Use this key to select AUTO mode. In this mode, the drive's parameter settings for frequency command source is Pr.00-20, and that for operation command is Pr.00-21. 3. Press the AUTO key at STOP, then the setting switches to the AUTO frequency source and AUTO operation source. 4. Press AUTO key at RUN, and it stops the AC motor drive first (displays AHSP warning), and switches to AUTO frequency source and AUTO operation source. 5. Successful mode switching for the KPC-CC01 displays AUTO mode on the screen.

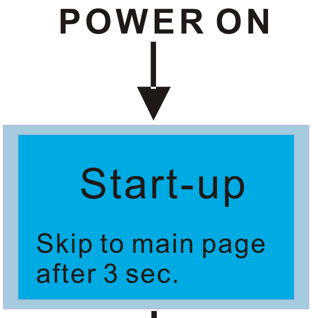
NOTE The defaults for the frequency command and operation command source of HAND / AUTO mode are both from the keypad.

LED Functions Descriptions

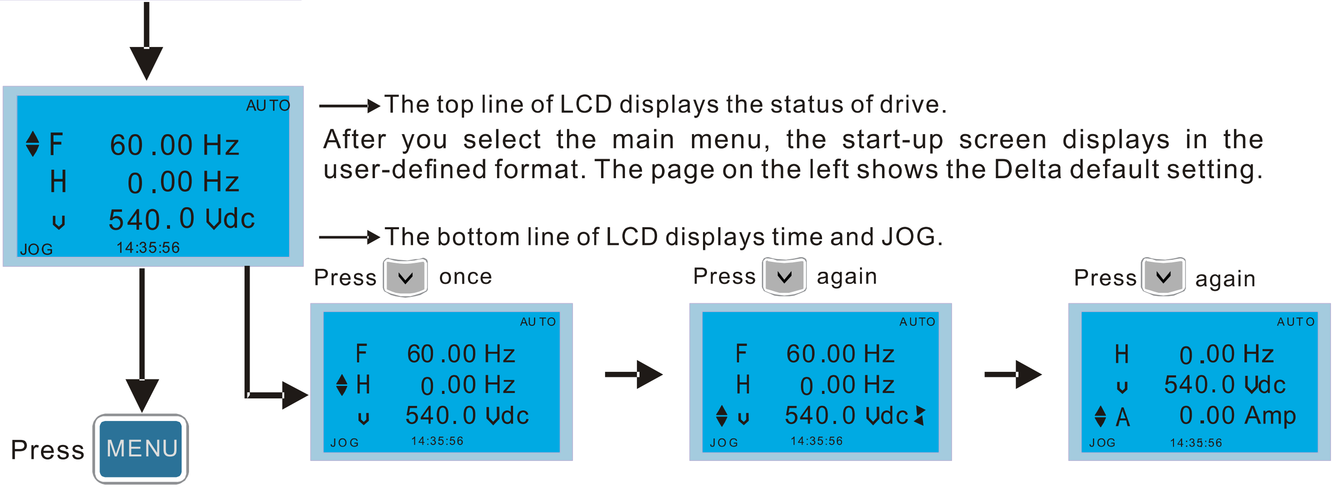
LED	Descriptions
STOP RESET	Steady ON: STOP indicator for the AC motor drive. Blinking: the drive is in standby. Steady OFF: the drive does not execute the "STOP" command.
FWD REV	Operation Direction LED 1. Green light: the drive is running forward. 2. Red light: the drive is running backward. 3. Flashing light: the drive is changing direction. Operation Direction LED under Torque Mode 1. Green light: when the torque command ≥ 0, and the motor is running forward. 2. Red light: when the torque command < 0, and the motor is running backward. 3. Flashing light: when the torque command < 0, and the motor is running forward.

<table>
<tr><th>LED</th><th>Descriptions</th></tr>
<tr><td>CANopen–“RUN”</td><td>RUN LED:
<table>
<tr><th>LED status</th><th>Condition/ State</th></tr>
<tr><td>OFF</td><td>CANopen at initial
No LED</td></tr>
<tr><td>Blinking</td><td>CANopen at pre-operation
 </td></tr>
<tr><td>Single flash</td><td>CANopen at stop
 </td></tr>
<tr><td>ON</td><td>CANopen at operation status
 </td></tr>
</table></td></tr>
<tr><td>CANopen–“ERR”</td><td>ERR LED:
<table>
<tr><th>LED status</th><th>Condition/ State</th></tr>
<tr><td>OFF</td><td>No Error</td></tr>
<tr><td>Single flash</td><td>One message fail
 </td></tr>
<tr><td>Double flash</td><td>Node guarding failure or heartbeat message failure
 </td></tr>
<tr><td>Triple flash</td><td>Synchronization failure
 </td></tr>
<tr><td>ON</td><td>Bus off
 </td></tr>
</table></td></tr>
</table>

10-2 Function of Digital Keypad KPC-CC01



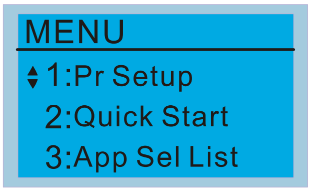
1) The default Start-up page is Delta Logo. (Default 1 and 2)
2) User can customize their start-up page through the edited function. (Need to purchase the optional accessories.)



The top line of LCD displays the status of drive.

After you select the main menu, the start-up screen displays in the user-defined format. The page on the left shows the Delta default setting.

The bottom line of LCD displays time and JOG.



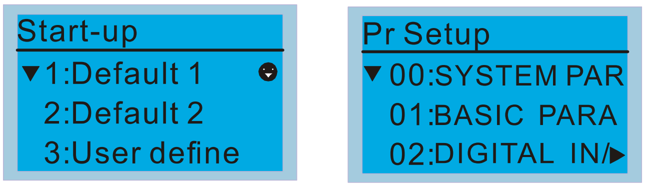
MENU

1: Parameter Setup
2: Quick Start
3: Application Selection List
4: Changed List
5: Copy Parameter
6: Fault Record
7: Language Setup
8: Time Setup
9: Keypad Locked
10: PLC Function
11: Copy PLC
12: Display Setup
13: Start-up Menu
14: Main Page
15: PC Link
16: Start Wizard

NOTE

1. Start-up screen can only display pictures, not animation.
2. When powered ON, it displays the start-up screen then the main screen. The main screen displays Delta's default setting F/H/A/U. You can set the display order with Pr.00-03 (Start-up display). When you selected the U screen, use the left / right keys to switch between the items, and set the display order for the U screen with Pr.00-04 (User display).

Display Icon



● : present setting

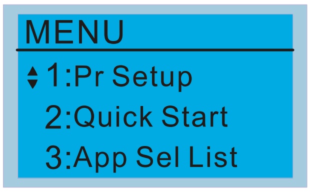
▼ : Scroll down the page for more options

Press ⌃ ⌄ for more options

▶ : show complete sentence

Press ‹ › for complete information

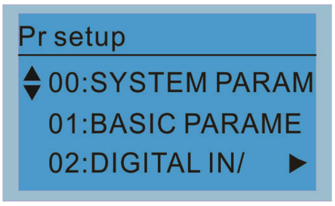
Display item



MENU

1: Parameter Setup
2: Quick Start
3: Application Selection List
4: Changed List
5: Copy Parameter
6: Fault Record
7: Language Setup
8: Time Setup
9: Keypad Locked
10: PLC Function
11: Copy PLC
12: Display Setup
13: Start-up Menu
14: Main Page
15: PC Link
16: Start Wizard

1. Parameter Setup



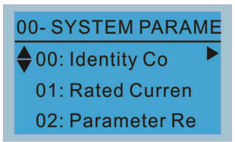
```
Pr setup
⬍00:SYSTEM PARAM
 01:BASIC PARAME
 02:DIGITAL IN/  ►
```

Press ENTER to select.

Press ⌃ ⌄ to select the parameter group.

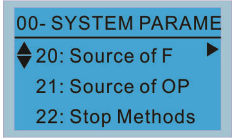
Once you select a parameter group, press ENTER to go into that group.

For example: Setup source for the master frequency command.



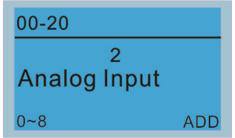
```
00- SYSTEM PARAME
⬍00: Identity Co  ►
 01: Rated Curren
 02: Parameter Re
```

In the Group 00 Motor Drive Parameter, use Up/Down keys to select parameter 20: Auto Frequency Command.



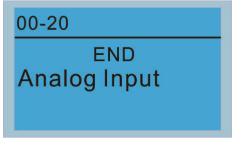
```
00- SYSTEM PARAME
⬍20: Source of F  ►
 21: Source of OP
 22: Stop Methods
```

Press ENTER to go to this parameter's setting menu.



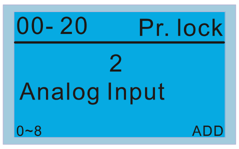
```
00-20
        2
Analog Input
0~8              ADD
```

Use the Up/Down keys to choose a setting.
For example: choose 2 Analog Input, and then press ENTER key.



```
00-20
       END
Analog Input
```

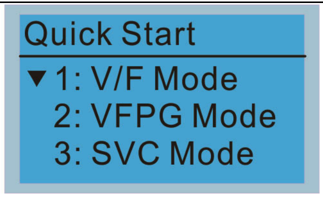
After you press ENTER, END is displayed which means the parameter setting is done.



```
00- 20       Pr. lock
        2
Analog Input
0~8              ADD
```

NOTE: When parameter lock / password protection function is enabled, it displays "Pr. lock" on the upper right corner of the keypad. The parameter cannot be written or is protected by the password under this circumstances.

2. Quick Start



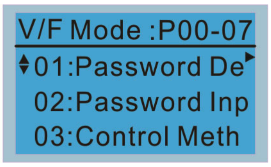
```
Quick Start
▼1: V/F Mode
 2: VFPG Mode
 3: SVC Mode
```

Press ENTER to select.

Quick Start:
1. V/F Mode
2. SVC Mode
3. My Mode

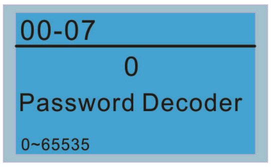
Description:

1. VF Mode



```
V/F Mode :P00-07
⬍01:Password De►
 02:Password Inp
 03:Control Meth
```

01:Password Decoder

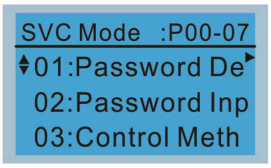


```
00-07
        0
Password Decoder
0~65535
```

Items
1. Parameter protection password input (Pr.00-07)
2. Parameter protection password setting (Pr.00-08)
3. Speed control mode (Pr.00-11)
4. Load selection (Pr.00-16)
5. Carrier frequency (Pr.00-17)
6. Master frequency command source (AUTO) / Source selection of the PID target (Pr.00-20)
7. Operation command source (AUTO) (Pr.00-21)
8. Stop method (Pr.00-22)
9. Digital keypad STOP function (Pr.00-32)
10. Max. operation frequency (Pr.01-00)
11. Output frequency of motor 1 (Pr.01-01)
12. Output voltage of motor 1 (Pr.01-02)
13. Mid-point frequency 1 of motor 1 (Pr.01-03)
14. Mid-point voltage 1 of motor 1 (Pr.01-04)
15. Mid-point frequency 2 of motor 1 (Pr.01-05)
16. Mid-point voltage 2 of motor 1 (Pr.01-06)
17. Min. output frequency of motor 1 (Pr.01-07)
18. Min. output voltage of motor 1 (Pr.01-08)
19. Output frequency upper limit (Pr.01-10)

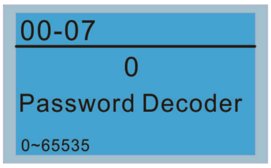
20. Output frequency lower limit (Pr.01-11)
21. Acceleration time 1 (Pr.01-12)
22. Deceleration time 1 (Pr.01-13)
23. Over-voltage stall prevention (Pr.06-01)
24. Derating protection (Pr.06-55)
25. Software brake chopper action level (Pr.07-00)
26. Speed tracking during start-up (Pr.07-12)
27. Emergency stop (EF) & force to stop selection (Pr.07-20)
28. Torque command filter time (Pr.07-24)
29. Slip compensation filter time (Pr.07-25)
30. Torque compensation gain (Pr.07-26)
31. Slip Compensation Gain (Pr.07-27)

2. SVC Mode



```
SVC Mode   :P00-07
01:Password De
 02:Password Inp
 03:Control Meth
```

01: Password Decoder



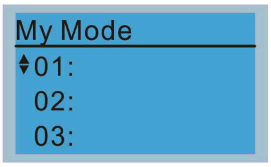
```
00-07
        0
Password Decoder
0~65535
```

Items

1. Parameter protection password input (Pr.00-07)
2. Parameter protection password setting (Pr.00-08)
3. Speed control mode (Pr.00-11)
4. Load selection (Pr.00-16)
5. Carrier frequency (Pr.00-17)
6. Master frequency command source (AUTO) / Source selection of the PID target (Pr.00-20)
7. Operation command source (AUTO) (Pr.00-21)
8. Stop method (Pr.00-22)
9. Digital keypad STOP function (Pr.00-32)
10. Max. operation frequency (Pr.01-00)
11. Output frequency of motor 1 (Pr.01-01)
12. Output voltage of motor 1 (Pr.01-02)
13. Min. output frequency of motor 1 (Pr.01-07)
14. Min. output voltage of motor 1 (Pr.01-08)
15. Output frequency upper limit (Pr.01-10)
16. Output frequency lower limit (Pr.01-11)
17. Acceleration time 1 (Pr.01-12)
18. Deceleration time 1 (Pr.01-13)
19. Full-load current for induction motor 1 (Pr.05-01)
20. Rated power for induction motor 1 (Pr.05-02)
21. Rated speed for induction motor 1 (Pr.05-03)
22. Number of poles for induction motor 1 (Pr.05-04)
23. No-load current for induction motor 1 (Pr.05-05)
24. Over-voltage stall prevention (Pr.06-01)
25. Over-current stall prevention during acceleration (Pr.06-03)
26. Derating protection (Pr.06-55)

27. Software brake chopper action level (Pr.07-00)
28. Emergency stop (EF) & Force to stop selection (Pr.07-20)
29. Torque command filter time (Pr.07-24)
30. Slip compensation filter time (Pr.07-25)
31. Slip compensation gain (Pr.07-27)

3. My Mode


My Mode
01:
02:
03:

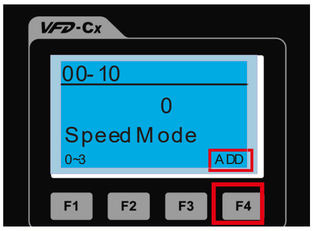
Press F4 in parameter setting screen to save the parameter to My Mode. To delete or correct the parameter, select this parameter and press F4 for DEL in the bottom right corner.

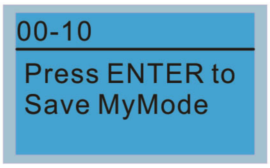
Items

It can save 1–32 sets of parameters (Pr).

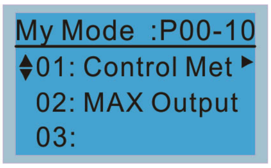
Setup process

1. Go to Parameter Setup function.
   Press ENTER to select the parameter to use. There is an ADD on the bottom right corner of the screen. Press F4 to add this parameter to My Mode.

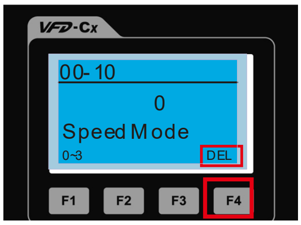

00- 10
0
Speed Mode
0~3
ADD

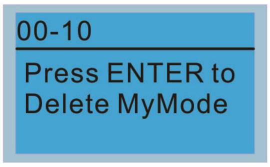

00-10
Press ENTER to
Save MyMode

2. The parameter (Pr) displays in My mode if it is properly saved.
   To correct or to delete this parameter, press F4 for DEL.

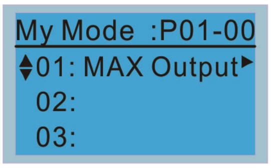

My Mode :P00-10
01: Control Met
02: MAX Output
03:

3. To delete a parameter, go to My Mode and select the parameter to delete. Press ENTER to enter the parameter setting screen. DEL appears in the bottom left corner of the screen. Press F4 to delete this parameter from My Mode.

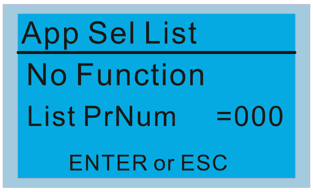

00- 10
0
Speed Mode
0~3
DEL


00-10
Press ENTER to
Delete MyMode

4. After you press ENTER to delete <01 Control Mode>, the <02 Maximum Operating Frequency > automatically replaces <01 Control Mode>.

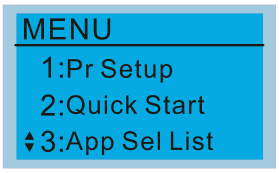

My Mode :P01-00
01: MAX Output
02:
03:

3. Application Selection List

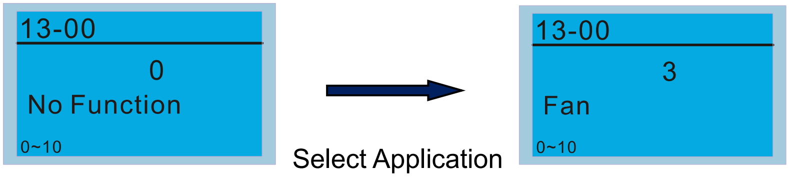

App Sel List
No Function
List PrNum =000
ENTER or ESC

This function enables you to select application and its parameters sets.

Example:
In the menu content, select 3: Application Selection List


MENU
1:Pr Setup
2:Quick Start
3:App Sel List

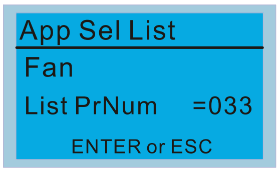
Press ENTER to go into the Application Selection List


13-00
0
No Function
0~10

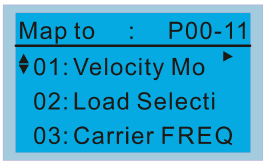
13-00
3
Fan
0~10

Select Application

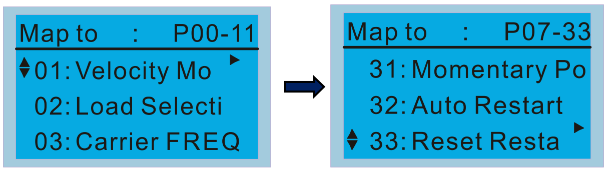
Press ENTER to enter the application selection screen, and the selected application industry is “Fan”.


App Sel List
Fan
List PrNum =033
ENTER or ESC

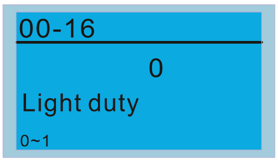
Press ENTER to enter the Fan application screen.


Map to : P00-11
01: Velocity Mo
02: Load Selecti
03: Carrier FREQ

Press the Up/ Down keys to select the parameter to set.

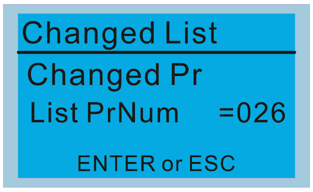

Map to : P00-11
01: Velocity Mo
02: Load Selecti
03: Carrier FREQ

Map to : P07-33
31: Momentary Po
32: Auto Restart
33: Reset Resta


00-16
0
Light duty
0~1

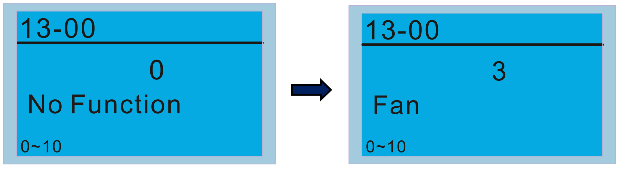
Choose 0: Light duty or 1: Normal duty according to your needs, then press ENTER.

4. Changed List



Changed List
Changed Pr
List PrNum =026
ENTER or ESC

This function records the parameters you have changed.
Example:
Set Pr.13-00 Application Selection = 3: Fan

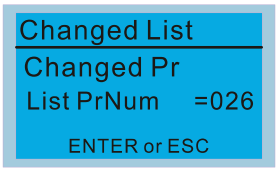


13-00
0
No Function
0~10

➡

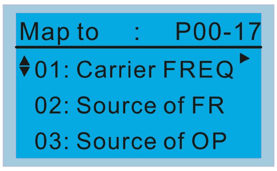
13-00
3
Fan
0~10

Enter the changed list screen. List PrNum = 026 means that there are 26 parameters that have been changed.



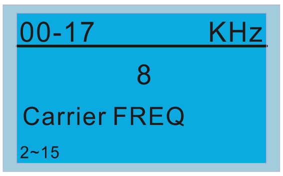
Changed List
Changed Pr
List PrNum =026
ENTER or ESC

Press ENTER to enter the changed list screen.



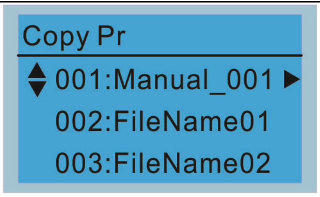
Map to : P00-17
▲▼01: Carrier FREQ ▶
02: Source of FR
03: Source of OP

Use the Up / Down keys to select the parameters to check or to change.
Press ENTER to enter the parameter.



00-17 KHz
8
Carrier FREQ
2~15

5. Copy Parameter



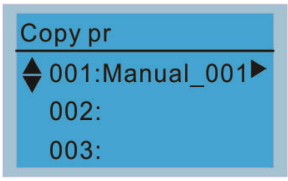
Copy Pr
▲▼001:Manual_001 ▶
002:FileName01
003:FileName02

Press ENTER key to go to

001–004: content storage

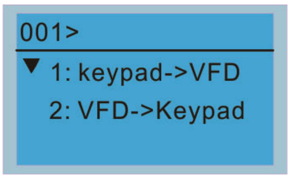
Four groups of parameters are available to copy
The steps are shown in the example below.

Example: parameter saved in the motor drive.



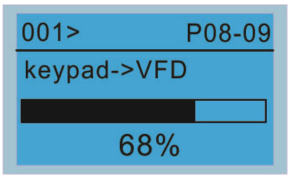
Copy pr
▲▼001:Manual_001 ▶
002:
003:

1. Go to Copy Parameter
2. Select the parameter group to copy and press ENTER.



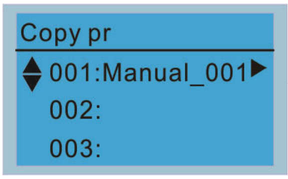
001>
▼ 1: keypad->VFD
2: VFD->Keypad

1. Select 1: keypad → VFD
2. Press ENTER to go to the “keypad → VFD” screen.



001> P08-09
keypad->VFD
68%

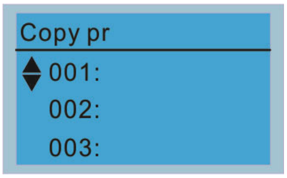
Begin copying parameters until it is done.



Copy pr
▲▼001:Manual_001 ▶
002:
003:

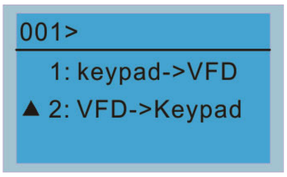
After copying is done, the keypad automatically returns to this screen.

Example: parameter saved in the keypad.



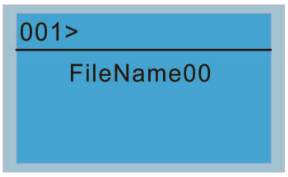
Copy pr
▲▼ 001:
002:
003:

1. Go to Copy parameter
2. Select the parameter group to copy and press ENTER.



001>
1: keypad->VFD
▲ 2: VFD->Keypad

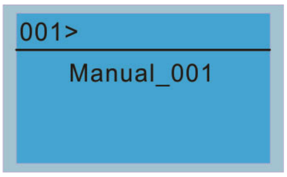
Press ENTER key to go to the “VFD → keypad” screen.



001>
FileName00

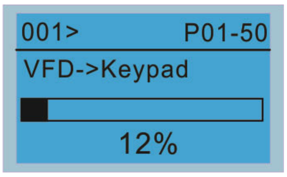
Press the Up / Down keys to select a symbol. Press the Left / Right keys to move the cursor to select a file name.

String & Symbol Table:
！” ＃＄％＆’ （）＊＋，－．／０１２３４５６７８９：；＜＝＞？＠ＡＢＣＤＥＦ
ＧＨＩＪＫＬＭＮＯＰＱＲＳＴＵＶＷＸＹＺ〔＼〕︿＿ ‘ａｂｃｄｆｇｈｉｊｋｌｍ
ｎｏｐｑｒｓｔｕｖｗｘｙｚ｛｜｝～



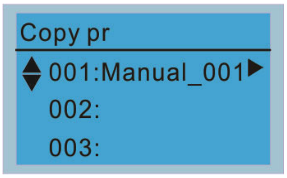
001>
Manual_001

After you confirm the file name, press ENTER.



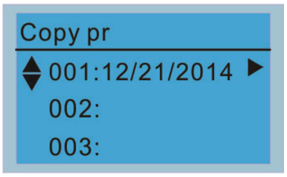
001> P01-50
VFD->Keypad
12%

Begin copying parameters until it is done.



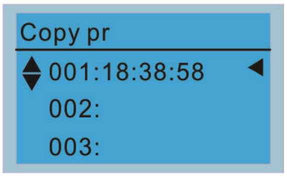
Copy pr
▲▼ 001:Manual_001 ►
002:
003:

After copying parameters is done, the keypad automatically returns to this screen.



Copy pr
▲▼ 001:12/21/2014 ►
002:
003:

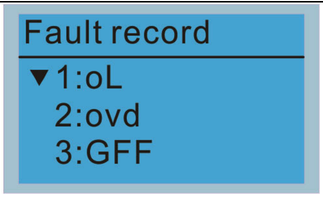
Press the Right key to see the date of the parameters copied.



Copy pr
▲▼ 001:18:38:58 ◄
002:
003:

Press the Right key to see the time of the parameters copied.

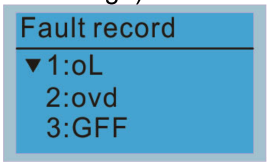
6. Fault Record



Fault record
▼1:oL
2:ovd
3:GFF

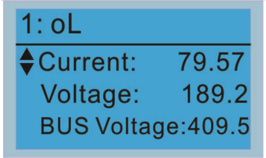
Press **ENTER** to see an error record's details.

Able to store 6 error codes (Keypad V1.02 and previous versions)
Able to store 30 error codes (Keypad V1.20 and later version)
The most recent error record shows as the first record. Choose an error record to see details such as date, time, frequency, current, voltage, and DC bus voltage)

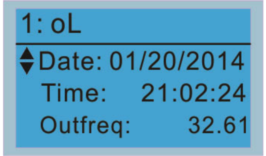


Fault record
▼1:oL
2:ovd
3:GFF

Press the Up / Down keys to select an error record. Press ENTER to see that error record's details.

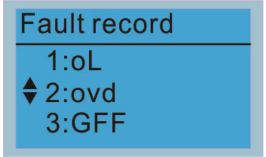


1: oL
⬍Current: 79.57
Voltage: 189.2
BUS Voltage:409.5



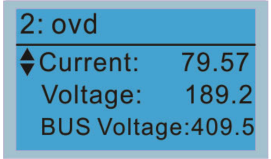
1: oL
⬍Date: 01/20/2014
Time: 21:02:24
Outfreq: 32.61

Press the Up / Down keys to scroll through an error record's details such as date, time, frequency, current, voltage, and DC bus voltage.

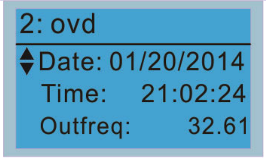


Fault record
1:oL
⬍2:ovd
3:GFF

Press the Up / Down keys to select the next error code.
After selecting an error code, press ENTER to see that error record's details.



2: ovd
⬍Current: 79.57
Voltage: 189.2
BUS Voltage:409.5



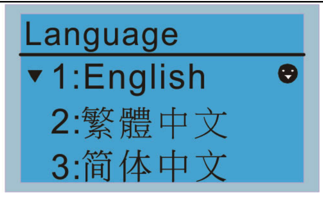
2: ovd
⬍Date: 01/20/2014
Time: 21:02:24
Outfreq: 32.61

Press the Up / Down keys to see an error record's details such as date, time, frequency, current, voltage, and DC bus voltage.

NOTE

The AC motor drive actions are recorded and saved to the KPC-CC01. When you remove the KPC-CC01 and connect it to another AC motor drive, the previous fault records are not deleted. The new fault records of the new AC motor drive continue to be added to the KPC-CC01.

7. Language Setup



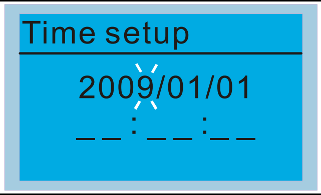
Language
▼1:English
2:繁體中文
3:简体中文

Use the Up / Down keys to select the language, and then press ENTER.

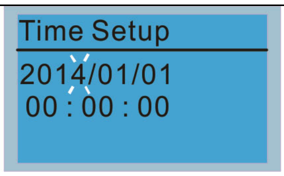
The language setting option is displayed in the language of your choice.
Language setting options:

1. English
2. 繁體中文
3. 简体中文
4. Türkçe
5. Русский
6. Español
7. Português
8. Français
9. Polski
10. Deutsch
11. Italiano
12. Svenska

8. Time Setup

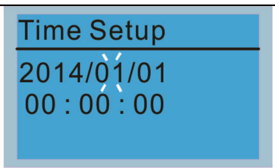
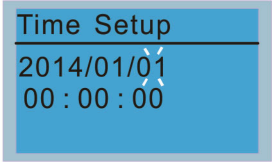
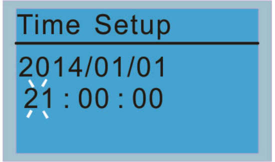
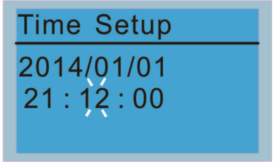
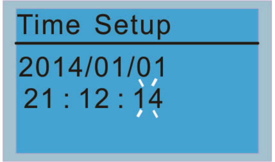
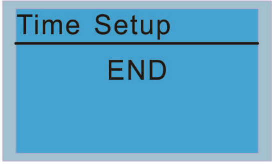


Time setup
2009/01/01
__:__:__

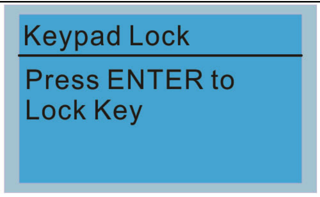
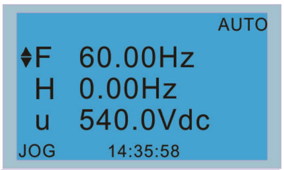
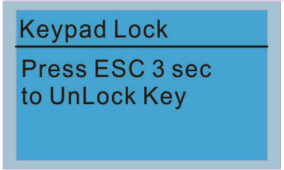
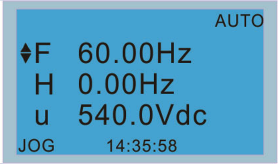
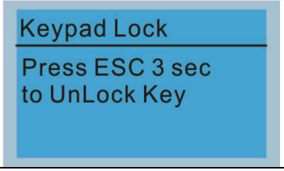


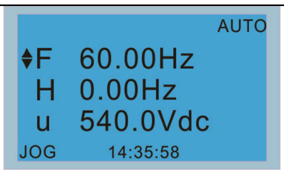
Time Setup
2014/01/01
00 : 00 : 00

Press the Up / Down keys to set the Year

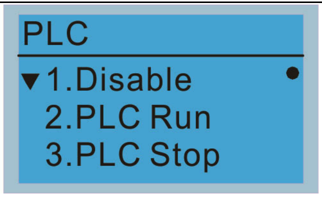
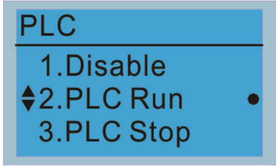
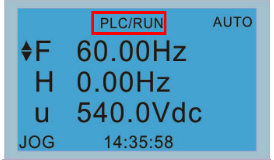
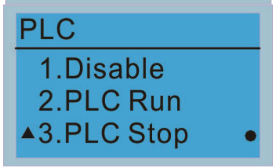
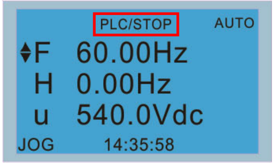
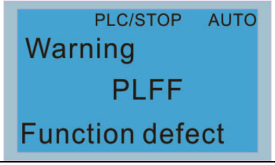
Use the Left / Right keys to select Year, Month, Day, Hour, Minute or Second to change.	 Time Setup 2014/01/01 00 : 00 : 00	Press the Up / Down keys to set the Month
	 Time Setup 2014/01/01 00 : 00 : 00	Press the Up / Down keys to set the Day
	 Time Setup 2014/01/01 21 : 00 : 00	Press the Up / Down keys to set the Hour
	 Time Setup 2014/01/01 21 : 12 : 00	Press the Up / Down keys to set the Minute
	 Time Setup 2014/01/01 21 : 12 : 14	Press the Up / Down keys to set the Second
	 Time Setup END	Press ENTER to confirm the Time Setup.
	NOTE Limitation: The charging process for the keypad super capacitor finishes in about 6 minutes. **When the digital keypad is removed, the time setting is saved for 7 days**. After 7 days, you must reset the time.	

9. Keypad Locked

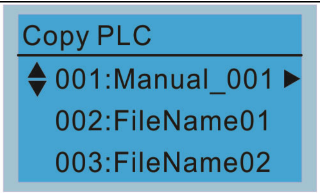
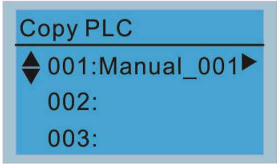
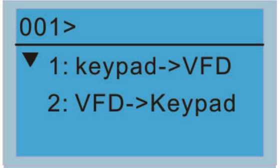
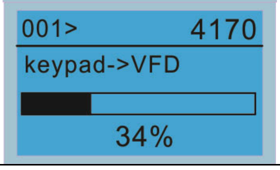
 Keypad Lock Press ENTER to Lock Key Press **ENTER** to lock	Lock the keypad Use this function to lock the keypad. The main screen does not display "keypad locked" when the keypad is locked; however, it displays the message" Press ESC 3 sec to UnLock Key" when you press any key.	
	 AUTO ♦F 60.00Hz H 0.00Hz u 540.0Vdc JOG 14:35:58	When the keypad is locked, the main screen does not indicate the lock status.
	 Keypad Lock Press ESC 3 sec to UnLock Key	Press any key on the keypad; a message displays as shown on the left.
	 AUTO ♦F 60.00Hz H 0.00Hz u 540.0Vdc JOG 14:35:58	If you do not press the ESC key, the keypad automatically returns to this screen.
	 Keypad Lock Press ESC 3 sec to UnLock Key	Press any key on the keypad, a message displays as shown on the left.

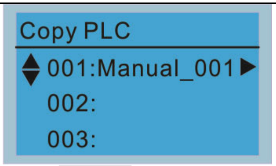
	 AUTO F 60.00Hz H 0.00Hz u 540.0Vdc JOG 14:35:58 Press ESC for 3 seconds to unlock the keypad; the keypad returns to this screen. All keys on the keypad is functional. All keys on the keypad is functional. Turning the power off and on does not lock the keypad.

10. PLC Function

 PLC ▼1.Disable ● 2.PLC Run 3.PLC Stop Press the Up/Down keys to select a PLC's function, and then press ENTER.	When activating and stopping the PLC function (choosing 2: PLC Run or 3: PLC Stop), the PLC status displays on main screen (Delta default setting).  PLC 1.Disable 2.PLC Run ● 3.PLC Stop Choose option 2: PLC Run to enable the PLC function.  PLC/RUN AUTO F 60.00Hz H 0.00Hz u 540.0Vdc JOG 14:35:58 The default on the main screen displays the PLC / RUN status message.  PLC 1.Disable 2.PLC Run ▲3.PLC Stop ● Choose option 3: PLC Stop to disable the PLC function.  PLC/STOP AUTO F 60.00Hz H 0.00Hz u 540.0Vdc JOG 14:35:58 The default on the main screen displays the PLC / STOP status message.  PLC/STOP AUTO Warning PLFF Function defect If the PLC program is not available in the control board, the PLFF warning displays when you choose option 2 or 3. In this case, choose option 1: Disable to clear PLFF warning.

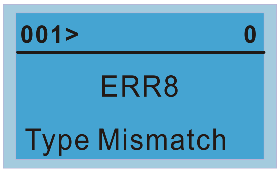
11. Copy PLC

 Copy PLC 001:Manual_001 ▶ 002:FileName01 003:FileName02	Four groups of parameters are available to copy. The steps are shown in the example below. Example: PLC program saved in the motor drive.  Copy PLC 001:Manual_001▶ 002: 003: 1. Go to Copy PLC 2. Select the PLC program to copy and press ENTER.  001> ▼ 1: keypad->VFD 2: VFD->Keypad 1. Select 1: Keypad→VFD 2. Press ENTER to go to the "Keypad→VFD" screen.  001> 4170 keypad->VFD 34% Begin copying the PLC program until it is done.

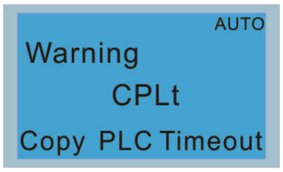

Copy PLC
001:Manual_001
002:
003:

After copying is done, the keypad automatically returns to this screen.

NOTE

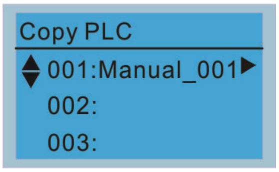

001> 0
ERR8
Type Mismatch

If you select “Option 1: Keypad→VFD”, check if the PLC program is built-in to the KPC-CC01 keypad. If the PLC program is not available in the keypad when you select “Option 1: Keypad→VFD”, an “ERR8 Warning: Type Mismatch” displays on the screen.

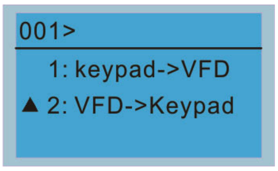

AUTO
Warning
CPLt
Copy PLC Timeout

If you unplug the keypad and plug it back while copying the PLC program, the screen displays a CPLt warning.

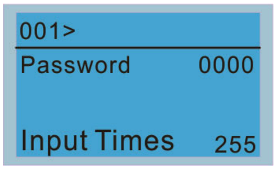
Example: PLC program saved in the keypad.


Copy PLC
001:Manual_001
002:
003:

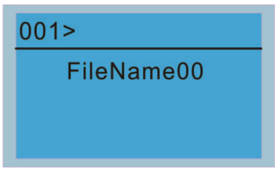
1. Go to Copy PLC.
2. Select the PLC program to copy and press ENTER.


001>
1: keypad->VFD
2: VFD->Keypad

Press ENTER to go to the “VFD→Keypad” screen.

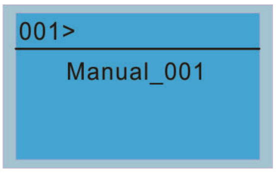

001>
Password 0000
Input Times 255

If the WPLSoft editor is installed uses password, enter the password to save the file to the keypad.

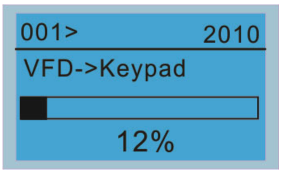

001>
FileName00

Press the Up / Down keys to select a symbol.
Press the Left / Right keys to move the cursor to select a file name.

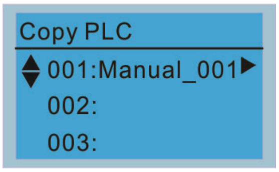
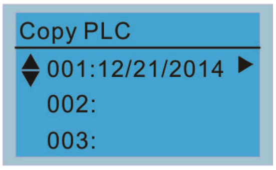
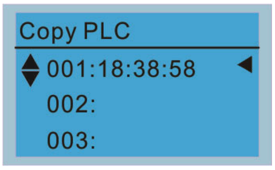
String & Symbol Table:
！”＃＄％＆’（）＊＋，－．／０１２３４５６７８９：；＜＝＞？＠ＡＢ
ＣＤＥＦＧＨＩＪＫＬＭＮＯＰＱＲＳＴＵＶＷＸＹＺ〔＼〕︿＿‘ａｂｃｄ
ｆｇｈｉｊｋｌｍｎｏｐｑｒｓｔｕｖｗｘｙｚ｛｜｝～


001>
Manual_001

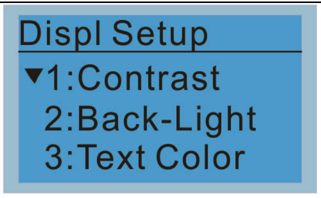
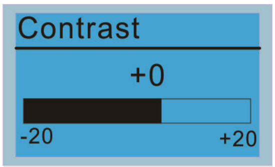
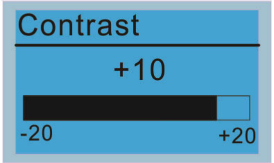
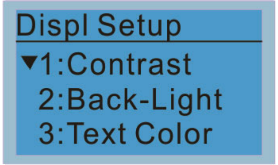
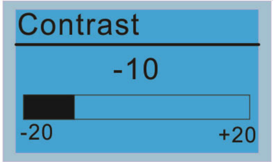
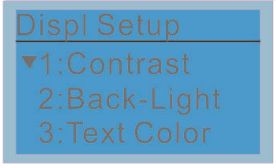
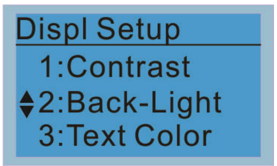
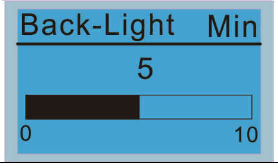
After you confirm the file name, press ENTER.

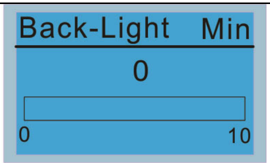

001> 2010
VFD->Keypad
12%

Begin copying the PLC program until it is done.

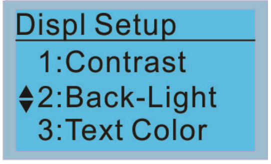
	 Copy PLC ⬍001:Manual_001 ▶ 002: 003:	After copying is done, the keypad automatically returns to this screen.
	 Copy PLC ⬍001:12/21/2014 ▶ 002: 003:	Press the Right key to see the date of the program copied.
	 Copy PLC ⬍001:18:38:58 ◀ 002: 003:	Press the Right key to see the time of program copied.

12. Display setup

 Displ Setup ▼1:Contrast 2:Back-Light 3:Text Color Press ENTER to go to the setting screen.	1. Contrast	
	 Contrast +0 -20 +20	Press the Up / Down keys to adjust the setting value.
	 Contrast +10 -20 +20	For example, increase Contrast to +10.
	 Displ Setup ▼1:Contrast 2:Back-Light 3:Text Color	After you set the value, press ENTER to see the screen display after contrast is adjusted to +10.
	 Contrast -10 -20 +20	Then press ENTER and decrease the Contrast to -10.
	 Displ Setup ▼1:Contrast 2:Back-Light 3:Text Color	Press ENTER to see screen display after contrast is adjusted to -10.
	2. Back-light	
	 Displ Setup 1:Contrast ⬍2:Back-Light 3:Text Color	Press ENTER to go to the Back-Light Time Setting screen.
	 Back-Light Min 5 0 10	Press the Up / Down keys to adjust the setting value.

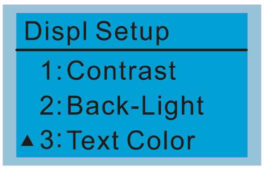


When the setting value is 0 Min, the backlight remains on.

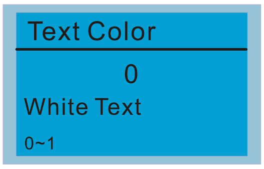


When the setting value is 10 Min, the backlight turns off in 10 minutes.

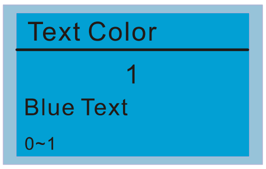
3. Text Color



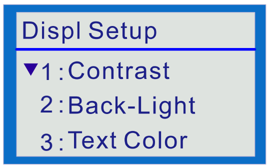
Press ENTER to go to the Text Color Setting screen.



The default value is White Text.

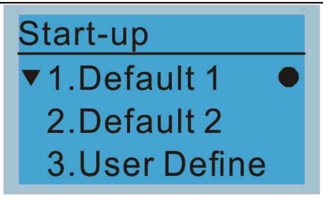


Press the Up / Down keys to adjust the setting value, and then press ENTER.

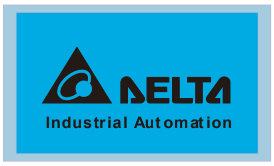


The setting value changes to Blue Text.

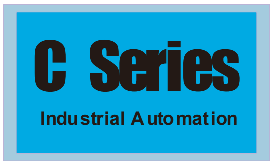
13. Start-up



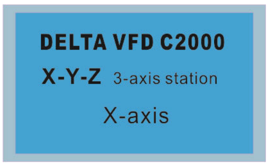
1. Default 1 DELTA LOGO



2. Default 2 DELTA Text



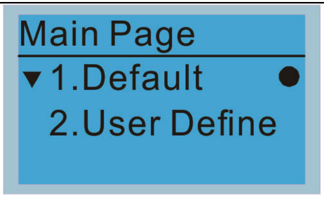
3. User Defined: an optional accessory is required (TPEditor & USB / RS-485 Communication Interface-IFD6530) to design your own start-up screen. If the editor accessory is not installed, the User Define option displays a blank screen.



USB/RS-485 Communication Interface-IFD6530
Refer to Chapter 07 Optional Accessories for more detail.

TPEditor
Download TPEditor software at Delta website, select TPEditor version 1.60 or above. Refer to the installation instruction for TPEditor in Section 10-3.

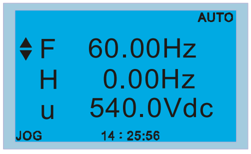
14. ain page



Default screen and editable screen are available upon selection.

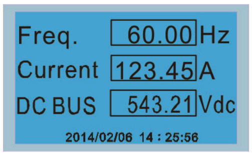
Press ENTER to select.

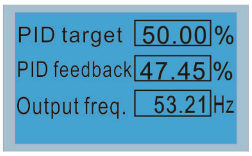
1. Default page



F 60.00Hz >>> H >>> A >>> U (options rotate)

2. User Define: an optional accessory is required (TPEditor & USB / RS-485 Communication Interface-IFD6530) to design your own main screen.
   If the editor accessory is not installed, the User Define option displays a blank screen.

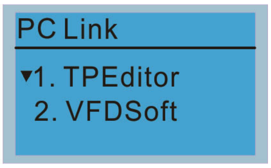




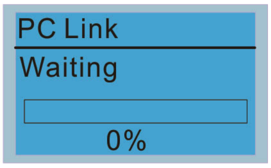
USB/RS-485 Communication Interface-IFD6530
Refer to Chapter 07 Optional Accessories for more detail.

TPEditor
Download TPEditor software at Delta website, select TPEditor version 1.60 or above. Refer to the installation instruction for TPEditor in Section 10-3.

15. PC Link

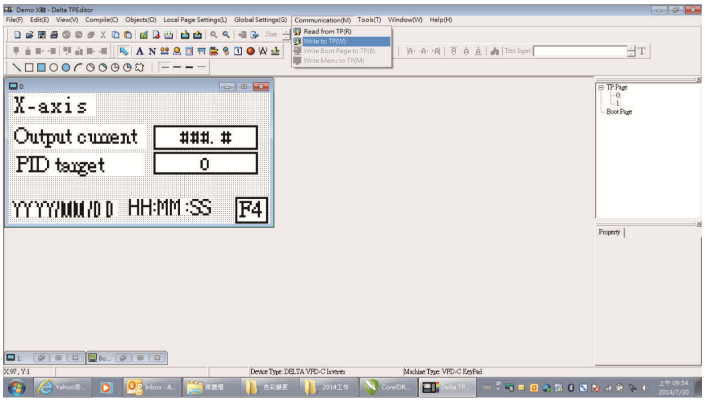


1. TPEditor: This function enables you to connect the keypad to a computer then to download and edit user-defined screens.

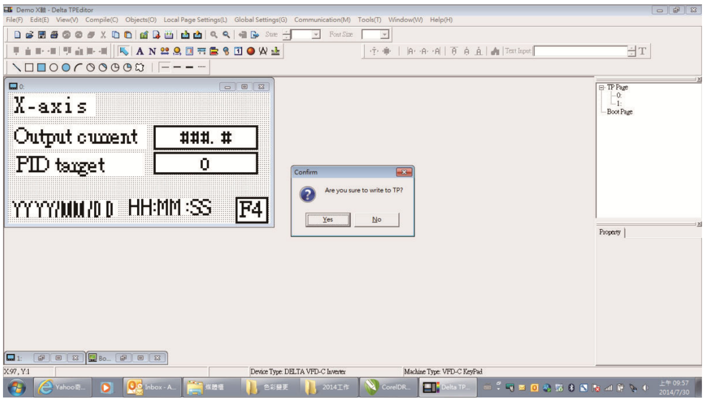


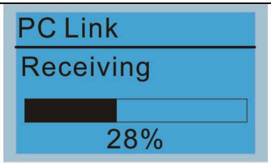
Click ENTER to go to <Waiting to connect to PC>

In TPEditor, from the **Communication** menu, then choose "Write to HMI"

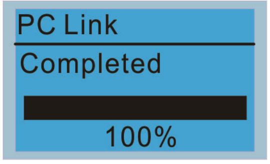

Demo X - Delta TPEditor
File(F) Edit(E) View(V) Compile(C) Objects(O) Local Page Settings(L) Global Settings(G) Communication(M) Tools(T) Window(W) Help(H)
Read from TP(R)
Write to TP(W)
Write Boot Page to TP(B)
Write Menu to TP(M)
X-axis
Output current ###.#
PID target 0
YYYY/MM/DD HH:MM:SS F4
TP Page
Boot Page
Property
Device Type: DELTA VFD-C Inverter
Machine Type: VFD-C KeyPad

In the **Confirm** message box, click **YES**.


Demo X - Delta TPEditor
File(F) Edit(E) View(V) Compile(C) Objects(O) Local Page Settings(L) Global Settings(G) Communication(M) Tools(T) Window(W) Help(H)
X-axis
Output current ###.#
PID target 0
YYYY/MM/DD HH:MM:SS F4
Confirm
Are you sure to write to TP?
Yes
No
TP Page
Boot Page
Property
Device Type: DELTA VFD-C Inverter
Machine Type: VFD-C KeyPad



The software starts downloading screens to edit to the KPC-CC01.

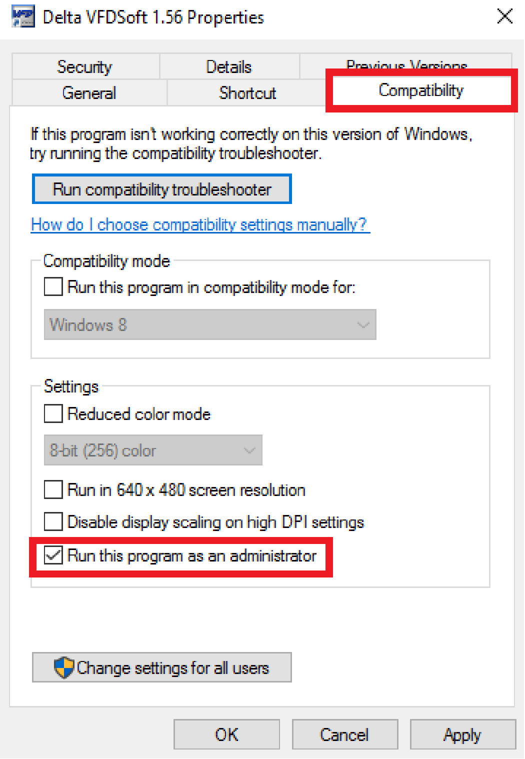


Download completed

2. VFDSoft: this function enables you to link to the VFDSoft then upload the parameters 1–4 you have saved in KPC-CC01.

NOTE

If the Operation System (OS) of your computer is Windows 10, right-click on the VFDSoft icon to enter the **Property**. Then, click the **Compatibility** tab and select the **Run this program as an administrator** checkbox. (as shown in the red frames in the figure below)


Delta VFDSoft 1.56 Properties

Security
Details
Previous Versions
General
Shortcut
Compatibility

If this program isn't working correctly on this version of Windows, try running the compatibility troubleshooter.

Run compatibility troubleshooter
How do I choose compatibility settings manually?

Compatibility mode

☐ Run this program in compatibility mode for:

Windows 8

Settings

☐ Reduced color mode

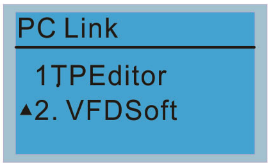
8-bit (256) color

☐ Run in 640 x 480 screen resolution

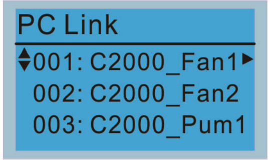
☐ Disable display scaling on high DPI settings

☑ Run this program as an administrator

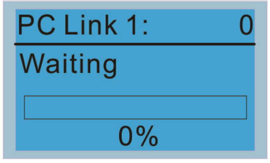
Connecting the KPC-CCO1 to a computer



Select 2: VFDSoft, and then press ENTER.

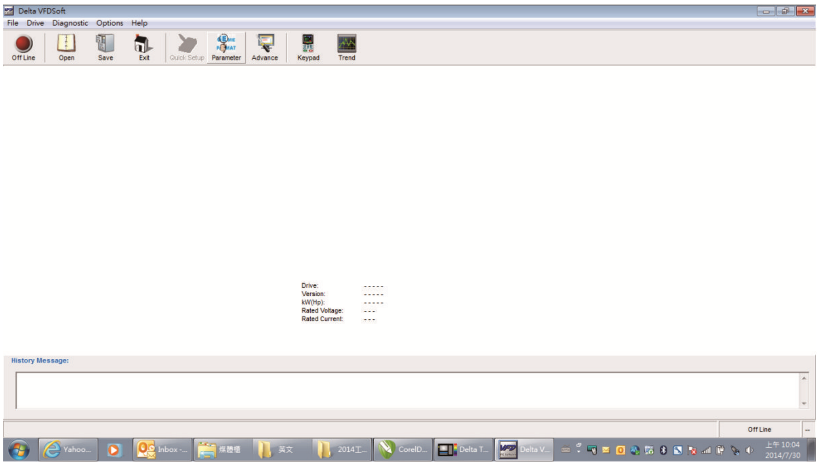


Press the Up / Down keys to select a parameter group to upload to VFDSoft.

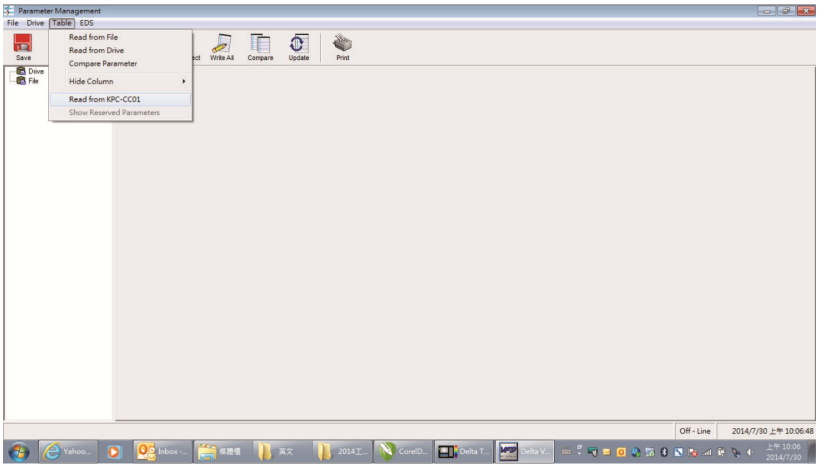


Press ENTER to go to Waiting to connect to PC screen.

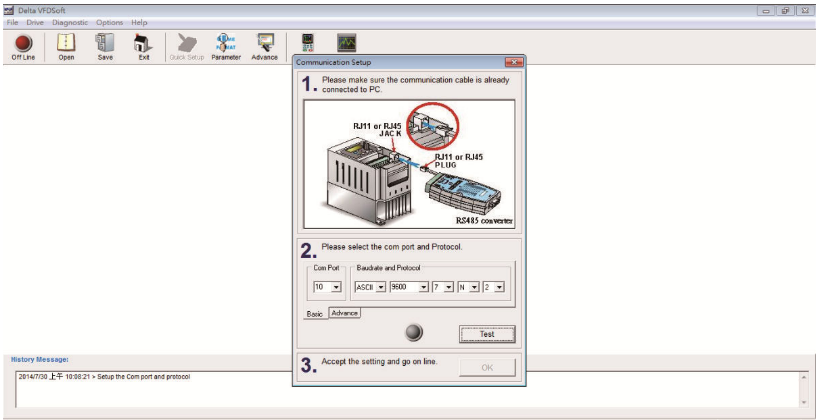
Open VFDSoft and click **Parameter** on the toolbar.

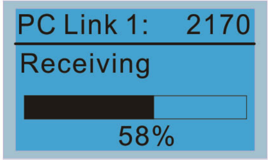


In Parameter Manager, from the **Table** menu, choose **Read from KPC-CC01**.

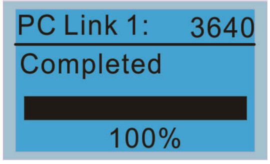


Choose the correct communication port and click **OK**.


Delta VFDSoft
Communication Setup
1. Please make sure the communication cable is already connected to PC.
RJ11 or RJ45 JACK
RJ11 or RJ45 PLUG
RS485 converter
2. Please select the com port and Protocol.
Com Port
Baudrate and Protocol
10
ASCII
9600
7
N
2
Basic
Advance
Test
3. Accept the setting and go on line.
OK
History Message:
2014/7/30 上午 10:08:21 > Setup the Com port and protocol
Off Line


PC Link 1: 2170
Receiving
58%

Start to upload parameters to VFDSoft


PC Link 1: 3640
Completed
100%

Uploading parameter is completed

Before using the user-defined start-up screen and user-defined main screen, you must preset the start-up screen and the main screen as user-defined. If you do not download the user-defined screen to the KPC-CC01, the start-up screen and the main screen are blank.

16. Start Wizard (applicable for CP2000 firmware V2.06 and above)

16.1 New drive start-up setting process

When a new drive is powered on, it directly enters the Start Wizard. There are three modes in the start-up setting process: Start Wizard, Exit Wizard and Test Mode.

(1) Start Wizard:

- In Start Wizard, you can set drive's parameters such as Calendar, Maximum operation frequency and Maximum voltage…; refer to Table 1 for setting items and orders.
- The drive exits Start Wizard when you finish the complete setting process, and will not enter this process when rebooting the power.

(2) Exit Wizard:

- Exit the Start Wizard mode. The drive does not go to Start Wizard when rebooting the power.

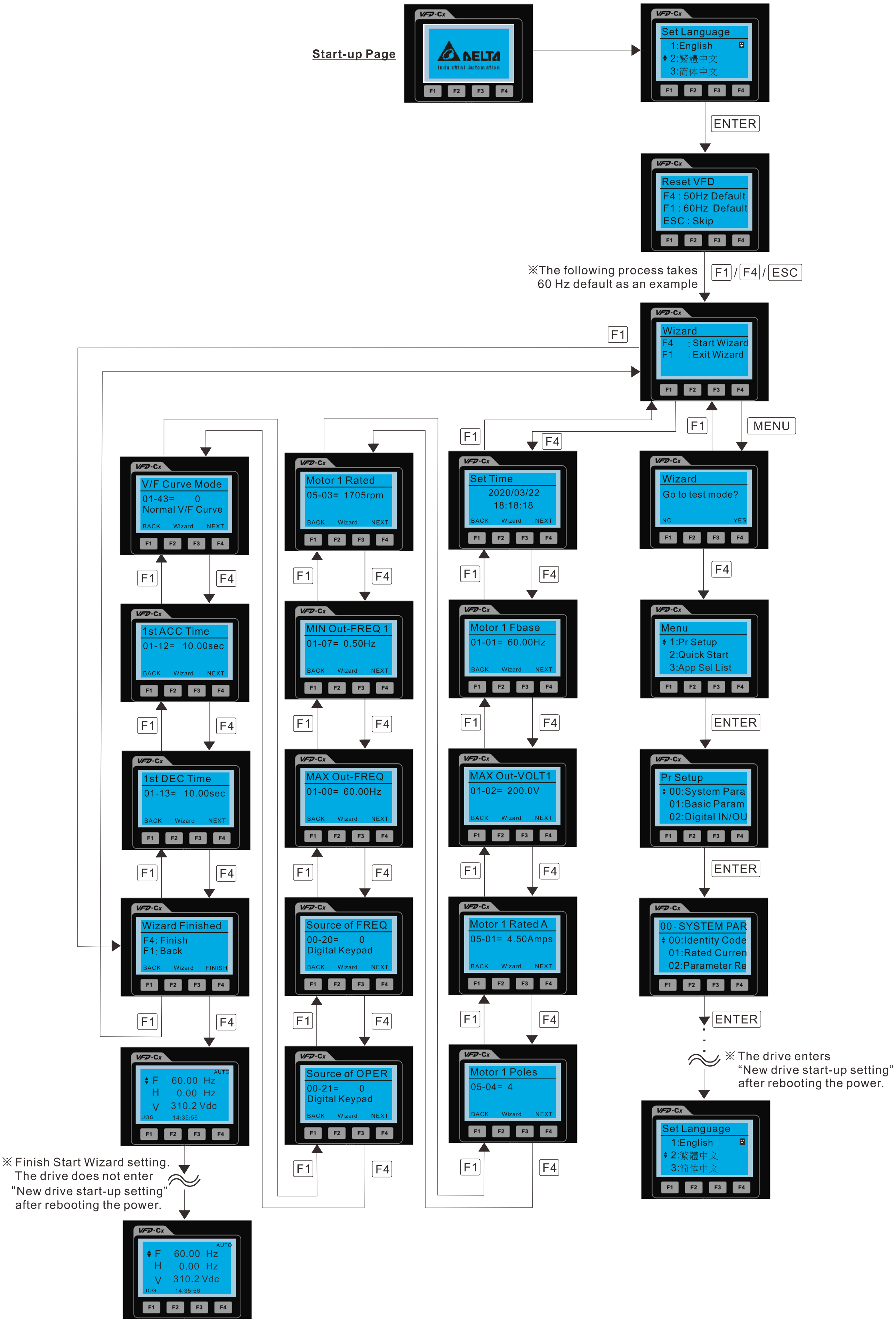
(3) Test Mode:

- This function is hidden to avoid misuse. Refer to the following flow chart to enter Test Mode.
- When the drive is in Test mode, it temporarily disables the Start Wizard and Exit Wizard mode.
- The Test Mode is designed for distributors / suppliers / clients to manage and operate the drive before shipping it out.
- If you enter Test Mode without exiting the Start Wizard process, the drive will begin with the new drive start-up process upon next power on.

Setting Order	Description	Parameter
1	Calendar	N/A
2	Output frequency of motor 1	01-01
3	Output voltage of motor 1	01-02
4	Full-load current for induction motor 1 (A)	05-01
5	Number of poles for induction motor 1	05-04
6	Rated speed for induction motor 1 (rpm)	05-03
7	Minimum output frequency of motor 1	01-07
8	Maximum operation frequency	01-00
9	Master frequency command source (AUTO) / Source selection of the PID target	00-20
10	Operation command source (AUTO)	00-21
11	V/F curve selection	01-43
12	Acceleration time 1	01-12
13	Deceleration time 1	01-13

Table 1: Start Wizard setting items

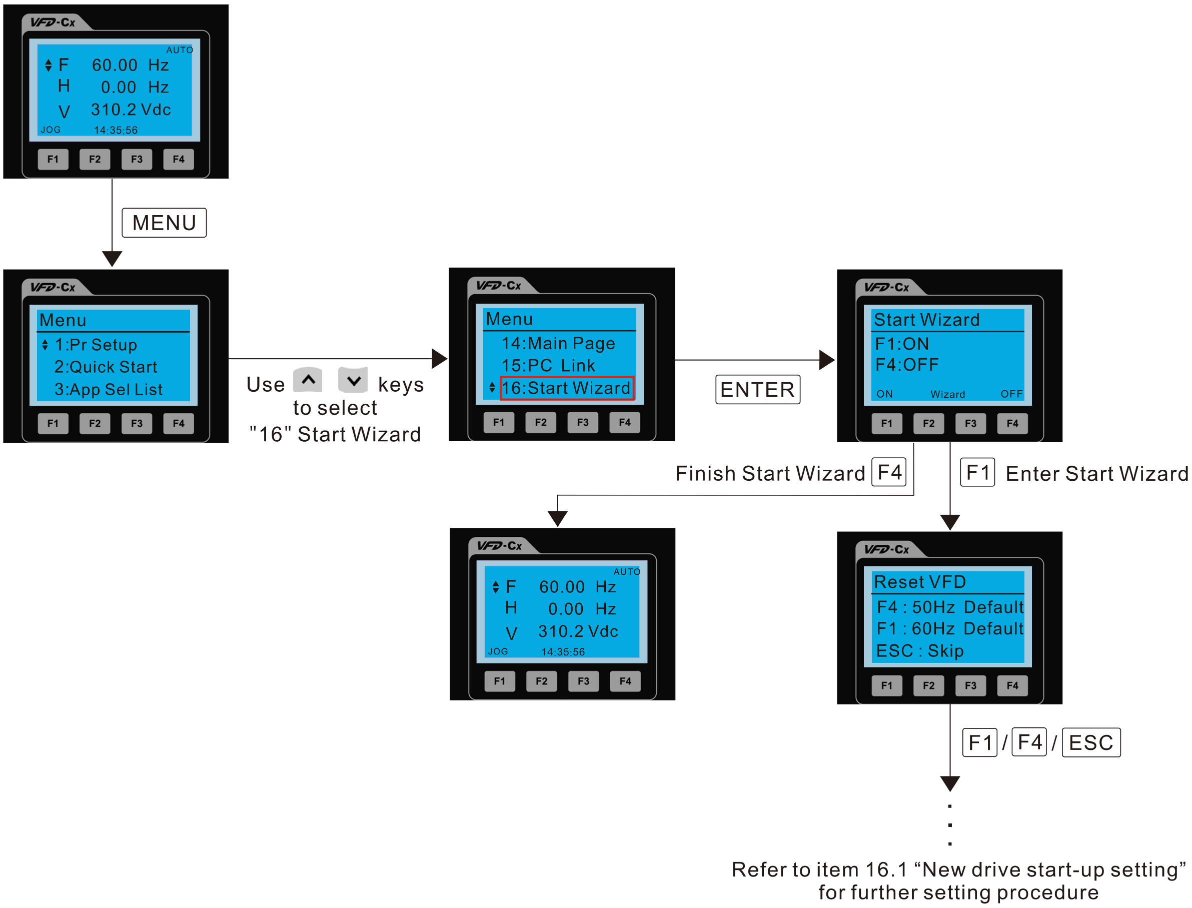
Flow chart for the above setting process:


※The following process takes 60 Hz default as an example

※ Finish Start Wizard setting. The drive does not enter "New drive start-up setting" after rebooting the power.

※ The drive enters "New drive start-up setting" after rebooting the power.

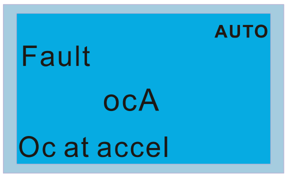
16.2 Re-start Start Wizard



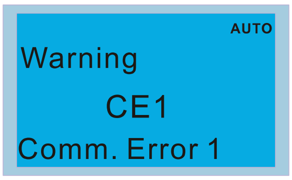
NOTE: The "16: Start Wizard" on the menu is to set whether the screen shows start wizard when powering on the drive.

Other displays

When a fault occurs, the screen display shows the fault or warning:



AUTO
Fault
ocA
Oc at accel



AUTO
Warning
CE1
Comm. Error 1

1. Press the STOP / RESET key to reset the fault code. If there is no response, contact your local distributor or return the unit to the factory. To view the fault DC bus voltage, output current and output voltage, press MENU and then choose 6: Fault Record.
2. After resetting, if the screen returns to the main page and shows no fault after you press ESC, the fault is cleared.
3. When the fault or warning message appears, the LED backlight blinks until you clear the fault or warning.

Optional accessory: RJ45 Extension Lead for Digital Keypad

Part No.	Description
CBC-K3FT	RJ45 extension lead, 3 feet (approximately 0.9 m)
CBC-K5FT	RJ45 extension lead, 5 feet (approximately 1.5 m)
CBC-K7FT	RJ45 extension lead, 7 feet (approximately 2.1 m)
CBC-K10FT	RJ45 extension lead, 10 feet (approximately 3 m)
CBC-K16FT	RJ45 extension lead, 16 feet (approximately 4.9 m)

Note: When you need to buy communication cables, buy non-shielded, 24 AWG, four-wire twisted pair, 100 ohms communication cables.

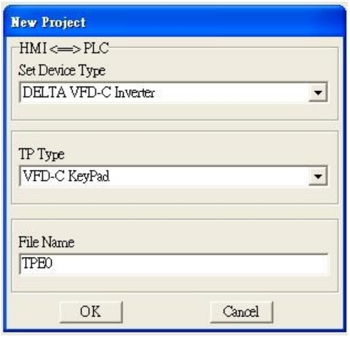
10-3 TPEditor Installation Instruction

TPEditor can edit up to 256 HMI (Human-Machine Interface) pages with a total storage capacity of 256 KB. Each page can include 50 normal objects and 10 communication objects.

1) TPEditor: Setup & Basic Functions

1. Run TPEditor version 1.60 or above by double-clicking the program icon.

2. On the **File** menu, click **New**. In the New project dialog box, for **Set Device Type**, select **DELTA VFD-C Inverter**. For **TP Type**, select **VFD-C KeyPad**. For **File Name**, enter TPE0 and then click **OK**.

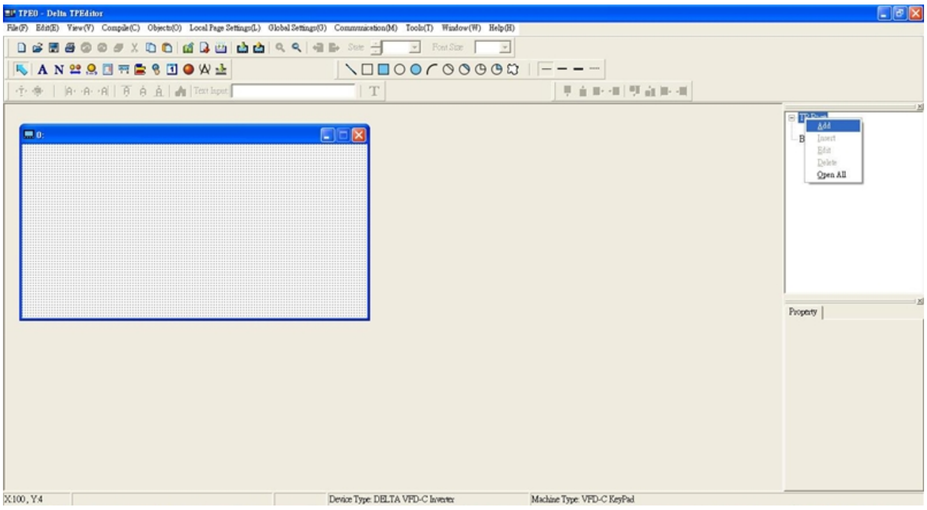


Set Device Type: DELTA VFD-C Inverter

TP Type: VFD-C KeyPad

File Name: TPE0

3. The editor displays the Design window. On the **Edit** menu, click **Add a New Page**. You can also right-click on the TP page in the upper right corner of the Design window and click **Add** to add one more page(s) to edit.


TPE0 - Delta TPEditor
File(F) Edit(E) View(V) Compile(C) Objects(O) Local Page Settings(L) Global Settings(G) Communication(M) Tools(T) Window(W) Help(H)
Add
Insert
Edit
Delete
Open All
Property

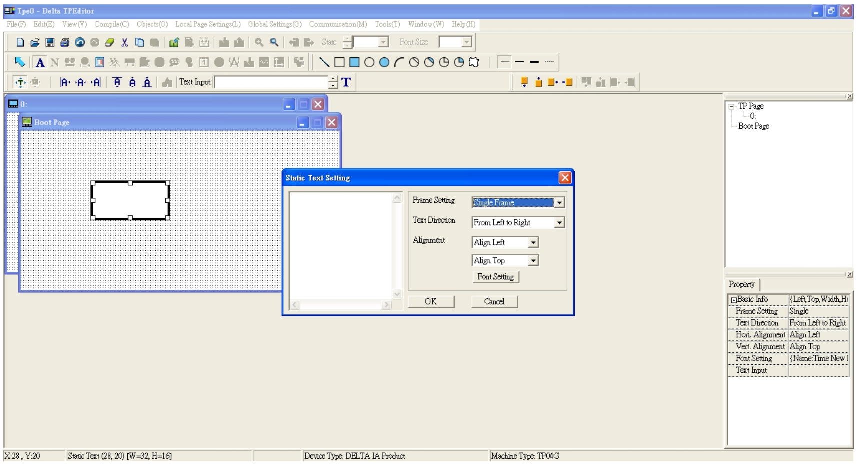
X100, Y4

Device Type: DELTA VFD-C Inverter

Machine Type: VFD-C KeyPad

4. Edit the start-up screen

5. Add static text. Open a blank page (step 3), then on the toolbar click A. Double-click the blank page to display the **Static Text Setting** dialog box, and then enter the static text.

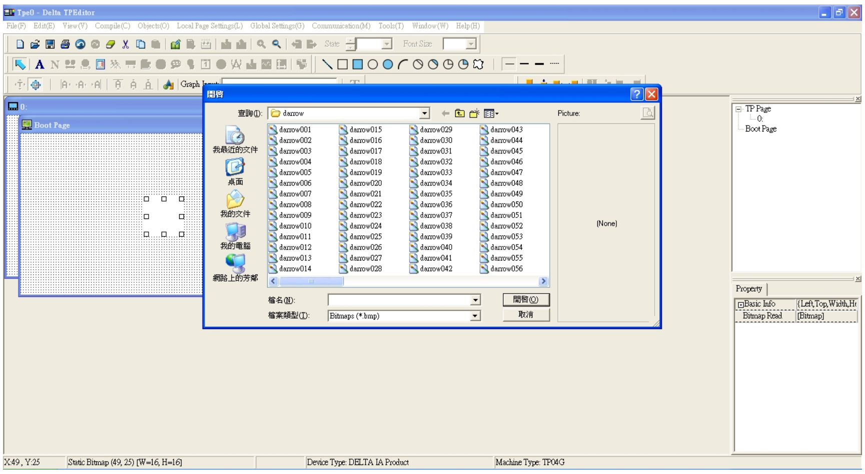

Tpe0 - Delta TPEditor
File(F) Edit(E) View(V) Compile(C) Objects(O) Local Page Settings(L) Global Settings(G) Communication(M) Tools(T) Window(W) Help(H)
Text Input
0:
Boot Page
Static Text Setting
OK
Cancel
TP Page
Property

Frame Setting: Single Frame
Text Direction: From Left to Right
Alignment: Align Left, Align Top
Font Setting

Basic Info: (Left,Top,Width,H
Frame Setting: Single
Text Direction: From Left to Right
Hori. Alignment: Align Left
Vert. Alignment: Align Top
Font Setting: (Name:Time New
Text Input

X:28 , Y:20 Static Text (28, 20) [W=32, H=16] Device Type: DELTA IA Product Machine Type: TP04G

6. Add a static bitmap. Open a blank page (step 3), then on the toolbar, click 🖼. Double-click the blank page to display the **Static Bitmap Setting** dialog box where you can choose the bitmap.



查詢(I): darrow
Picture: [None]
檔名(N):
檔案類型(T): Bitmaps (*.bmp)

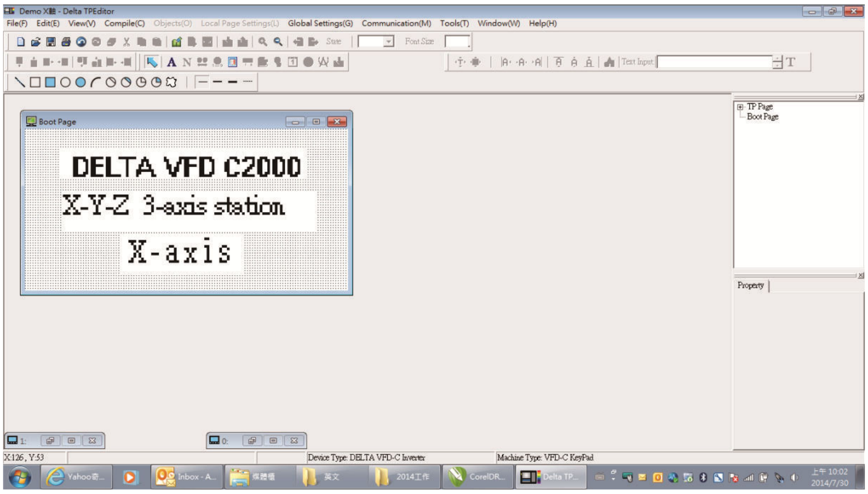
Basic Info: (Left,Top,Width,H
Bitmap Read: [Bitmap]

X:49 , Y:25 Static Bitmap (49, 25) [W=16, H=16] Device Type: DELTA IA Product Machine Type: TP04G

You can only use images in the BMP format. Click the image and then click Open to show the image in the page.

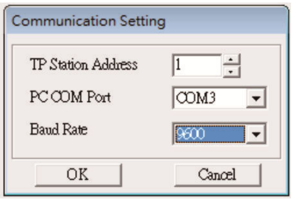
7. Add a geometric bitmap. There are 11 kinds of geometric bitmaps to choose. Open a new blank page (step 3), then on the toolbar click the geometric bitmap icon that you need ╲ □ ■ ○ ● ◜ ⊘ ⊘ ◔ ◔ ✧. In the page, drag the geometric bitmap and enlarge it to the size that you need.

8. When you finish editing the start-up screen, on the **Communication** menu, click **Input User Defined Keypad Starting Screen.**


Demo X軸 - Delta TPEditor
Boot Page
DELTA VFD C2000
X-Y-Z 3-axis station
X-axis
TP Page
Boot Page
Property
Device Type: DELTA VFD-C Inverter
Machine Type: VFD-C KeyPad

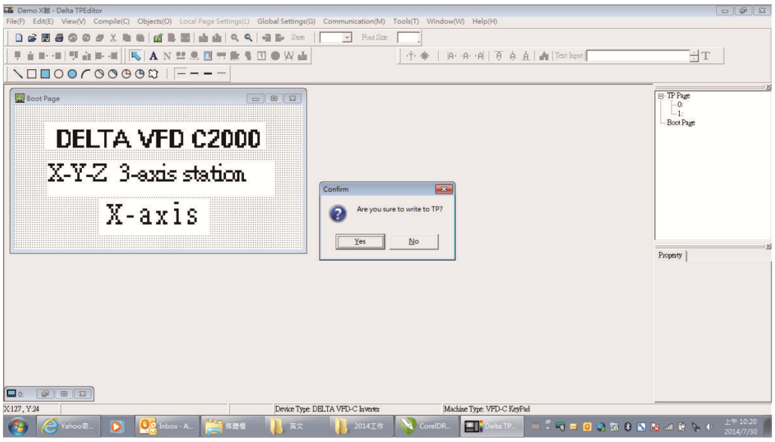
9. Download the new setting: On the **Tool** menu, click **Communication**. Set up the communication port and speed for the IFD6530. There are three speeds available: 9600 bps, 19200 bps, and 38400 bps.

10. On the **Communication** menu, click **Input User Defined Keypad Starting Screen**.

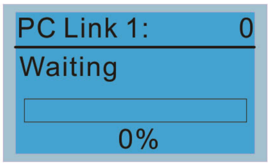

Communication Setting

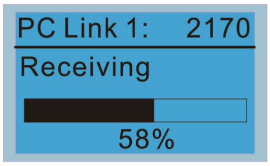
TP Station Address: 1
PC COM Port: COM3
Baud Rate: 9600

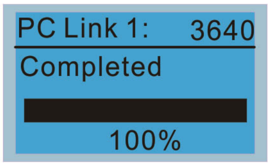
11. The Editor displays a message asking you to confirm the new setting. Before you click **OK**, on the keypad, go to MENU, select PC LINK, press ENTER and then wait for few seconds. Then click **YES** in the confirmation dialog box to start downloading.



Are you sure to write to TP?

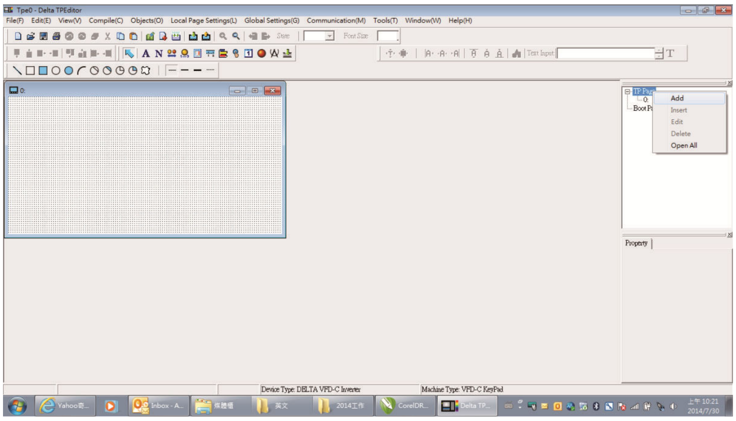

PC Link 1: 0
Waiting
0%


PC Link 1: 2170
Receiving
58%

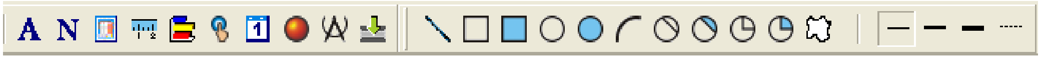

PC Link 1: 3640
Completed
100%

2) Edit the Main Page and Download to the Keypad

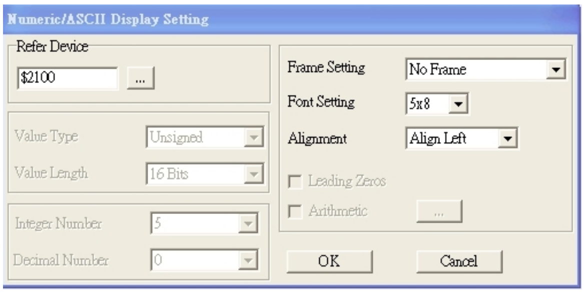
1. In the Editor, add a page to edit. On the **Edit** menu, click **Add a New Page**. You can also right-click on the TP page in the upper right corner of the Design window and click **Add** to add one more pages to edit. This keypad currently supports up to 256 pages.


Tpe0 - Delta TPEditor
File(F) Edit(E) View(V) Compile(C) Objects(O) Local Page Settings(L) Global Settings(G) Communication(M) Tools(T) Window(W) Help(H)
Add
Insert
Edit
Delete
Open All
Property
Device Type: DELTA VFD-C Inverter
Machine Type: VFD-C KeyPad

2. In the bottom right-hand corner of the Editor, click the page number to edit, or on the **View** menu, click **HMI Page** to start editing the main page. As shown in the picture above, the following objects are available. From left to right they are: Static Text, ASCII Display, Static Bitmap, Scale, Bar Graph, Button, Clock Display, Multi-state bit map, Units, Numeric Input, the 11 geometric bitmaps, and lines of different widths. Use the same steps to add Static Text, Static Bitmap, and geometric bitmaps as for the start-up page.



3. Add a numeric/ASCII display. On the toolbar, click the **Numeric/ASCII** button. In the page, double-click the object to specify the **Refer Device**, **Frame Setting**, **Font Setting** and **Alignment**.



Numeric/ASCII Display Setting

Refer Device: $2100

Value Type: Unsigned

Value Length: 16 Bits

Integer Number: 5

Decimal Number: 0

Frame Setting: No Frame

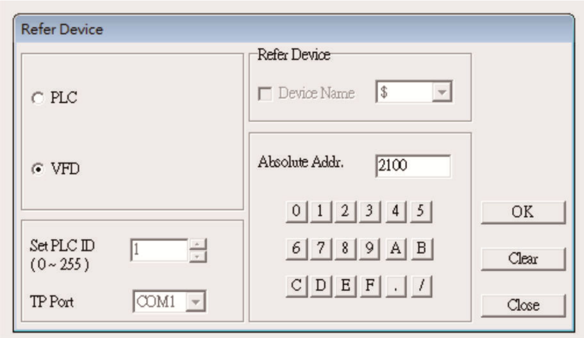
Font Setting: 5x8

Alignment: Align Left

☐ Leading Zeros

☐ Arithmetic

Click **[…]**. In the **Refer Device** dialog box, choose the VFD communication port that you need. If you want to read the output frequency (H), set the **Absolute Addr.** to 2202. For other values, refer to the ACMD Modbus Comm Address List (see Pr.09-04 in Chapter 12 Group 09 Communication Parameters).



Refer Device

○ PLC

● VFD

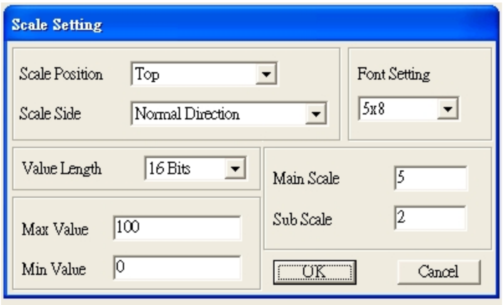
Set PLC ID (0～255): 1

TP Port: COM1

☐ Device Name: $

Absolute Addr.: 2100

4. Scale Setting. On the toolbar, click to add a scale. You can also edit the Scale Setting in the Property Window on the right-hand side of your computer screen.



Scale Position: Top
Scale Side: Normal Direction
Font Setting: 5x8
Value Length: 16 Bits
Main Scale: 5
Sub Scale: 2
Max Value: 100
Min Value: 0

a. **Scale Position**: specifies where to place the scale.

b. **Scale Side**: specifies whether the scale is numbered from smaller numbers to larger numbers or from larger to smaller.

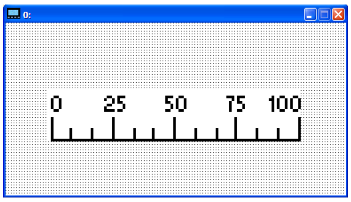
c. **Font Setting**: specifies the font.

d. **Value Length**: specifies 16 bits or 32 bits.

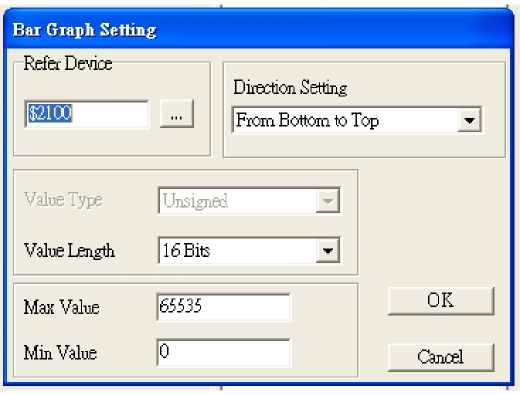
e. **Main Scale & Sub-Scale**: divides the whole scale into equal parts; enter the numbers for the main scale and sub-scale.

f. **Max Value & Min Value**: specifies the numbers on the two ends of the scale. They can be negative numbers, but the maximum and minimum values are limited by the **Value Length** setting. For example, when **Value Length** is **hexadecimal** (**16 bits**), the maximum and the minimum value cannot be entered as -40000.

Clicking **OK** creates a scale as in the picture below.



5. Bar Graph setting. On the toolbar, click to add a bar graph.



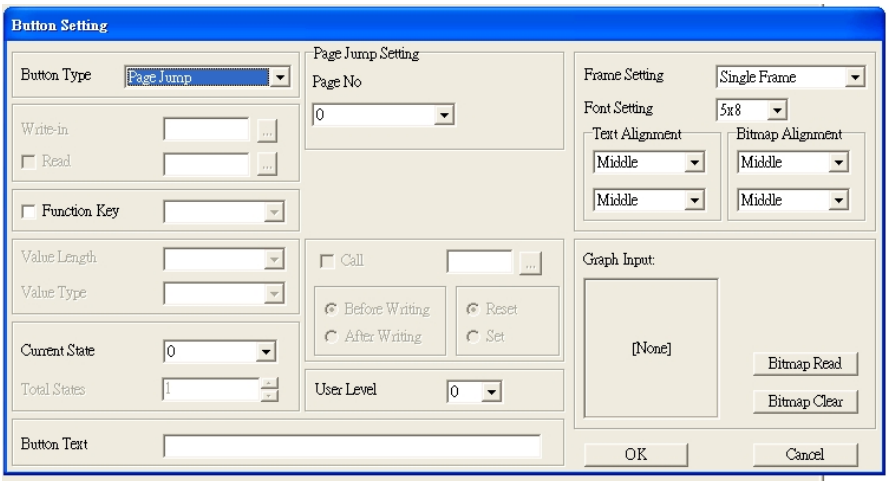
Refer Device: $2100
Direction Setting: From Bottom to Top
Value Type: Unsigned
Value Length: 16 Bits
Max Value: 65535
Min Value: 0

a. **Refer Device**: specifies the VFD communication port.

b. **Direction Setting**: specifies the direction: **From Bottom to Top**, **From Top to Bottom**, **From Left to Right** or **From Right to Left**.

c. **Max Value** and **Min Value**: specifies the maximum value and minimum value. A value smaller than or equal to the minimum value causes the bar graph to be blank (0). A value is bigger or equal to the maximum value causes the bar graph is full (100%). A value between the minimum and maximum values causes the bar graph to be filled proportionally.

6. Button : on the toolbar, click . Currently this function only allows the keypad to switch pages; other functions are not yet available (including text input and insert image). In the blank page, double-click to open the Button Setting dialog box.

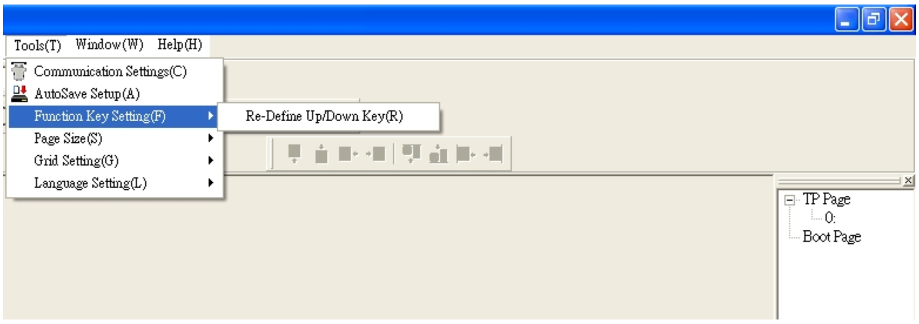


Button Type: specifies the button's functions.

Page Jump and **Constant Setting** are the only functions currently supported.

A. Page Jump Setting

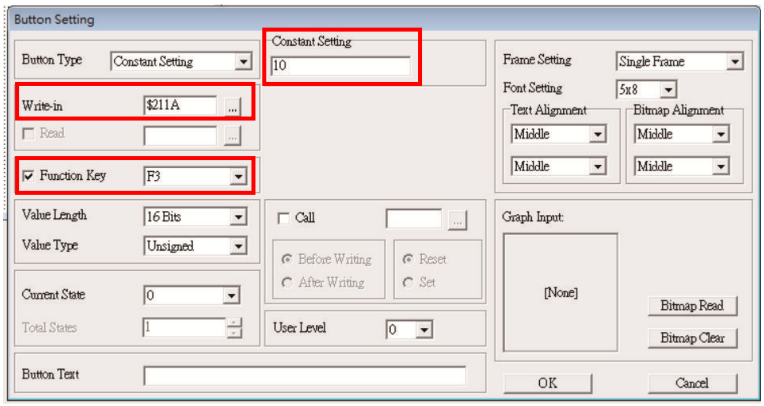
- **Page Jump Setting**: in the **Button Type** list, choose **Page Jump** to show the **Page Jump Setting**.
- **Function Key**: specifies the functions for the following keys on the KPC-CC01 keypad: F1, F2, F3, F4, Up, Down, Left and Right. Note that the Up and Down keys are locked by TPEditor. You cannot program these two keys. If you want to program Up and Down keys, on the **Tool** menu, click **Function Key Setting**, and then click **Re-Define Up/Down Key**.



- **Button Text**: specifies the text that appears on a button. For example, when you enter Next Page for the button text, that text appears on the button.

B. Constant setting

This function specifies the memory address' values for the VFD or PLC. When you press the **Function Key**, it writes a value to the memory address specified by the value for **Constant Setting**. You can use this function to initialize a variable.



Button Setting

Button Type: Constant Setting

Write-in: $211A

☐ Read

☑ Function Key: F3

Value Length: 16 Bits

Value Type: Unsigned

Current State: 0

Total States: 1

Button Text:

Constant Setting: 10

☐ Call

● Before Writing ○ After Writing

● Reset ○ Set

User Level: 0

Frame Setting: Single Frame

Font Setting: 5x8

Text Alignment: Middle, Middle

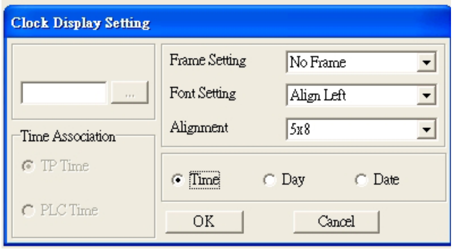
Bitmap Alignment: Middle, Middle

Graph Input: [None]

7. **Clock Display Setting**: on the toolbar, click . You can display the time, day, or date on the keypad.

Open a new page and click once in that window to add a clock display.

Choose to display **Time**, **Day**, or **Date** on the keypad. To adjust time, go to #8 on the keypad's menu. You can also specify the **Frame Setting**, **Font Setting**, and **Alignment**.



Clock Display Setting

Frame Setting: No Frame

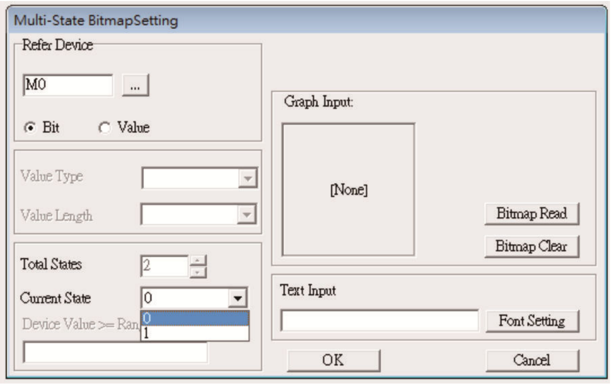
Font Setting: Align Left

Alignment: 5x8

Time Association: ● TP Time ○ PLC Time

● Time ○ Day ○ Date

8. Multi-state bitmap: on the toolbar, click . Open a new page and click once in that window to add a Multi-state bitmap. This object reads a bit's property value from the PLC. It defines the image or text that appears when this bit is 0 or 1. Set the initial status (**Current State**) to be 0 or 1 to define the displayed image or text.



Multi-State BitmapSetting

Refer Device: M0

● Bit ○ Value

Value Type:

Value Length:

Total States: 2

Current State: 0 (0, 1)

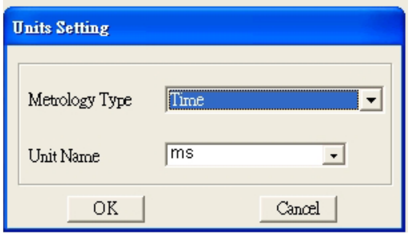
Device Value >= Ran

Graph Input: [None]

Text Input:

9. Unit Measurement: on the toolbar, click

   Open a new blank page, and double-click on that window to display the **Units Setting** dialog box. Choose the Metrology Type and the Unit Name. For Metrology, the choices are Length, Square Measure, Volume/Solid Measure, Weight, Speed, Time, and Temperature. The unit name changes automatically when you change metrology type.

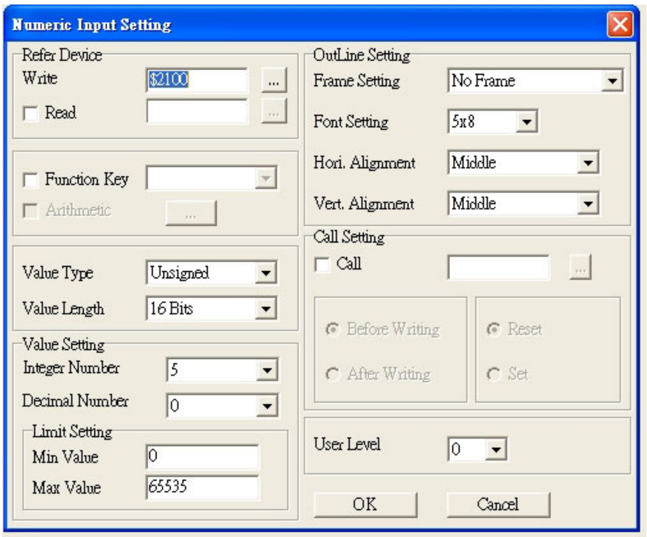

Units Setting

Metrology Type: Time

Unit Name: ms

10. Numeric Input Setting: on the toolbar, click

    This object enables you to provide parameters or communication ports (0x22xx) and to input numbers. Open a new file and double click on that window to display the **Numeric Input Setting** dialog box.


Numeric Input Setting

Refer Device

Write: $2100

☐ Read

☐ Function Key

☐ Arithmetic

Value Type: Unsigned

Value Length: 16 Bits

Value Setting

Integer Number: 5

Decimal Number: 0

Limit Setting

Min Value: 0

Max Value: 65535

OutLine Setting

Frame Setting: No Frame

Font Setting: 5x8

Hori. Alignment: Middle

Vert. Alignment: Middle

Call Setting

☐ Call

● Before Writing ○ After Writing

● Reset ○ Set

User Level: 0

a. **Refer Device**: specifies the **Write** and the **Read** values. Enter the numbers to display and the corresponding parameter and communication port numbers. For example, enter 012C to Read and Write Parameter Pr.01-44.

b. **OutLine Setting**: specifies the **Frame Setting**, **Font Setting**, **Hori. Alignment**, and **Vert. Alignment** for the outline.

c. **Function Key**: specifies the function key to program on the keypad in the **Function Key** box. The corresponding key on the keypad starts to blink. Press ENTER to confirm the setting.

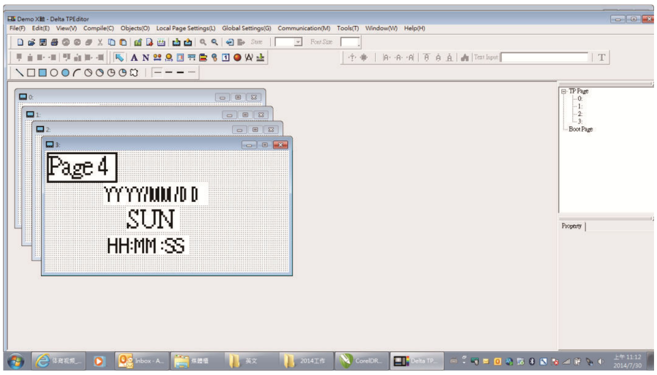
d. **Value Type** and **Value Length**: specify the range of the **Min Value** and **Max Value** for the **Limit Setting**. Note that the corresponding supporting values for MS300 must be 16 bits. 32-bit values are not supported.

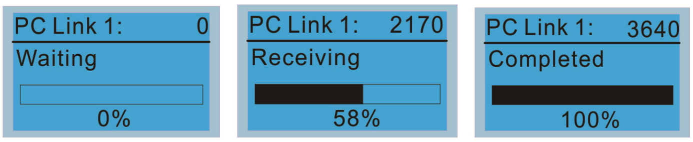
e. **Value Setting**: automatically set by the keypad itself.

f. **Limit Setting**: specifies the range for the numeric input here.

For example, if you set **Function Key** to **F1**, **Min Value** to 0 and **Max Value** to 4, when you press F1 on the keypad, then you can press Up/Down on the keypad to increase or decrease the value. Press ENTER on the keypad to confirm your setting. You can also view the parameter table 01-44 to verify if you correctly entered the value.

11. Download TP Page: Press Up / Down on the keypad to select #13 PC Link.
    Then press ENTER on the keypad. The screen displays “Waiting”. In TPEditor, choose a page that you have created, and then on the **Communication** menu click **Write to TP** to start downloading the page to the keypad.
    When you see “Completed” on the keypad screen, the download is finished. You can then press ESC on the keypad to go back to the menu screen.


Demo X - Delta TPEditor
File(F) Edit(E) View(V) Compile(C) Objects(O) Local Page Settings(L) Global Settings(G) Communication(M) Tools(T) Window(W) Help(H)
Page 4
YYYY/MM/DD
SUN
HH:MM:SS
TP Page
0
1
2
3
Boot Page
Property

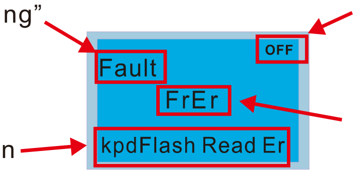


PC Link 1: 0
Waiting
0%

PC Link 1: 2170
Receiving
58%

PC Link 1: 3640
Completed
100%

10-4 Fault Code Description of Digital Keypad KPC-CC01



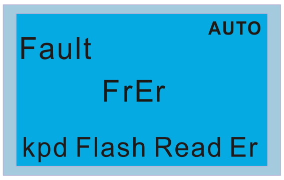
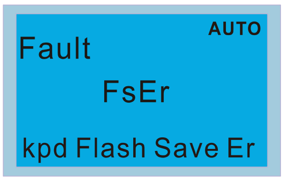
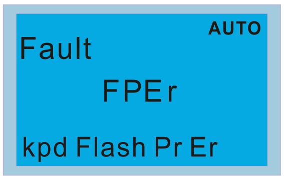
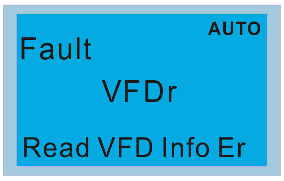
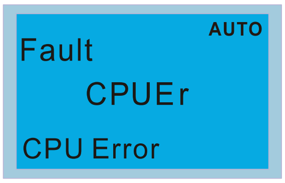
Displays “Fault” or “Warning”

Status indicator for information on main screen. “OFF” displays on the keypad if the keypad cannot read the control board status, otherwise it displays HAND/AUTO. The default value of control board is AUTO.

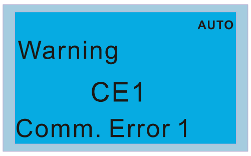
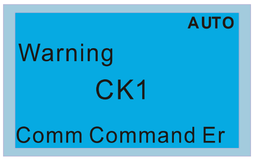
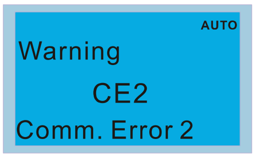
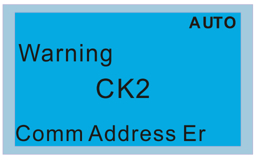
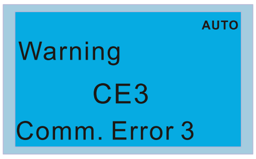
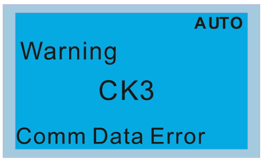
Fault code

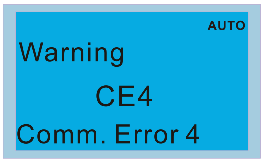
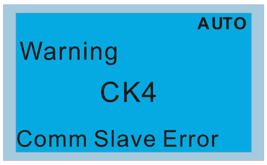
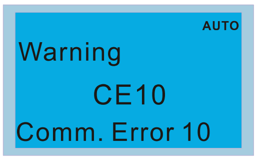
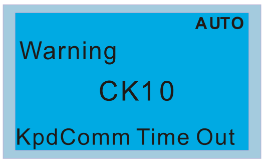
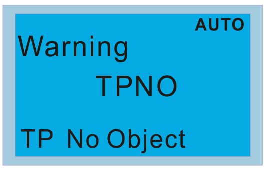
Fault code desciprtion

Fault Codes

LCD Display *	Fault Name	Description	Corrective Actions
 AUTO Fault FrEr kpd Flash Read Er	Flash memory read error (FrEr)	Keypad flash memory read error	Error in the keypad’s flash memory. 1. Press RESET to clear the errors. 2. Check for any problem on Flash IC. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your authorized local dealer for assistance.
 AUTO Fault FsEr kpd Flash Save Er	Flash memory save error (FsEr)	Keypad flash memory save error	Error in the keypad’s flash memory. 1. Press RESET to clear the errors. 2. Check for any problem on Flash IC. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your authorized local dealer for assistance.
 AUTO Fault FPEr kpd Flash Pr Er	Flash memory parameter error (FPEr)	Keypad flash memory parameter error	Error in the default parameters. It might be caused by a firmware update. 1. Press RESET to clear the errors. 2. Check for any problem on Flash IC. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your authorized local dealer for assistance.
 AUTO Fault VFDr Read VFD Info Er	Reading AC motor drive data error (VFDr)	Keypad error when reading AC motor drive data	Keypad cannot read any data sent from the VFD. 1. Verify that the keypad is properly connected to the motor drive by a communication cable such as RJ45. 2. Press RESET to clear the errors. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your authorized local dealer for assistance.
 AUTO Fault CPUEr CPU Error	CPU error (CPUEr)	Keypad CPU error	A serious error in the keypad’s CPU. 1. Check for any problem on CPU clock. 2. Check for any problem on Flash IC. 3. Check for any problem on RTC IC. 4. Verify that the communication quality of the RS-485 cable is good. 5. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your authorized local dealer for assistance.

Warning Codes

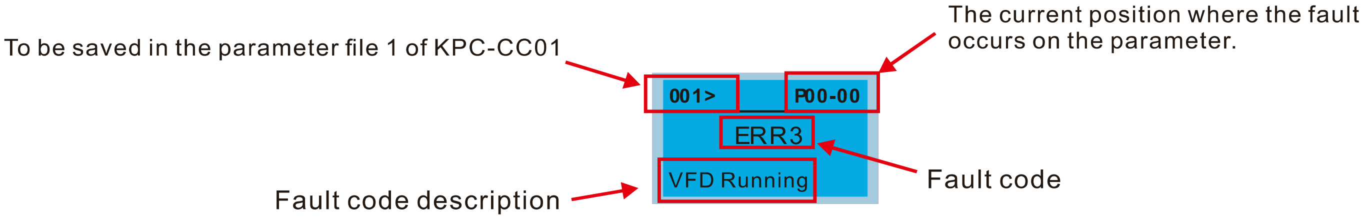
LCD Display *	Warning Name	Description	Corrective Actions
 AUTO Warning CE1 Comm. Error 1	Commuication error 1 (CE1)	RS-485 Modbus illegal function code	Motor drive does not accept the communication command sent from the keypad. 1. Verify that the keypad is properly connected to the motor drive by a communication cable such as RJ45. 2. Press RESET on the keypad to clear errors. If none of the above solutions works, contact your local authorized dealer for assistance.
 AUTO Warning CK1 Comm Command Er	Communication command error 1 (CK1)	Keypad communication data, illegal function code (Keypad auto-detect this error and display it)	Keypad does not accept the motor drive's communication command. 1. Remove the keypad and reconnect it. 2. Verify if the Baud rate = 19200 bps, and the Format = RTU8, N, 2 3. Verify if the keypad is properly connected to the motor drive on the communication contact by a communication cable such as RJ45. If none of the above solution works, contact your local authorized dealer.
 AUTO Warning CE2 Comm. Error 2	Communication error 2 (CE2)	RS-485 Modbus illegal data address	Motor drive does not accept the keypad's communication address. 1. Verify that the keypad is properly connected to the motor drive by a communication cable such as RJ45. 2. Press RESET to clear the errors. If none of the above solutions works, contact your local authorized dealer for assistance.
 AUTO Warning CK2 Comm Address Er	Communication address error (CK2)	Keypad communication data, illegal data address (Keypad auto-detect this error and display it)	Keypad does not accept the motor drive's communication command. 1. Remove the keypad and reconnect it. 2. Verify if the Baud rate = 19200 bps, and the Format = RTU8, N, 2 3. Verify if the keypad is properly connected to the motor drive on the communication contact by a communication cable such as RJ45. If none of the above solution works, contact your local authorized dealer.
 AUTO Warning CE3 Comm. Error 3	Communication error 3 (CE3)	RS-485 Modbus illegal data value	Motor drive does not accept the communication data sent from the keypad. 1. Verify that the keypad is properly connected to the motor drive by a communication cable such as RJ45. 2. Press RESET to clear the errors. If none of the above solutions works, contact your local authorized dealer for assistance.
 AUTO Warning CK3 Comm Data Error	Communication data error (CK3)	Keypad communication data, illegal data value (Keypad auto-detect this error and display it)	Keypad does not accept the motor drive's communication command. 1. Remove the keypad and reconnect it. 2. Verify if the Baud rate = 19200 bps, and the Format = RTU8, N, 2 3. Verify if the keypad is properly connected to the motor drive on the communication contact by a communication cable such as RJ45. If none of the above solution works, contact your local authorized dealer.

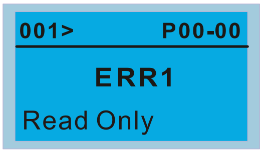
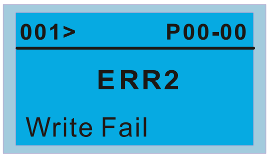
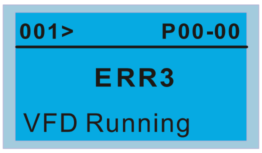
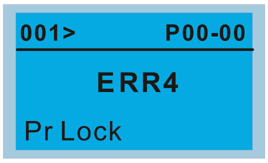
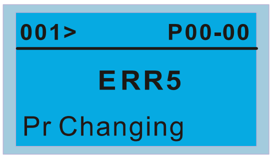
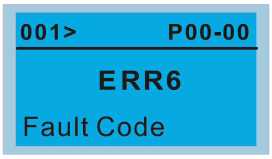
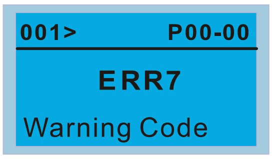
LCD Display *	Warning Name	Description	Corrective Actions
 AUTO Warning CE4 Comm. Error 4	Communication error 4 (CE4)	RS-485 Modbus data is written to read-only address	Motor drive cannot process the communication command sent from the keypad. 1. Verify that the keypad is properly connected to the motor drive by a communication cable such as RJ45. 2. Press RESET to clear the errors. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your local authorized dealer for assistance.
 AUTO Warning CK4 Comm Slave Error	Communication slave error (CK4)	Keypad communication data is written to read-only address (Keypad auto-detect this error and display it)	Keypad does not accept the motor drive's communication command. 1. Remove the keypad and reconnect it. 2. Verify if the Baud rate = 19200 bps, and the Format = RTU8, N, 2 3. Verify if the keypad is properly connected to the motor drive on the communication contact by a communication cable such as RJ45. If none of the above solution works, contact your local authorized dealer.
 AUTO Warning CE10 Comm. Error 10	Communication error 10 (CE10)	RS-485 Modbus transmission time-Out	Motor drive does not respond to the communication command sent from the keypad. 1. Verify that the keypad is properly connected to the motor drive by a communication cable such as RJ45. 2. Press RESET to clear the errors. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your local authorized dealer for assistance.
 AUTO Warning CK10 KpdComm Time Out	Keypad communication time out (CK10)	Keypad communication data, transmission time-out (Keypad auto-detect this error and display it).	Keypad does not accept the motor drive's communication command. 1. Remove the keypad and reconnect it. 2. Verify if the Baud rate = 19200 bps, and the Format = RTU8, N, 2 3. Verify if the keypad is properly connected to the motor drive on the communication contact by a communication cable such as RJ45. If none of the above solution works, contact your local authorized dealer.
 AUTO Warning TPNO TP No Object	Keypad communication time out (CK10)	Object not supported by TPEditor	Keypad's TPEditor uses an unsupported object. 1. Verify that the TPEditor is not using an unsupported object or setting. Delete unsupported objects and unsupported settings. 2. Re-edit the object in the TPEditor, and then download it to the keypad. 3. Verify that the motor drive supports the TP functions. If the drive does not support TP function, the main page displays Default. If none of the above solutions works, contact your local authorized dealer for assistance.

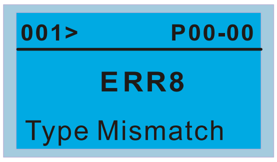
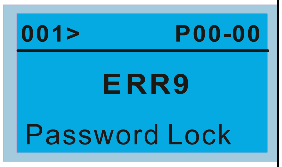
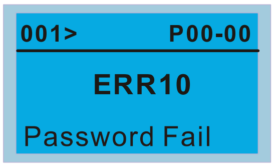
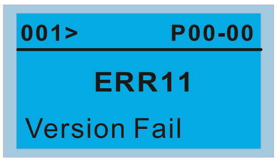
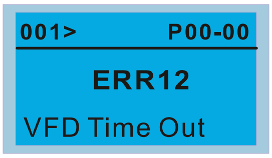
NOTE The warning code CExx only occurs when the communication problem is between the drive and the keypad. It has nothing to do with the drive and other devices. Note the warning code description to find the cause of the error if CExx appears.

File Copy Setting Fault Description:

These faults occur when KPC-CC01 cannot perform the command after clicking the ENTER key in the copy function.


To be saved in the parameter file 1 of KPC-CC01
The current position where the fault occurs on the parameter.
001>
P00-00
ERR3
VFD Running
Fault code
Fault code description

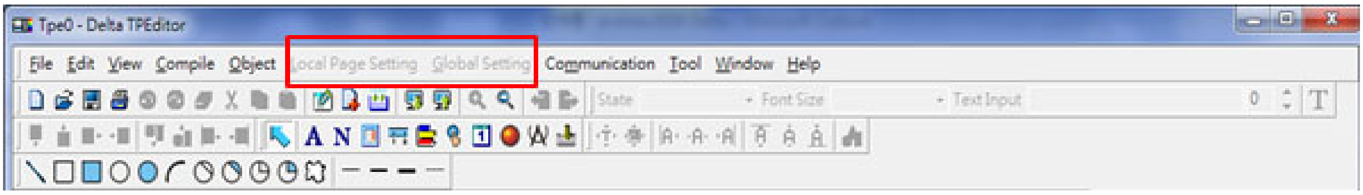
LCD Display *	Fault Name	Description	Corrective Actions
 001> P00-00 ERR1 Read Only	Read only (ERR1)	Parameter and file are read-only	The parameter / file is read-only and cannot be written to. 1. Verify the specification in the user manual. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR2 Write Fail	Write in error (ERR2)	Fail to write parameter and file	An error occurred while writing to a parameter / file. 1. Check for any problem on the Flash IC. 2. Shut down the system, wait for ten minutes, and then restart the system. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR3 VFD Running	Drive operating (ERR3)	AC motor drive is in operating status	A setting cannot be changed while the motor drive is in operation. 1. Verify that the drive is not in operation. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR4 Pr Lock	Parameter locked (ERR4)	AC motor drive parameter is locked	A setting cannot be changed because a parameter is locked. 1. Check if the parameter is locked. If it is locked, unlock it and try to set the parameter again. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR5 Pr Changing	Parameter changing (ERR5)	AC motor drive parameter is changing	A setting cannot be changed because a parameter is being modified. 1. Check if the parameter is being modified. If it is not being modified, try to change that parameter again. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR6 Fault Code	Fault code (ERR6)	Fault code is not cleared	A setting cannot be changed because an error has occurred in the motor drive. 1. Check if any error occurred in the motor drive. If there is no error, try to change the setting again. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR7 Warning Code	Warning code (ERR7)	Warning code is not cleared	A setting cannot be changed because of a warning message given to the motor drive. 1. Check if there is a warning message given to the motor drive. If this solution does not work, contact your local authorized dealer for assistance.

LCD Display *	Fault Name	Description	Corrective Actions
 001> P00-00 ERR8 Type Mismatch	File type mismatch (ERR8)	File type mismatch	Data to be copied are not the correct type, so the setting cannot be changed. 1. Check if the products' serial numbers to be copied are in the same category. If they are in the same category, try to copy the setting again. If this solution does not work, contact your local authorized dealer for assistance.
 001> P00-00 ERR9 Password Lock	Password locked (ERR9)	File is locked with password	A setting cannot be changed because some data are locked. 1. Check if the data are unlocked or able to be unlocked. If the data are unlocked, try to change the setting again. 2. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your local authorized dealer for assistance.
 001> P00-00 ERR10 Password Fail	Password fail (ERR10)	File password mismatch	A setting cannot be changed because the password is incorrect. 1. Check if the password is correct. If the password is correct, try to change the setting again. 2. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your local authorized dealer for assistance.
 001> P00-00 ERR11 Version Fail	Version fail (ERR11)	File version mismatch	A setting cannot be changed because the version of the data is incorrect. 1. Check if the version of the data matches the motor drive. If it matches, try to change the setting again. If none of the above solutions works, contact your local authorized dealer for assistance.
 001> P00-00 ERR12 VFD Time Out	VFD Time out (ERR12)	AC motor drive copy function time-out	A setting cannot be changed because the data copying time-out expired. 1. Try copying the data again. 2. Check if copying data is authorized. If it is authorized, try to copy the data again. 3. Shut down the system, wait for ten minutes, and then restart the system. If none of the above solutions works, contact your local authorized dealer for assistance.

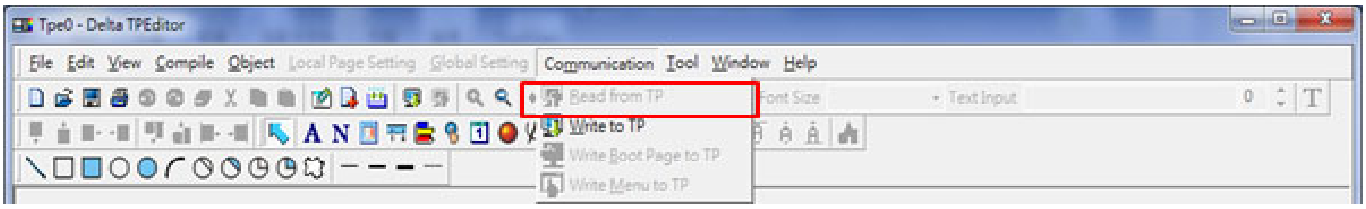
※ The content in this section only applies to the KPC-CC01 keypad V1.01 and later versions.

10-5 Unsupported Functions when using TPEditor with the KPC-CC01

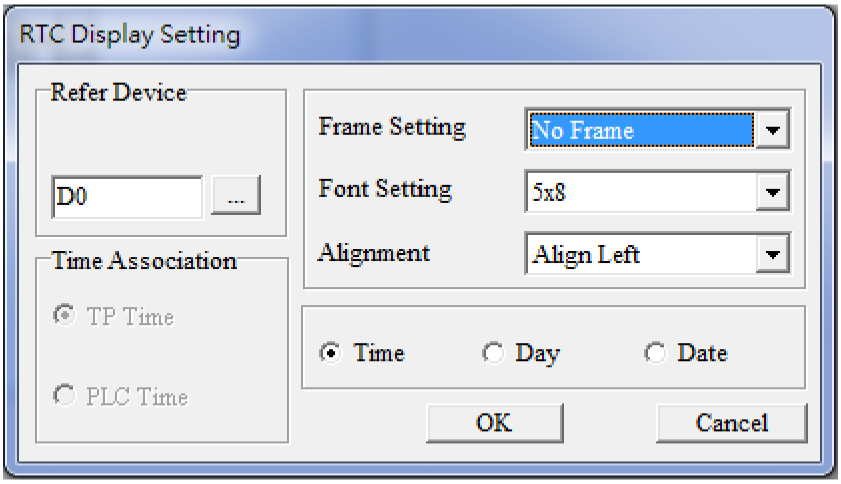
1. **Local Page Setting** and **Global Setting** functions are not supported.



2. In the **Communication** menu, **Read from TP** function is not supported.



3. In the **RTC Display Setting**, you cannot change the **Refer Device**.


RTC Display Setting

Refer Device: D0

Frame Setting: No Frame

Font Setting: 5x8

Alignment: Align Left

Time Association: ● TP Time ○ PLC Time

● Time ○ Day ○ Date

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Chapter 11 Summary of Parameter Settings

This chapter provides a summary of parameter (Pr.) setting ranges and defaults. You can set, changed and reset parameters through the digital keypad.

NOTE

1) ✎: You can set this parameter during operation
2) For more detail on parameters, refer to Ch12 Description of Parameter Settings.
3) The following are abbreviations for different types of motors:
   - IM: Induction motor
   - PM: Permanent magnet synchronous AC motor
   - IPM: Interior permanent magnet synchronous AC motor
   - SPM: Surface permanent magnet synchronous AC motor
   - SynRM: Synchronous reluctance motor

00 Drive Parameters

Pr.	Parameter Name	Settings Range	Default
00-00	AC motor drive identity code	4: 230V, 0.75 kW 5: 460V, 0.75 kW 6: 230V, 1.50 kW 7: 460V, 1.50 kW 8: 230V, 2.20 kW 9: 460V, 2.20 kW 10: 230V, 3.70 kW 11: 460V, 3.70 kW 12: 230V, 5.50 kW 13: 460V, 5.50 kW 14: 230V, 7.50 kW 15: 460V, 7.50 kW 16: 230V, 11.0 kW 17: 460V, 11.0 kW 18: 230V, 15.0 kW 19: 460V, 15.0 kW 20: 230V, 18.5 kW 21: 460V, 18.5 kW 22: 230V, 22.0 kW 23: 460V, 22.0 kW 24: 230V, 30.0 kW 25: 460V, 30.0 kW 26: 230V, 37.0 kW 27: 460V, 37.0 kW 28: 230V, 45.0 kW 29: 460V, 45.0 kW 30: 230V, 55.0 kW 31: 460V, 55.0 kW 32: 230V, 75.0 kW	Read only

Pr.	Parameter Name	Settings Range	Default
		33: 460V, 75.0 kW 34: 230V, 90.0 kW 35: 460V, 90.0 kW 37: 460V, 110.0 kW 39: 460V, 132.0 kW 41: 460V, 160.0 kW 43: 460V, 185.0 kW 45: 460V, 220.0 kW 47: 460V, 280.0 kW 49: 460V, 315.0 kW 51: 460V, 355.0 kW 53: 460V, 400.0 kW 55: 460V, 450.0 kW 57: 460V, 500.0 kW 59: 460V, 560.0 kW 61: 460V, 630.0 kW 90: 230V, 3.00 kW 91: 460V, 3.00 kW 92: 230V, 4.00 kW 93: 460V, 4.00 kW 486: 460V, 200 kW 487: 460V, 250 kW 505: 575V, 1.5 kW 506: 575V, 2.2 kW 507: 575V, 3.7 kW 508: 575V, 5.5 kW 509: 575V, 7.5 kW 510: 575V, 11 kW 511: 575V, 15 kW 612: 690V, 18.5 kW 613: 690V, 22 kW 614: 690V, 30 kW 615: 690V, 37 kW 616: 690V, 45 kW 617: 690V, 55 kW 618: 690V, 75 kW 619: 690V, 90 kW 620: 690V, 110 kW 621: 690V, 132 kW 622: 690V, 160 kW 626: 690V, 315 kW 628: 690V, 400 kW 629: 690V, 450 kW 631: 690V, 560 kW 632: 690V, 630 kW 686: 690V, 200 kW 687: 690V, 250 kW	
00-01	AC motor drive rated current display	Display by models	Read only

Pr.	Parameter Name	Settings Range	Default
00-02	Parameter reset	0: No function 1: Write protection for parameters 5: Return kWh displays to 0 6: Reset PLC (including CANopen Master Index) 7: Reset CANopen Slave index 9: Reset all parameters to defaults (base frequency is 50 Hz) 10: Reset all parameters to defaults (base frequency is 60 Hz)	0
✎ 00-03	Start-up display	0: F (frequency command) 1: H (output frequency) 2: U (user-defined, see Pr.00-04) 3: A (output current)	0
✎ 00-04	Content of multi-function display (user-defined)	0: Display output current (A) (Unit: Amp) 1: Display counter value (c) (Unit: CNT) 2: Display the motor's actual output frequency (H.) (Unit: Hz) 3: Display the drive's DC bus voltage (v) (Unit: V_{DC}) 4: Display the drive's output voltage (E) (Unit: V_{AC}) 5: Display the drive's output power angle (n) (Unit: deg) 6: Display the drive's output power (P) (Unit: kW) 7: Display the motor speed rpm (r) (Unit: rpm) 10: Display PID feedback (b) (Unit: %) 11: Display AVI1 analog input terminal signal (1.) (Unit: %) 12: Display ACI analog input terminal signal (2.) (Unit: %) 13: Display AVI2 analog input terminal signal (3.) (Unit: %) 14: Display the drive's IGBT temperature (i.) (Unit: °C) 15: Display the drive's capacitance temperature (c.) (Unit: °C) 16: The digital input status (ON / OFF) (i) 17: The digital output status (ON / OFF) (o) 18: Display multi-step speed (S) 19: The corresponding CPU digital input pin status (d) 20: The corresponding CPU digital output pin status (0.) 26: Ground fault GFF (G.) (Unit: %) 27: DC bus voltage ripple (r.) (Unit: V_{DC}) 28: Display PLC register D1043 data (C) 30: Display the output of User-defined (U) 31: Display Pr.00-05 user gain (K) 34: Operation speed of fan (F.) (Unit: %) 36: Present operating carrier frequency of the drive (J.) (Unit: Hz)	3

<table>
<tr><th>Pr.</th><th>Parameter Name</th><th>Settings Range</th><th>Default</th></tr>
<tr><td></td><td></td><td>38: Display the drive status (6.)
41: kWh display (J) (Unit: kWh)
42: PID target value (h.) (Unit: %)
43: PID compensation (o.) (Unit: %)
44: PID output frequency (b.) (Unit: Hz)
45: Hardware ID
51: PMSVC torque offset
52: AI10%
53: AI11%
68: STO version
69: STO checksum-high word (d)
70: STO checksum-low word (d)</td><td></td></tr>
<tr><td>⌿ 00-05</td><td>Coefficient gain in actual output frequency</td><td>0.00–160.00</td><td>1.00</td></tr>
<tr><td>00-06</td><td>Firmware version</td><td>Read only</td><td>Read only</td></tr>
<tr><td>⌿ 00-07</td><td>Parameter protection password input</td><td>0–65535
0–4: the number of password attempts allowed</td><td>0</td></tr>
<tr><td>⌿ 00-08</td><td>Parameter protection password setting</td><td>0–65535
0: No password protection or password entered correctly (Pr.00-07)
1: Parameter has been set</td><td>0</td></tr>
<tr><td>00-11</td><td>Speed control mode</td><td>0: IMVF (IM V/F control)
2: IM / PM SVC (IM / PM Space vector control)
6: PM Sensorless (PM filed-oriented sensorless vector control) (applied to 230V / 460V models)
8: SynRM Sensorless control (applied to 230V / 460V models)</td><td>0</td></tr>
<tr><td>00-16</td><td>Load selection</td><td>0: Light duty
1: Normal duty</td><td>0</td></tr>
<tr><td>00-17</td><td>Carrier Frequency (kHz)</td><td>230V / 460V models
Light duty
<table>
<tr><th>Control mode / Model</th><th>VF, SVC</th><th>PMFOC</th><th>SRMFOC*</th></tr>
<tr><td>VFD007–150CP23A/E
VFD007–185CP43A/E</td><td>2–15</td><td>4–10</td><td>4–8</td></tr>
<tr><td>VFD185–450CP23A/E
VFD220–750CP43A/E</td><td>2–10</td><td>4–10</td><td>4–8</td></tr>
<tr><td>VFD550–1100CP23A/E
VFD900–6300CP43A/E</td><td>2–9</td><td>4–9</td><td>4–8</td></tr>
</table>
*The default is 4 kHz in SRMFOC mode.
Normal duty
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<tr><th>Control mode / Model</th><th>VF, SVC</th><th>PMFOC</th><th>SRMFOC*</th></tr>
<tr><td>VFD007–150CP23A/E
VFD007–185CP43A/E</td><td>2–15</td><td>4–10</td><td>4–8</td></tr>
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VFD220–750CP43A/E</td><td>2–10</td><td>4–10</td><td>4–8</td></tr>
<tr><td>VFD550–1100CP23A/E
VFD900–6300CP43A/E</td><td>2–9</td><td>4–9</td><td>4–8</td></tr>
</table>
*The default is 4 kHz in SRMFOC mode.</td><td>8
6
4

8
6
4</td></tr>
</table>

<table>
<tr><th>Pr.</th><th>Parameter Name</th><th>Settings Range</th><th>Default</th></tr>
<tr><td></td><td></td><td>575V / 690V models
Light duty
<table>
<tr><th>Control mode
Model</th><th>VF, SVC</th></tr>
<tr><td>VFD015–150CP53A</td><td>2–9</td></tr>
<tr><td>VFD185–5600CP63A</td><td>2–9</td></tr>
<tr><td>VFD6300CP63A</td><td>2–9</td></tr>
</table>
Normal duty
<table>
<tr><th>Control mode
Model</th><th>VF, SVC</th></tr>
<tr><td>VFD015–150CP53A</td><td>2–9</td></tr>
<tr><td>VFD185–5600CP63A</td><td>2–9</td></tr>
<tr><td>VFD6300CP63A</td><td>2–9</td></tr>
</table></td><td>4
4
3

4
4
3</td></tr>
<tr><td>00-19</td><td>PLC command mask</td><td>bit0: Control command is forced by PLC control
bit1: Frequency command is forced by PLC control</td><td>Read only</td></tr>
<tr><td>00-20</td><td>Master frequency command source (AUTO) / Source selection of the PID target</td><td>0: Digital keypad
1: RS-485 communication input
2: External analog input (Refer to Pr.03-00–03-02)
3: External UP / DOWN terminal (multi-function input terminals)
6: CANopen communication card
8: Communication card (does not include CANopen card)</td><td>0</td></tr>
<tr><td>00-21</td><td>Operation command source (AUTO)</td><td>0: Digital keypad
1: External terminals
2: RS-485 communication input
3: CANopen communication card
5: Communication card (does not include CANopen card)</td><td>0</td></tr>
<tr><td>✓ 00-22</td><td>Stop method</td><td>0: Ramp to stop
1: Coast to stop</td><td>0</td></tr>
<tr><td>✓ 00-23</td><td>Motor direction control</td><td>0: Enable forward / reverse
1: Disable reverse
2: Disable forward</td><td>0</td></tr>
<tr><td>00-24</td><td>Digital operator (keypad) frequency command memory</td><td>Read only</td><td>Read only</td></tr>
<tr><td>✓ 00-25</td><td>User-defined characteristics</td><td>bit0–3: user-defined decimal place
0000b: no decimal place
0001b: one decimal place
0010b: two decimal places
0011b: three decimal places
bit4–15: user-defined unit
000xh: Hz
001xh: rpm
002xh: %
003xh: kg</td><td>0</td></tr>
</table>

Pr.	Parameter Name	Settings Range	Default
		004xh: m/s 005xh: kW 006xh: HP 007xh: ppm 008xh: 1/m 009xh: kg/s 00Axh: kg/m 00Bxh: kg/h 00Cxh: lb/s 00Dxh: lb/m 00Exh: lb/h 00Fxh: ft/s 010xh: ft/m 011xh: m 012xh: ft 013xh: degC 014xh: degF 015xh: mbar 016xh: bar 017xh: Pa 018xh: kPa 019xh: mWG 01Axh: inWG 01Bxh: ftWG 01Cxh: psi 01Dxh: atm 01Exh: L/s 01Fxh: L/m 020xh: L/h 021xh: m3/s 022xh: m3/h 023xh: GPM 024xh: CFM xxxxh: Hz	
00-26	Maximum user-defined value	0: No function 0–65535 (when Pr.00-25 is set to no decimal place) 0.0–6553.5 (when Pr.00-25 is set to 1 decimal place) 0.00–655.35 (when Pr.00-25 is set to 2 decimal places) 0.000–65.535 (when Pr.00-25 is set to 3 decimal places)	0
00-27	User-defined value	Read only	Read Only
✓ 00-28	Switching from AUTO mode to HAND mode	bit0: Sleep function control bit 0: Cancel sleep function 1: Sleep function and Auto mode are the same bit1: Control bit unit 0: Displaying unit in Hz	

Pr.	Parameter Name	Settings Range	Default
		1: Same unit as the Auto mode bit2: PID control bit 0: Cancel PID control 1: PID control and Auto mode are the same bit3: Frequency source control bit 0: Frequency source set up by parameter, if the multi-step speed is activated, then multi-speed has the priority. 1: Frequency command set up by Pr.00-30, regardless of whether the multi-step speed is activated.	
00-29	LOCAL / REMOTE selection	0: Standard HOA function 1: When switching between local and remote, the drive stops 2: When switching between local and remote, the drive runs with REMOTE settings for frequency and operation status 3: When switching between local and remote, the drive runs with LOCAL settings for frequency and operation status 4: When switching between local and remote, the drive runs with LOCAL settings when switched to Local and runs with REMOTE settings when switched to Remote for frequency and operation status.	0
00-30	Master frequency command source (HAND)	0: Digital keypad 1: RS-485 communication input 2: External analog input (Refer to Pr.03-00–03-02) 3: External UP / DOWN terminal 6: CANopen communication card 8: Communication card (does not include CANopen card)	0
00-31	Operation command source (HAND)	0: Digital keypad 1: External terminals 2: RS-485 communication input 3: CANopen communication card 5: Communication card (does not include CANopen card)	0
ϟ 00-32	Digital keypad STOP function	0: STOP key disabled 1: STOP key enabled	0
ϟ 00-37	Over-modulation gain	80–120	100
ϟ 00-48	Display filter time (current)	0.001–65.535 sec.	0.100
ϟ 00-49	Display filter time (keypad)	0.001–65.535 sec.	0.100
00-50	Software version (Date)	Read only	Read only

01 Basic Parameters

	Pr.	Parameter Name	Settings Range	Default
〆	01-00	Maximum operation frequency of motor 1	50.00–599.00 Hz Setting range for/including 45 kW (60 HP) and above: 0.00–400 Hz	60.00 / 50.00
	01-01	Rated / base frequency of motor 1	0.00–599.00 Hz	60.00 / 50.00
	01-02	Rated / base voltage of motor 1	230V models: 0.0–255.0 V 460V models: 0.0–510.0 V 575V models: 0.0–637.0 V 690V models: 0.0–765.0 V	200.0 400.0 575.0 660.0
	01-03	Mid-point frequency 1 of motor 1	0.00–599.00 Hz	3.00 / 0.00
〆	01-04	Mid-point voltage 1 of motor 1	230V models: 0.0–240.0 V 460V models: 0.0–480.0 V 575V models: 0.0–637.0 V 690V models: 0.0–720.0 V *690V, with 185 kW and above: 10.0	11.0 22.0 0.0 0.0
	01-05	Mid-point frequency 2 of motor 1	0.00–599.00 Hz	1.50
〆	01-06	Mid-point voltage 2 of motor 1	230V models: 0.0–240.0 V 460V models: 0.0–480.0 V 575V models: 0.0–637.0 V 690V models: 0.0–720.0 V *690V, with 185 kW and above: 2.0	5.0 10.0 0.0 0.0
	01-07	Minimum output frequency of motor 1	0.00–599.00 Hz	1.50
〆	01-08	Minimum output voltage of motor 1	230V models: 0.0–240.0 V 460V models: 0.0–480.0 V 575V models: 0.0–637.0 V 690V models: 0.0–720.0 V	1.0 2.0 0.0 0.0
	01-09	Start-up frequency	0.00–599.00 Hz	0.50
〆	01-10	Output frequency upper limit	0.00–599.00 Hz	599.00
〆	01-11	Output frequency lower limit	0.00–599.00 Hz	0.00

〆	01-12	Acceleration time 1	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

〆	01-13	Deceleration time 1	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

〆	01-14	Acceleration time 2	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

	Pr.	Parameter Name	Settings Range	Default

ϟ	01-15	Deceleration time 2	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-16	Acceleration time 3	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-17	Deceleration time 3	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-18	Acceleration time 4	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-19	Deceleration time 4	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-20	JOG acceleration time	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-21	JOG deceleration time	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
			Motor drive with 230V/460V/690V, 22 kW and above: 60.00 / 60.0
			Motor drive with 690V, 160 kW and above: 80.00 / 80.0
				10.00

ϟ	01-22	JOG frequency	0.00–599.00 Hz	6.00
ϟ	01-23	Switch frequency between first and fourth Accel. / Decel.	0.00–599.00 Hz	0.00

ϟ	01-24	S-curve for acceleration begin time 1	Pr.01-45 = 0: 0.00–25.00 sec.
			Pr.01-45 = 1: 0.0–250.0 sec.
				0.20

ϟ	01-25	S-curve for acceleration arrival time 2	Pr.01-45 = 0: 0.00–25.00 sec.
			Pr.01-45 = 1: 0.0–250.0 sec.
				0.20

ϟ	01-26	S-curve for deceleration begin time 1	Pr.01-45 = 0: 0.00–25.00 sec.
			Pr.01-45 = 1: 0.0–250.0 sec.
				0.20

ϟ	01-27	S-curve for deceleration arrival time 2	Pr.01-45 = 0: 0.00–25.00 sec.
			Pr.01-45 = 1: 0.0–250.0 sec.
				0.20

	01-28	Skip frequency 1 (upper limit)	0.00–599.00 Hz	0.00
	01-29	Skip frequency 1 (lower limit)	0.00–599.00 Hz	0.00

Pr.	Parameter Name	Settings Range	Default
01-30	Skip frequency 2 (upper limit)	0.00–599.00 Hz	0.00
01-31	Skip frequency 2 (lower limit)	0.00–599.00 Hz	0.00
01-32	Skip frequency 3 (upper limit)	0.00–599.00 Hz	0.00
01-33	Skip frequency 3 (lower limit)	0.00–599.00 Hz	0.00
01-34	Zero-speed mode	0: Output waiting 1: Zero-speed operation 2: Minimum frequency (Refer to Pr.01-07 and Pr.01-41)	0
01-35	Rated / base frequency of motor 2	0.00–599.00 Hz	60.00 / 50.00
01-36	Rated / base voltage of motor 2	230V models: 0.0–255.0 V 460V models: 0.0–510.0 V 575V models: 0.0–637.0 V 690V models: 0.0–765.0 V	200.0 400.0 575.0 660.0
01-37	Mid-point frequency 1 of motor 2	0.00–599.00 Hz	3.00
⌁ 01-38	Mid-point voltage 1 of motor 2	230V models: 0.0–240.0 V 460V models: 0.0–480.0 V 575V models: 0.0–637.0 V 690V models: 0.0–720.0 V Motor drive with 690V, 185 kW and above: 10.0	11.0 22.0 0.0 0.0
01-39	Mid-point frequency 2 of motor 2	0.00–599.00 Hz	1.50
⌁ 01-40	Mid-point voltage 2 of motor 2	230V models: 0.0–240.0 V 460V models: 0.0–480.0 V 575V models: 0.0–637.0 V 690V models: 0.0–720.0 V Motor drive with 690V, 185 kW and above: 2.0	5.0 10.0 0.0 0.0
01-41	Minimum output frequency of motor 2	0.00–599.00 Hz	0.50
⌁ 01-42	Minimum output voltage of motor 2	230V models: 0.0–240.0 V 460V models: 0.0–480.0 V 575V models: 0.0–637.0 V 690V models: 0.0–720.0 V	1.0 2.0 0.0 0.0
01-43	V/F curve selection	0: V/F curve determined by Pr.01-00–01-08 1: V/F curve to the power of 1.5 2: V/F curve to the power of 2 3: 60 Hz, voltage saturation in 50 Hz 4: 72 Hz, voltage saturation in 60 Hz 5: 50 Hz, decrease gradually with cube 6: 50 Hz, decrease gradually with square 7: 60 Hz, decrease gradually with cube 8: 60 Hz, decrease gradually with square 9: 50 Hz, medium starting torque 10: 50 Hz, high starting torque 11: 60 Hz, medium starting torque 12: 60 Hz, high starting torque 13: 90 Hz, voltage saturation in 60 Hz 14: 120 Hz, voltage saturation in 60 Hz 15: 180 Hz, voltage saturation in 60 Hz	0

	Pr.	Parameter Name	Settings Range	Default
⌁	01-44	Auto-acceleration and auto-deceleration setting	0: Linear acceleration and deceleration 1: Auto-acceleration and linear deceleration 2: Linear acceleration and auto-deceleration 3: Auto-acceleration and auto-deceleration 4: Stall prevention by auto-acceleration and auto-deceleration (limited by Pr.01-12–01-21)	0
	01-45	Time unit for acceleration / deceleration and S-curve	0: Unit: 0.01 sec. 1: Unit: 0.1 sec.	0

⌁	01-46	CANopen quick stop time	Pr.01-45 = 0: 0.00–600.00 sec.
			Pr.01-45 = 1: 0.0–6000.0 sec.
				1.00
				1.0

	01-49	Deceleration method selection	0: Normal deceleration 1: Over-voltage energy restriction 2: Traction energy control (TEC) 3: Electromagnetic energy traction control	0
⌁	01-50	Electromagnetic traction energy consumption coefficient	0.00–5.00 Hz	0.50
⌁	01-51	Flux-weakening overload stall prevention time (applied to 230V / 460V models)	0.00–600.00 sec.	1.00

02 Digital Input / Output Parameters

Pr.	Parameter Name	Setting Range	Default
02-00	Two-wire / three-wire operation control	0: Two-wire mode 1, power on for operation control 1: Two-wire mode 2, power on for operation control 2: Three-wire, power on for operation control	0
02-01	Multi-function input command 1 (MI1)	0: No function 1: Multi-step speed command 1 2: Multi-step speed command 2 3: Multi-step speed command 3 4: Multi-step speed command 4 5: Reset 6: JOG operation (By KPC-CC01 or external control) 7: Acceleration / deceleration speed inhibit 8: 1st and 2nd acceleration / deceleration time selection 9: 3rd and 4th acceleration / deceleration time selection 10: External Fault (EF) input (Pr.07-20) 11: Base Block (B.B) input from external 12: Output stop 13: Cancel the setting of auto-acceleration / auto-deceleration time 14: Switch between motor 1 and motor 2 15: Rotating speed command from AVI1 16: Rotating speed command from ACI 17: Rotating speed command from AVI2 18: Forced to stop (Pr.07-20) 19: Frequency up command 20: Frequency down command 21: PID function disabled 22: Clear the counter 23: Input the counter value (MI6) 24: FWD JOG command 25: REV JOG command 28: Emergency stop (EF1) 29: Signal confirmation for Y-connection 30: Signal confirmation for Δ-connection 38: Disable write EEPROM function 40: Force coasting to stop 41: HAND switch 42: AUTO switch 49: Enable drive 50: Slave dEb action to execute 51: Selection for PLC mode bit0 52: Selection for PLC mode bit1 53: Trigger CANopen quick stop	1
02-02	Multi-function input command 2 (MI2)		2
02-03	Multi-function input command 3 (MI3)		3
02-04	Multi-function input command 4 (MI4)		4
02-05	Multi-function input command 5 (MI5)		0
02-06	Multi-function input command 6 (MI6)		0
02-07	Multi-function input command 7 (MI7)		0
02-08	Multi-function input command 8 (MI8)		0
02-26	Input terminal of I/O extension card (MI10)		0
02-27	Input terminal of I/O extension card (MI11)		0
02-28	Input terminal of I/O extension card (MI12)		0
02-29	Input terminal of I/O extension card (MI13)		0
02-30	Input terminal of I/O extension card (MI14)		0
02-31	Input terminal of I/O extension card (MI15)		0

	Pr.	Parameter Name	Setting Range	Default
			54: UVW output electromagnetic valve switch 55: Brake release 56: Local / Remote selection 58: Enable fire mode (with RUN command) 59: Enable fire mode (without RUN command) 60: Disable all the motors 61: Disable Motor 1 62: Disable Motor 2 63: Disable Motor 3 64: Disable Motor 4 65: Disable Motor 5 66: Disable Motor 6 67: Disable Motor 7 68: Disable Motor 8 69: Preheating command	
✎	02-09	UP / DOWN key mode	0: UP / DOWN by the acceleration / deceleration time 1: UP / DOWN constant speed (Pr.02-10)	0
✎	02-10	Constant speed, acceleration / deceleration speed of the UP / DOWN key	0.001–1.000 Hz / ms	0.001
✎	02-11	Multi-function input response time	0.000–30.000 sec.	0.005
✎	02-12	Multi-function input mode selection	0000h–FFFFh (0: N.O.; 1: N.C.)	0000h
✎	02-13	Multi-function output 1 RLY1	0: No function 1: Indication during RUN 2: Operation speed reached 3: Desired frequency reached 1 (Pr.02-22) 4: Desired frequency reached 2 (Pr.02-24) 5: Zero speed (Frequency command) 6: Zero speed including STOP (Frequency command) 7: Over-torque 1 (Pr.06-06–06-08) 8: Over-torque 2 (Pr.06-09–06-11) 9: Drive is ready 10: Low voltage warning (Lv) (Pr.06-00) 11: Malfunction indication 12: Mechanical brake release (Pr.02-32) 13: Overheat warning (Pr.06-15) 14: Software brake signal indication (Pr.07-00) 15: PID feedback error (Pr.08-13, Pr.08-14) 16: Slip error (oSL) 17: Count value reached, does not return to 0 (Pr.02-20) 18: Count value reached, returns to 0 (Pr.02-19) 19: External interrupt B.B. input (Base Block) 20: Warning output 21: Over-voltage	11
✎	02-14	Multi-function output 2 RLY2		1
✎	02-15	Multi-function output 3 RLY3		66
✎	02-36	Output terminal of I/O extension card (MO10) or (RA10)		0
✎	02-37	Output terminal of I/O extension card (MO11) or (RA11)		0
✎	02-38	Output terminal of I/O extension card (RA12)		0
✎	02-39	Output terminal of I/O extension card (RA13)		0
✎	02-40	Output terminal of I/O extension card (RA14)		0
✎	02-41	Output terminal of I/O extension card (RA15)		0
✎	02-42	Output terminal of I/O extension card (MO16 virtual terminal)		0
✎	02-43	Output terminal of I/O extension card (MO17 virtual terminal)		0
✎	02-44	Output terminal of I/O extension card (MO18 virtual terminal)		0
✎	02-45	Output terminal of I/O extension card (MO19 virtual terminal)		0
✎	02-46	Output terminal of I/O extension card (MO20 virtual terminal)		0

	Pr.	Parameter Name	Setting Range	Default
			22: Over-current stall prevention 23: Over-voltage stall prevention 24: Operation mode 25: Forward command 26: Reverse command 27: Output when current ≥ Pr.02-33 28: Output when current < Pr.02-33 29: Output when frequency ≥ Pr.02-34 30: Output when frequency < Pr.02-34 31: Y-connection for the motor coil 32: ∆-connection for the motor coil 33: Zero speed (actual output frequency) 34: Zero speed including stop (actual output frequency) 35: Error output selection 1 (Pr.06-23) 36: Error output selection 2 (Pr.06-24) 37: Error output selection 3 (Pr.06-25) 38: Error output selection 4 (Pr.06-26) 40: Speed reached (including stop) 44: Low current output (use with Pr.06-71–06-73) 45: UVW output electromagnetic valve switch 46: Master dEb output 50: Output control for CANopen 51: Analog output control for RS-485 interface (InnerCOM / Modbus) 52: Output control for communication cards 53: Fire mode indication 54: Bypass fire mode indication 55: Motor 1 output 56: Motor 2 output 57: Motor 3 output 58: Motor 4 output 59: Motor 5 output 60: Motor 6 output 61: Motor 7 output 62: Motor 8 output 66: SO output logic A 67: Analog input level reached 68: SO output logic B 69: Preheating output indication	
ϰ	02-18	Multi-function output direction	0000h–FFFFh (0: N.O.; 1: N.C.)	0000h
ϰ	02-19	Terminal counting value reached (returns to 0)	0–65500	0
ϰ	02-20	Preliminary counting value reached (does not return to 0)	0–65500	0
ϰ	02-22	Desired frequency reached 1	0.00–599.00 Hz	60.00 / 50.00
ϰ	02-23	The width of the desired frequency reached 1	0.00–599.00 Hz	2.00

	Pr.	Parameter Name	Setting Range	Default
✓	02-24	Desired frequency reached 2	0.00–599.00 Hz	60.00 / 50.00
✓	02-25	The width of the desired frequency reached 2	0.00–599.00 Hz	2.00
	02-32	Brake delay time	0.000–65.000 sec.	0.000
✓	02-33	Output current level setting for multi-function output terminal	0–150%	0
✓	02-34	Output frequency setting for multi-function output terminal	0.00–599.00 Hz	3.00
✓	02-35	External operation control selection after reset and reboot	0: Disable 1: Drive runs if the RUN command remains after reset or reboot	0
	02-50	Display the status of multi-function input terminal	Monitor the status of multi-function input terminals	Read only
	02-51	Display the status of multi-function output terminal	Monitor the status of multi-function output terminals	Read only
	02-52	Display the external multi-function input terminals used by PLC	Monitor the status of PLC input terminals	Read only
	02-53	Display the external multi-function output terminals used by PLC	Monitor the status of PLC output terminals	Read only
	02-54	Display the frequency command executed by external terminal	0.00–599.00 Hz (Read only)	Read only
	02-70	IO card types	1: EMC-BPS01 4: EMC-D611A 5: EMC-D42A 6: EMC-R6AA 11: EMC-A22A	Read only
✓	02-72	Preheating output current level	0–100%	0
✓	02-73	Preheating output cycle	0–100%	0

03 Analog Input / Output Parameters

	Pr.	Parameter Name	Setting Range	Default
✓	03-00	AVI1 analog input selection	0: No function 1: Frequency command (speed limit under torque control mode) 4: PID target value 5: PID feedback signal 6: Thermistor (PTC) input value 11: PT100 thermistor input value 13: PID compensation value	1
✓	03-01	ACI analog input selection		0
✓	03-02	AVI2 analog input selection		0
✓	03-03	AVI1 analog input bias	-100.0–100.0%	0.0
✓	03-04	ACI analog input bias		
✓	03-05	AVI2 analog positive voltage input bias		
✓	03-07	AVI1 positive / negative bias mode	0: No bias 1: Lower than or equal to bias 2: Greater than or equal to bias 3: The absolute value of the bias voltage while serving as the center 4: Bias serves as the center	0
✓	03-08	ACI positive / negative bias mode		
✓	03-09	AVI2 positive / negative bias mode		
✓	03-10	Reverse setting when analog signal input is negative frequency	0: Negative frequency input is not allowed. The digital keypad or external terminal controls the forward and reverse direction. 1: Negative frequency is allowed. Positive frequency = run in a forward direction; negative frequency = run in a reverse direction. The digital keypad or external terminal control cannot change the running direction.	0
✓	03-11	AVI1 analog input gain	-500.0–500.0%	100.0
✓	03-12	ACI analog input gain		
✓	03-13	AVI2 analog positive input gain		
✓	03-14	AVI2 analog negative input gain		
✓	03-15	AVI1 analog input filter time	0.00–20.00 sec.	0.01
✓	03-16	ACI analog input filter time		
✓	03-17	AVI2 analog input filter time		
✓	03-18	Analog input addition function	0: Disable (AVI1, ACI, AVI2) 1: Enable	0
	03-19	Signal loss selection for the analog input 4–20 mA	0: Disable 1: Continue operation at the last frequency 2: Decelerate to 0 Hz 3: Stop immediately and display ACE	0
✓	03-20	AFM1 analog output selection	0: Output frequency (Hz) 1: Frequency command (Hz) 2: Motor speed (Hz) 3: Output current (rms) 4: Output voltage 5: DC bus voltage	0
✓	03-23	AFM2 analog output selection		0

	Pr.	Parameter Name	Setting Range	Default
			6: Power factor 7: Power 9: AVI1% 10: ACI% 11: AVI2% 20: CANopen analog output 21: RS-485 analog output 22: Communication card analog output 23: Constant voltage output	
✎	03-21	AFM1 analog output gain	0.0–500.0%	100.0
✎	03-22	AFM1 analog output REV direction	0: Absolute value in output voltage 1: Reverse output 0 V; forward output 0–10 V 2: Reverse output 5–0 V; forward output 5–10 V	0
✎	03-24	AFM2 analog output gain	0.0–500.0%	100.0
✎	03-25	AFM2 analog output REV direction	0: Absolute value in output voltage 1: Reverse output 0 V; forward output 0–10 V 2: Reverse output 5–0 V; forward output 5–10 V	0
✎	03-27	AFM2 output bias	-100.00–100.00%	0.00
✎	03-28	AVI1 terminal input selection	0: 0–10 V 1: 0–20 mA 2: 4–20 mA	0
✎	03-29	ACI terminal input selection	0: 4–20 mA 1: 0–10 V 2: 0–20 mA	0
	03-30	PLC analog output terminal status	Monitor the status of the PLC analog output terminals	Read only
✎	03-31	AFM2 output selection	0: 0–20 mA output 1: 4–20 mA output	0
✎	03-32	AFM1 DC output setting level	0.00–100.00%	0.00
✎	03-33	AFM2 DC output setting level		
	03-34	AFM1 output selection	0: 0–20 mA output 1: 4–20 mA output	0
✎	03-35	AFM1 output filter time	0.00–20.00 sec.	0.01
✎	03-36	AFM2 output filter time		
✎	03-44	Multi-function output (MO) by AI level source	0: AVI1 1: ACI 2: AVI2	0
✎	03-45	AI upper level	-100.00–100.00%	50.00
✎	03-46	AI lower level	-100.00–100.00%	10.00
✎	03-50	Analog input curve selection	0: Normal curve 1: Three-point curve of AVI1 2: Three-point curve of ACI 3: Three-point curve of AVI1 & ACI 4: Three-point curve of AVI2 5: Three-point curve of AVI1 & AVI2 6: Three-point curve of ACI & AVI2 7: Three-point curve of AVI1 & ACI & AVI2	7

	Pr.	Parameter Name	Setting Range	Default

ϟ	03-51	AVI1 lowest point	Pr.03-28 = 0, 0.00–10.00 V
			Pr.03-28 = 1, 0.00–20.00 mA
			Pr.03-28 = 2, 0.00–20.00 mA
				0.00
				0.00
				4.00

ϟ	03-52	AVI1 proportional lowest point	-100.00–100.00%	0.00

ϟ	03-53	AVI1 mid-point	Pr.03-28 = 0, 0.00–10.00 V
			Pr.03-28 = 1, 0.00–20.00 mA
			Pr.03-28 = 2, 0.00–20.00 mA
				5.00
				10.00
				12.00

ϟ	03-54	AVI1 proportional mid-point	-100.00–100.00%	50.00

ϟ	03-55	AVI1 highest point	Pr.03-28 = 0, 0.00–10.00 V
			Pr.03-28 = 1, 0.00–20.00 mA
			Pr.03-28 = 2, 0.00–20.00 mA
				10.00
				20.00
				20.00

ϟ	03-56	AVI1 proportional highest point	-100.00–100.00%	100.00

ϟ	03-57	ACI lowest point	Pr.03-29 = 0, 0.00–20.00 mA
			Pr.03-29 = 1, 0.00–10.00 V
			Pr.03-29 = 2, 0.00–20.00 mA
				4.00
				0.00
				0.00

ϟ	03-58	ACI proportional lowest point	-100.00–100.00%	0.00

ϟ	03-59	ACI mid-point	Pr.03-29 = 0, 0.00–20.00 mA
			Pr.03-29 = 1, 0.00–10.00 V
			Pr.03-29 = 2, 0.00–20.00 mA
				12.00
				5.00
				10.00

ϟ	03-60	ACI proportional mid-point	-100.00–100.00%	50.00

ϟ	03-61	ACI high point	Pr.03-29 = 0, 0.00–20.00 mA
			Pr.03-29 = 1, 0.00–10.00 V
			Pr.03-29 = 2, 0.00–20.00 mA
				20.00
				10.00
				20.00

ϟ	03-62	ACI proportional highest point	-100.00–100.00%	100.00
ϟ	03-63	Positive AVI2 voltage lowest point	0.00–10.00 V	0.00
ϟ	03-64	Positive AVI2 voltage proportional lowest point	-100.00–100.00%	0.00
ϟ	03-65	Positive AVI2 voltage mid-point	0.00–10.00 V	5.00
ϟ	03-66	Positive AVI2 voltage proportional mid-point	-100.00–100.00%	50.00
ϟ	03-67	Positive AVI2 voltage highest point	0.00–10.00 V	10.00
ϟ	03-68	Positive AVI2 voltage proportional highest point	-100.00–100.00%	100.00

04 Multi-step Speed Parameters

	Pr.	Parameter Name	Setting Range	Default
ϟ	04-00	1st step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-01	2nd step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-02	3rd step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-03	4th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-04	5th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-05	6th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-06	7th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-07	8th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-08	9th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-09	10th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-10	11th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-11	12th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-12	13th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-13	14th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-14	15th step speed frequency	0.00–599.00 Hz	0.00
ϟ	04-50	PLC buffer 0	0–65535	0
ϟ	04-51	PLC buffer 1	0–65535	0
ϟ	04-52	PLC buffer 2	0–65535	0
ϟ	04-53	PLC buffer 3	0–65535	0
ϟ	04-54	PLC buffer 4	0–65535	0
ϟ	04-55	PLC buffer 5	0–65535	0
ϟ	04-56	PLC buffer 6	0–65535	0
ϟ	04-57	PLC buffer 7	0–65535	0
ϟ	04-58	PLC buffer 8	0–65535	0
ϟ	04-59	PLC buffer 9	0–65535	0
ϟ	04-60	PLC buffer 10	0–65535	0
ϟ	04-61	PLC buffer 11	0–65535	0
ϟ	04-62	PLC buffer 12	0–65535	0
ϟ	04-63	PLC buffer 13	0–65535	0
ϟ	04-64	PLC buffer 14	0–65535	0
ϟ	04-65	PLC buffer 15	0–65535	0
ϟ	04-66	PLC buffer 16	0–65535	0
ϟ	04-67	PLC buffer 17	0–65535	0
ϟ	04-68	PLC buffer 18	0–65535	0
ϟ	04-69	PLC buffer 19	0–65535	0
ϟ	04-70	PLC Application parameter 0	0–65535	0
ϟ	04-71	PLC Application parameter 1	0–65535	0
ϟ	04-72	PLC Application parameter 2	0–65535	0
ϟ	04-73	PLC Application parameter 3	0–65535	0
ϟ	04-74	PLC Application parameter 4	0–65535	0
ϟ	04-75	PLC Application parameter 5	0–65535	0
ϟ	04-76	PLC Application parameter 6	0–65535	0
ϟ	04-77	PLC Application parameter 7	0–65535	0
ϟ	04-78	PLC Application parameter 8	0–65535	0
ϟ	04-79	PLC Application parameter 9	0–65535	0

	Pr.	Parameter Name	Setting Range	Default
✎	04-80	PLC Application parameter 10	0–65535	0
✎	04-81	PLC Application parameter 11	0–65535	0
✎	04-82	PLC Application parameter 12	0–65535	0
✎	04-83	PLC Application parameter 13	0–65535	0
✎	04-84	PLC Application parameter 14	0–65535	0
✎	04-85	PLC Application parameter 15	0–65535	0
✎	04-86	PLC Application parameter 16	0–65535	0
✎	04-87	PLC Application parameter 17	0–65535	0
✎	04-88	PLC Application parameter 18	0–65535	0
✎	04-89	PLC Application parameter 19	0–65535	0
✎	04-90	PLC Application parameter 20	0–65535	0
✎	04-91	PLC Application parameter 21	0–65535	0
✎	04-92	PLC Application parameter 22	0–65535	0
✎	04-93	PLC Application parameter 23	0–65535	0
✎	04-94	PLC Application parameter 24	0–65535	0
✎	04-95	PLC Application parameter 25	0–65535	0
✎	04-96	PLC Application parameter 26	0–65535	0
✎	04-97	PLC Application parameter 27	0–65535	0
✎	04-98	PLC Application parameter 28	0–65535	0
✎	04-99	PLC Application parameter 29	0–65535	0

05 Motor Parameters

Pr.	Parameter Name	Setting Range	Default
05-00	Motor parameter auto-tuning	0: No function 1: Simple rolling auto-tuning for induction motor (IM) 2: Static auto-tuning for induction motor (IM) 5: Rolling auto-tuning for PM (IPM / SPM) 11: SynRM parameter auto-tuning (applied to 230V / 460V models) 13: Static auto-tuning for PM (IPM / SPM)	0
05-01	Full-load current for induction motor 1 (A)	Depending on the model power	Depending on the model power
✎ 05-02	Rated power for induction motor 1 (kW)	0.00–655.35 kW	Depending on the model power
✎ 05-03	Rated speed for induction motor 1 (rpm)	0–xxxx rpm (Depending on the motor's number of poles) 1710 (60 Hz 4 poles); 1410 (50 Hz 4 poles)	Depending on the motor's number of poles
05-04	Number of poles for induction motor 1	2–64	4
05-05	No-load current for induction motor 1 (A)	0.00–Pr.05-01 default	Depending on the model power
05-06	Stator resistance (Rs) for induction motor 1	0.000–65.535 Ω	Depending on the model power
05-07	Rotor resistance (Rr) for induction motor 1	0.000–65.535 Ω	0.000
05-08	Magnetizing inductance (Lm) for induction motor 1	0.0–6553.5 mH	0.0
05-09	Stator inductance (Lx) for induction motor 1	0.0–6553.5 mH	0.0
05-13	Full-load current for induction motor 2 (A)	Depending on the model power	Depending on the model power
✎ 05-14	Rated power for induction motor 2 (kW)	0.00–655.35 kW	Depending on the model power
✎ 05-15	Rated speed for induction motor 2 (rpm)	0–xxxx rpm (Depending on the motor's number of poles) 1710 (60 Hz 4 poles) ; 1410 (50 Hz 4 poles)	Depending on the motor's number of poles
05-16	Number of poles for induction motor 2	2–64	4
05-17	No-load current for induction motor 2 (A)	0.00–Pr.05-13 default	Depending on the model power
05-18	Stator resistance (Rs) for induction motor 2	0.000–65.535 Ω	Depending on the model power

Pr.	Parameter Name	Setting Range	Default
05-19	Rotor resistance (Rr) for induction motor 2	0.000–65.535 Ω	0.000
05-20	Magnetizing inductance (Lm) for induction motor 2	0.0–6553.5 mH	0.0
05-21	Stator inductance (Lx) for induction motor 2	0.0–6553.5 mH	0.0
05-22	Induction motor 1 / 2 selection	1: Motor 1 2: Motor 2	1
⌿ 05-23	Frequency for Y-connection / Δ-connection switch for an induction motor	0.00–599.00 Hz	60.00
05-24	Y-connection / Δ-connection switch for an induction motor	0: Disable 1: Enable	0
⌿ 05-25	Delay time for Y-connection / Δ-connection switch for an induction motor	0.000–60.000 sec.	0.200
05-28	Accumulated Watt-hour for a motor (W-hour)	0.0–6553.5	Read only
05-29	Accumulated Watt-hour for a motor in low word (kW-hour)	0.0–6553.5	Read only
05-30	Accumulated Watt-hour for a motor in high word (MW-hour)	0–65535	Read only
05-31	Accumulated motor operation time (minutes)	0–1439	0
05-32	Accumulated motor operation time (days)	0–65535	0
05-33	Induction motor (IM) or permanent magnet synchronous AC motor (PM) selection	0: IM 1: SPM 2: IPM 3: SynRM (applied to 230V / 460V models)	0
05-34	Full-load current for a permanent magnet synchronous AC motor / reluctance motor	Depending on the model power	Depending on the model power
⌿ 05-35	Rated power for a permanent magnet synchronous AC motor / reluctance motor	0.00–655.35 kW	Depending on the motor power
⌿ 05-36	Rated speed for a permanent magnet synchronous AC motor / reluctance motor	0–65535 rpm	2000
05-37	Number of poles for a permanent magnet synchronous AC motor / reluctance motor	0–65535	10
05-38	System inertia for a permanent magnet synchronous AC motor / reluctance motor	0.0–6553.5 kg-cm^2	Depending on the motor power
05-39	Stator resistance for a permanent magnet synchronous AC motor / reluctance motor	0.000–65.535 Ω	0.000

Pr.	Parameter Name	Setting Range	Default
05-40	Permanent magnet synchronous AC motor / reluctance motor Ld	0.00–655.35 mH	0.00
05-41	Permanent magnet synchronous AC motor / reluctance motor Lq	0.00–655.35 mH	0.00
✎ 05-43	Ke parameter for a permanent magnet synchronous AC motor	0–65535 (Unit: V / krpm)	0

06 Protection Parameters

	Pr.	Parameter Name	Setting Range	Default
⌿	06-00	Low voltage level	230V models: Frame A–D: 150.0–220.0 V_{DC} Frame E and above : 190.0–220.0 V_{DC} 460V models: Frame A–D: 300.0–440.0 V_{DC} Frame E and above : 380.0–440.0 V_{DC} 575V models: 420.0–520.0 V_{DC} 690V models: 450.0–660.0 V_{DC}	180.0 200.0 360.0 400.0 470.0 480.0
⌿	06-01	Over-voltage stall prevention	0: Disabled 230V models: 0.0–450.0 V_{DC} 460V models: 0.0–900.0 V_{DC} 575V models: 0.0–1116.0 V_{DC} 690V models: 0.0–1318.0 V_{DC}	380.0 760.0 920.0 1087.0
⌿	06-02	Selection for stall prevention	0: Traditional over-voltage and traditional over-current stall prevention 1: Smart over-voltage and traditional over-current stall prevention 2: Traditional over-voltage and smart over-current stall prevention 3: Smart over-voltage and smart over-current stall prevention	0
⌿	06-03	Over-current stall prevention during acceleration	230V / 460V models Light duty: 0–130% (100% corresponds to the rated current of the drive) Normal duty: 0–160% (100% corresponds to the rated current of the drive) 575V / 690V models Light duty: 0–125% (100% corresponds to the rated current of the drive) Normal duty: 0–150% (100% corresponds to the rated current of the drive)	120 120 120 120
⌿	06-04	Over-current stall prevention during operation	230V / 460V models Light duty: 0–130% (100% corresponds to the rated current of the drive) Normal duty: 0–160% (100% corresponds to the rated current of the drive) 575V / 690V models Light duty: 0–125% (100% corresponds to the rated current of the drive) Normal duty: 0–150% (100% corresponds to the rated current of the drive)	120 120 120 120
⌿	06-05	Acceleration / deceleration time selection for stall prevention at constant speed	0: By current acceleration / deceleration time 1: By the first acceleration / deceleration time 2: By the second acceleration / deceleration time 3: By the third acceleration / deceleration time 4: By the fourth acceleration / deceleration time	0

	Pr.	Parameter Name	Setting Range	Default
			5: By auto-acceleration / auto-deceleration	
⌁	06-06	Over-torque detection selection (OT1)	0: No function 1: Continue operation after over-torque detection during constant speed operation 2: Stop after over-torque detection during constant speed operation 3: Continue operation after over-torque detection during RUN 4: Stop after over-torque detection during RUN	0
⌁	06-07	Over-torque detection level (OT1)	10–200% (100% corresponds to the drive's light-duty rated current)	120
⌁	06-08	Over-torque detection time (OT1)	0.0–60.0 sec.	0.1
⌁	06-09	Over-torque detection selection (OT2)	0: No function 1: Continue operation after over-torque detection during constant speed operation 2: Stop after over-torque detection during constant speed operation 3: Continue operation after over-torque detection during RUN 4: Stop after over-torque detection during RUN	0
⌁	06-10	Over-torque detection level (OT2)	10–200% (100% corresponds to the light-load rated current of the drive)	120
⌁	06-11	Over-torque detection time (OT2)	0.0–60.0 sec.	0.1
⌁	06-12	Current limit	0–200%	150
⌁	06-13	Electronic thermal relay selection 1 (Motor 1)	0: Inverter motor (with external forced cooling) 1: Standard motor (motor with fan on the shaft) 2: Disable	2
⌁	06-14	Electronic thermal relay action time 1 (Motor 1)	30.0–600.0 sec.	60.0
⌁	06-15	Temperature level overheat (OH) warning	0.0–110.0°C	105.0
⌁	06-16	Stall prevention limit level (Weak magnetic field current stall prevention level)	0–100% (Pr.06-03)	50
	06-17	Fault record 1	0: No fault record 1: Over-current during acceleration (ocA) 2: Over-current during deceleration (ocd) 3: Over-current during steady speed (ocn) 4: Ground fault (GFF) 5: IGBT short-circuit between upper bridge and lower bridge (occ) 6: Over-current at stop (ocS) 7: Over-voltage during acceleration (ovA) 8: Over-voltage during deceleration (ovd) 9: Over-voltage at constant speed (ovn) 10: Over-voltage at stop (ovS) 11: Low-voltage during acceleration (LvA) 12: Low-voltage during deceleration (Lvd)	0
	06-18	Fault record 2		0
	06-19	Fault record 3		0
	06-20	Fault record 4		0
	06-21	Fault record 5		0
	06-22	Fault record 6		0

Pr.	Parameter Name	Setting Range	Default
		13: Low-voltage at constant speed (Lvn) 14: Low-voltage at stop (LvS) 15: Phase loss protection (OrP) 16: IGBT overheating (oH1) 17: Heatsink overheating (oH2) 18: IGBT temperature detection failure (tH1o) 19: Capacitor hardware error (tH2o) 21: Over load (oL) 22: Electronic thermal relay 1 protection (EoL1) 23: Electronic thermal relay 2 protection (EoL2) 24: Motor overheating (oH3) (PTC / PT100) 26: Over torque 1 (ot1) 27: Over torque 2 (ot2) 28: Under current (uC) 30: EEPROM write error (cF1) 31: EEPROM read error (cF2) 33: U-phase error (cd1) 34: V-phase error (cd2) 35: W-phase error (cd3) 36: cc (current clamp) hardware error (Hd0) 37: oc (over-current) hardware error (Hd1) 38: ov (over-voltage) hardware error (Hd2) 39: occ hardware error (Hd3) 40: Auto-tuning error (AUE) 41: PID loss ACI (AFE) 48: ACI loss (ACE) 49: External fault (EF) 50: Emergency stop (EF1) 51: External base block (bb) 52: Enter wrong password three times and locked (Pcod) 53: Firmware version error (ccod) 54: Illegal command (CE1) 55: Illegal data address (CE2) 56: Illegal data value (CE3) 57: Data is written to read-only address (CE4) 58: Modbus transmission time-out (CE10) 60: Brake transistor error (bF) 61: Y-connection / Δ-connection switch error (ydc) 62: Deceleration energy backup error (dEb) 63: Over slip error (oSL) 64: Electric valve switch error (ryF) 68: Reverse direction of the speed feedback (SdRv) 69: Over speed rotation feedback (SdOr) 70: Large deviation of speed feedback (SdDe) 71: Watchdog (WDTT) 72: STO loss 1 (STL1) 73: Emergency stop for external safety (S1) 74: FIRE mode output (Fire)	

Pr.	Parameter Name	Setting Range	Default
		76: Safe torque off (STO) 77: STO loss 2 (STL2) 78: STO loss 3 (STL3) 82: Output phase loss U phase (OPHL) 83: Output phase loss V phase (OPHL) 84: Output phase loss W phase (OPHL) 89: Rotor position detection error (RoPd) 90: Forced to stop (FStp) 101: CANopen guarding error (CGdE) 102: CANopen heartbeat error (ChbE) 104: CANopen bus off error (CbFE) 105: CANopen index error (CidE) 106: CANopen station address error (CadE) 107: CANopen memory error (CfrE) 111: InrCOM time-out error (ictE) 142: Auto-tuning error 1 (no feedback current error) (AUE1) 143: Auto-tuning error 2 (motor phase loss error) (AUE2) 144: Auto-tuning error 3 (no-load current I_0 measuring error) (AUE3) 148: Auto-tuning error 4 (leakage inductance Lsigma measuring error) (AUE4)	
✎ 06-23	Fault output option 1	0–65535 (refer to bit table for fault code)	0
✎ 06-24	Fault output option 2		
✎ 06-25	Fault output option 3		
✎ 06-26	Fault output option 4		
✎ 06-27	Electronic thermal relay selection 2 (motor 2)	0: Inverter motor (with external forced cooling) 1: Standard motor (motor with fan on the shaft) 2: Disable	2
✎ 06-28	Electronic thermal relay action time 2 (motor 2)	30.0–600.0 sec.	60.0
✎ 06-29	PTC detection selection / PT100 motion	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning	0
✎ 06-30	PTC level	0.0–100.0%	50.0
06-31	Frequency command at malfunction	0.00–599.00 Hz	Read only
06-32	Output frequency at malfunction	0.00–599.00 Hz	Read only
06-33	Output voltage at malfunction	0.0–6553.5 V	Read only
06-34	DC bus voltage at malfunction	0.0–6553.5 V	Read only
06-35	Output current at malfunction	0.0–6553.5 Amp	Read only

	Pr.	Parameter Name	Setting Range	Default
	06-36	IGBT temperature at malfunction	-3276.7–3276.7°C	Read only
	06-37	Capacitance temperature at malfunction	-3276.7–3276.7°C	Read only
	06-38	Motor speed at malfunction	-32767–32767 rpm	Read only
	06-40	Status of the multi-function input terminal at malfunction	0000h–FFFFh	Read only
	06-41	Status of the multi-function output terminal at malfunction	0000h–FFFFh	Read only
	06-42	Drive status at malfunction	0000h–FFFFh	Read only
✓	06-44	STO latch selection	0: STO latch 1: STO no latch	0
✓	06-45	Output phase loss detection action (OPHL)	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning	3
✓	06-46	Detection time for output phase loss	0.000–65.535 sec.	0.500
✓	06-47	Current detection level for output phase loss	0.00–100.00%	1.00
✓	06-48	DC brake time for output phase loss	0.000–65.535 sec.	0.000
✓	06-49	LvX auto-reset	0: Disable 1: Enable	0
✓	06-50	Time for input phase loss detection	0.00–600.00 sec.	0.20
✓	06-52	Ripple of input phase loss	230V models: 0.0–100.0 V_{DC} 460V models: 0.0–200.0 V_{DC} 575V models: 0.0–400.0 V_{DC} 690V models: 0.0–480.0 V_{DC}	30.0 60.0 75.0 90.0
✓	06-53	Input phase loss detection action (OrP)	0: Fault and ramp to stop 1: Fault and coast to stop	0
✓	06-55	Derating protection	0: Auto-decrease carrier frequency and limit output current 1: Constant carrier frequency and limit output current 2: Auto-decrease carrier frequency	0
✓	06-56	PT100 voltage level 1	0.000–10.000 V	5.000
✓	06-57	PT100 voltage level 2	0.000–10.000 V	7.000
✓	06-58	PT100 level 1 frequency protection	0.00–599.00 Hz	0.00
✓	06-59	PT100 activation level 1 protection frequency delay time	0–6000 sec.	60
✓	06-60	Software detection GFF current level	0.0–6553.5% (100% corresponds to the light-duty rated current of the drive)	60.0
✓	06-61	Software detection GFF filter time	0.00–655.35 sec.	0.10

	Pr.	Parameter Name	Setting Range	Default
	06-63	Operation time of fault record 1 (Days)	0–65535 days	Read only
	06-64	Operation time of fault record 1 (Minutes)	0–1439 min.	Read only
	06-65	Operation time of fault record 2 (Days)	0–65535 days	Read only
	06-66	Operation time of fault record 2 (Minutes)	0–1439 min.	Read only
	06-67	Operation time of fault record 3 (Days)	0–65535 days	Read only
	06-68	Operation time of fault record 3 (Minutes)	0–1439 min.	Read only
	06-69	Operation time of fault record 4 (Days)	0–65535 days	Read only
	06-70	Operation time of fault record 4 (Minutes)	0–1439 min.	Read only
↯	06-71	Low current setting level	0.0–100.0% (100% corresponds to the light-duty rated current of the drive)	0.0
↯	06-72	Low current detection time	0.00–360.00 sec.	0.00
↯	06-73	Low current action	0: No function 1: Fault and coast to stop 2: Fault and ramp to stop by the second deceleration time 3: Warn and continue operation	0
↯	06-76	dEb motion offset	230V models: 0.0–200.0 V_{DC} 460V models: 0.0–200.0 V_{DC} 575V models: 0.0–200.0 V_{DC} 690V models: 0.0–200.0 V_{DC}	20.0 40.0 50.0 60.0
	06-80	Fire mode	0: Disable 1: Forward (counterclockwise) operation 2: Reverse (clockwise) operation	0
↯	06-81	Operating frequency when running fire mode	0.00–599.00 Hz	60.00
↯	06-82	Enable bypass on fire mode	0: Disable bypass 1: Enable bypass	0
↯	06-83	Bypass delay time on fire mode	0.0–6550.0 sec.	0.0
↯	06-84	Number of times of reset in fire mode	0–10	0
↯	06-85	Length of time of reset in fire mode	0.0–6000.0 sec.	60.0
	06-86	Fire mode motion	bit0: 0 = Open Loop; 1 = Close Loop (PID control) bit1: 0 = Manual reset fire mode; 1 = Auto reset fire mode 0: Open loop control and manual reset fire mode 1: Close loop control and manual reset fire mode 2: Open loop control and auto reset fire mode 3: Close loop control and auto reset fire mode	0
↯	06-87	Fire mode PID set point	0.00–100.00%	0.00

07 Special Parameters

	Pr.	Parameter Name	Setting Range	Default
✓	07-00	Software brake chopper action level	230V models: 350.0–450.0 V_{DC} 460V models: 700.0–900.0 V_{DC} 575V models: 850.0–1116.0 V_{DC} 690V models: 939.0–1318.0 V_{DC}	370.0 740.0 895.0 1057.0
✓	07-01	DC brake current level	0–100%	0
✓	07-02	DC brake time at start-up	0.0–60.0 sec.	0.0
✓	07-03	DC brake time at STOP	0.0–60.0 sec.	0.0
✓	07-04	DC brake frequency at STOP	0.00–599.00 Hz	0.00
✓	07-05	Voltage increasing gain	1–200%	100
✓	07-06	Restart after momentary power loss	0: Stop operation 1: Speed tracking by the speed before the power loss 2: Speed tracking by the minimum output frequency	0
✓	07-07	Allowed power loss duration	0.0–20.0 sec.	2.0
✓	07-08	Base block time	0.0–5.0 sec. (Depending on the model power)	Depending on the model power
✓	07-09	Current limit of speed tracking	20–200% (100% corresponds to the light-duty rated current of the drive)	100
✓	07-10	Restart after fault action	0: Stop operation 1: Speed tracking by current speed 2: Speed tracking by minimum output frequency	0
✓	07-11	Number of times of restart after fault	0–10	0
✓	07-12	Speed tracking during start-up	0: Disable 1: Speed tracking by the maximum output frequency 2: Speed tracking by the motor frequency at start-up 3: Speed tracking by the minimum output frequency	0
✓	07-13	dEb function selection	0: Disable 1: dEb with auto-acceleration / auto-deceleration, the drive does not output the frequency after the power is restored. 2: dEb with auto-acceleration / auto-deceleration, the drive outputs the frequency after the power is restored.	0
✓	07-15	Dwell time at acceleration	0.00–600.00 sec.	0.00
✓	07-16	Dwell frequency at acceleration	0.00–599.00 Hz	0.00
✓	07-17	Dwell time at deceleration	0.00–600.00 sec.	0.00
✓	07-18	Dwell frequency at deceleration	0.00–599.00 Hz	0.00
✓	07-19	Fan cooling control	0: Fan always ON 1: Fan is OFF after the AC motor drive stops for one minute 2: Fan is ON when the AC motor drive runs; fan is OFF when the AC motor drive stops	0

	Pr.	Parameter Name	Setting Range	Default
			3: Fan turns ON when temperature (IGBT) reaches around 60°C. 4: Fan always OFF	
⚡	07-20	Emergency stop (EF) & force to stop selection	0: Coast to stop 1: Stop by the first deceleration time 2: Stop by the second deceleration time 3: Stop by the third deceleration time 4: Stop by the fourth deceleration time 5: System deceleration 6: Automatic deceleration	0
⚡	07-21	Automatic energy-saving selection	0: Disable 1: Power factor energy-saving improvement 2: Automatic energy-saving optimization	0
⚡	07-22	Energy-saving gain	10–1000%	100
⚡	07-23	Automatic voltage regulation (AVR) function	0: Enable AVR 1: Disable AVR 2: Disable AVR during deceleration	0
⚡	07-24	Torque command filter time (V/F and SVC control mode)	0.001–10.000 sec.	0.500
⚡	07-25	Slip compensation filter time (V/F and SVC control mode)	0.001–10.000 sec.	0.100
⚡	07-26	Torque compensation gain	IM: 0–10 (when Pr.05-33 = 0) PM: 0–5000 (when Pr.05-33 = 1 or 2)	0
⚡	07-27	Slip compensation gain	0.00–10.00	0.00 (Default value is 1.00 in SVC mode)
⚡	07-29	Slip deviation level	0.0–100.0% 0：No detection	0.0
⚡	07-30	Over-slip deviation detection time	0.0–10.0 sec.	1.0
⚡	07-31	Over-slip deviation treatment	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning	0
⚡	07-32	Motor oscillation compensation factor	0–10000 0: Disable	1000
⚡	07-33	Auto-restart interval of fault	0.0–6000.0 sec.	60.0
⚡	07-38	PMSVC voltage feed forward gain	0.00–2.00	1.00
⚡	07-41	Minimum frequency for AES	0.00–40.00 Hz	10.00
	07-42	Delay time for AES	0–600 sec.	5
⚡	07-43	Targeted power factor angle for AES	0.00–65.00°	40.00
⚡	07-44	Maximum voltage drop for AES	0.00–70.00%	60.00
⚡	07-45	AES coefficient	0–10000%	100
⚡	07-50	PWM fan speed	60–100%	60

08 High-function PID Parameters

	Pr.	Parameter Name	Setting Range	Default
✓	08-00	Terminal selection of PID feedback	0: No function 1: Negative PID feedback: by analog input (Pr.03-00–03-02) 4: Positive PID feedback: by analog input (Pr.03-00–03-02)	0
✓	08-01	Proportional gain (P)	0.0–100.0	1.0
✓	08-02	Integral time (I)	0.00–100.00 sec. 0.00: No integral	1.00
✓	08-03	Differential time (D)	0.00–1.00 sec.	0.00
✓	08-04	Upper limit of integral control	0.0–100.0%	100.0
✓	08-05	PID output command limit	0.0–110.0%	100.0
✓	08-06	PID feedback value display	-200.00–200.00%	Read only
✓	08-07	Delay time	0.0–35.0 sec.	0.0
✓	08-08	Feedback signal detection time	0.0–3600.0 sec.	0.0
✓	08-09	Feedback signal fault treatment	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: Warn and operate at last frequency	0
✓	08-10	Sleep level	0.00–599.00 Hz or 0–200.00%	0.00
✓	08-11	Wake-up level	0.00–599.00 Hz or 0–200.00%	0.00
✓	08-12	Sleep delay time	0.0–6000.0 sec.	0.0
✓	08-13	PID feedback signal error deviation level	1.0–50.0%	10.0
✓	08-14	PID feedback signal error deviation detection time	0.1–300.0 sec.	5.0
✓	08-16	PID compensation selection	0: Parameter setting (Pr.08-17) 1: Analog input	0
✓	08-17	PID compensation	-100.0–100.0%	0.0
	08-18	Sleep mode function setting	0: Refer to PID output command 1: Refer to PID feedback signal	0
✓	08-19	Wake-up integral limit	0.0–200.0%	50.0
	08-20	PID mode selection	0: Serial connection 1: Parallel connection	0
	08-21	Enable PID to change the operation direction	0: Operation direction cannot be changed 1: Operation direction can be changed	0
✓	08-22	Wake-up delay time	0.00–600.00 sec.	0.00

09 Communication Parameters

	Pr.	Parameter Name	Setting Range	Default
ϟ	09-00	Communication address	1–254	1
ϟ	09-01	COM1 transmission speed	4.8–115.2 Kbps	9.6
ϟ	09-02	COM1 transmission fault treatment	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning, no fault and continue operation	3
ϟ	09-03	COM1 time-out detection	0.0–100.0 sec.	0.0
ϟ	09-04	COM1 communication protocol	1: 7, N, 2 (ASCII) 2: 7, E, 1 (ASCII) 3: 7, O, 1 (ASCII) 4: 7, E, 2 (ASCII) 5: 7, O, 2 (ASCII) 6: 8, N, 1 (ASCII) 7: 8, N, 2 (ASCII) 8: 8, E, 1 (ASCII) 9: 8, O, 1 (ASCII) 10: 8, E, 2 (ASCII) 11: 8, O, 2 (ASCII) 12: 8, N, 1 (RTU) 13: 8, N, 2 (RTU) 14: 8, E, 1 (RTU) 15: 8, O, 1 (RTU) 16: 8, E, 2 (RTU) 17: 8, O, 2 (RTU)	1
ϟ	09-09	Communication response delay time	0.0–200.0 ms	2.0
	09-10	Communication main frequency	0.00–599.00 Hz	60.00
ϟ	09-11	Block transfer 1	0000–FFFFh	0000h
ϟ	09-12	Block transfer 2	0000–FFFFh	0000h
ϟ	09-13	Block transfer 3	0000–FFFFh	0000h
ϟ	09-14	Block transfer 4	0000–FFFFh	0000h
ϟ	09-15	Block transfer 5	0000–FFFFh	0000h
ϟ	09-16	Block transfer 6	0000–FFFFh	0000h
ϟ	09-17	Block transfer 7	0000–FFFFh	0000h
ϟ	09-18	Block transfer 8	0000–FFFFh	0000h
ϟ	09-19	Block transfer 9	0000–FFFFh	0000h
ϟ	09-20	Block transfer 10	0000–FFFFh	0000h
ϟ	09-21	Block transfer 11	0000–FFFFh	0000h
ϟ	09-22	Block transfer 12	0000–FFFFh	0000h
ϟ	09-23	Block transfer 13	0000–FFFFh	0000h
ϟ	09-24	Block transfer 14	0000–FFFFh	0000h
ϟ	09-25	Block transfer 15	0000–FFFFh	0000h
ϟ	09-26	Block transfer 16	0000–FFFFh	0000h
	09-30	Communication decoding method	0: Decoding method 1 (20xx) 1: Decoding method 2 (60xx)	1

	Pr.	Parameter Name	Setting Range	Default
	09-31	Internal communication protocol	1: BACnet 0: Modbus 485 -1: Internal communication slave 1 -2: Internal communication slave 2 -3: Internal communication slave 3 -4: Internal communication slave 4 -5: Internal communication slave 5 -6: Internal communication slave 6 -7: Internal communication slave 7 -8: Internal communication slave 8 -10: Internal communication master -12: Internal PLC control	0
⌿	09-33	PLC command force to 0	bit0: Before PLC scans, set up PLC target frequency = 0	0
	09-35	PLC address	1–254	2
	09-36	CANopen slave address	0: Disable 1–127	0
	09-37	CANopen speed	0: 1 Mbps 1: 500 Kbps 2: 250 Kbps 3: 125 Kbps 4: 100 Kbps (Delta only) 5: 50 Kbps	0
	09-39	CANopen warning record	bit0: CANopen guarding time out bit1: CANopen heartbeat time out bit2: CANopen SYNC time out bit3: CANopen SDO time out bit4: CANopen SDO buffer overflow bit5: Can Bus off bit6: Error protocol of CANopen bit8: The setting values of CANopen indexes are fail bit9: The setting value of CANopen address is fail bit10: The checksum value of CANopen indexes is fail	Read only
	09-40	CANopen decoding method	0: Disable (Delta-defined decoding method) 1: Enable (CANopen standard DS402 protocol)	1
	09-41	CANopen communication status	0: Node reset state 1: Com reset state 2: Boot up state 3: Pre-operation state 4: Operation state 5: Stop state	Read only
	09-42	CANopen control status	0: Not ready for use state 1: Inhibit start state 2: Ready to switch on state 3: Switched on state	Read only

Pr.	Parameter Name	Setting Range	Default
		4: Enable operation state 7: Quick stop active state 13: Error reaction activation state 14: Error state	
09-45	CANopen master function	0: Disable 1: Enable	0
09-46	CANopen master address	0–127	100
09-49	CANopen extension setting	0: Update Index 604F and 6050 to Acceleration / Deceleration time 1 bit0 = 0: Enabled (default) bit0 = 1: Disabled 1: Distinguish the CANopen identity code by models or by series bit1 = 0: Distinguish the CANopen identify code by models bit1 = 1: Distinguish the CANopen identify code by series	0002h
09-50	BACnet MS / TP node address	0–127	10
09-51	BACnet baud rate	9.6–76.8 Kbps	38.4
09-52	BACnet Device index L	0–65535	10
09-53	BACnet Device index H	0–63	0
09-55	BACnet Max Address	0–127	127
09-56	BACnet password	0–65535	0
09-60	Communication card identifications	0: No communication card 1: DeviceNet slave 2: Profibus-DP slave 3: CANopen slave / master 4: Modbus –TCP Slave 5: EtherNet/IP Slave 6: EtherCAT 8: BACnet IP 12: PROFINET	Read only
09-61	Firmware version of communication card	Read only	Read only
09-62	Product code	Read only	Read only
09-63	Fault code	Read only	Read only
⌿ 09-70	Communication card address (for DeviceNet or PROFIBUS)	DeviceNet: 0–63 Profibus-DP: 1–125	1
⌿ 09-71	Communication card speed setting (for DeviceNet)	Standard DeviceNet: 0: 100 Kbps 1: 125 Kbps 2: 250 Kbps 3: 1 Mbps (Delta only) Non-standard DeviceNet: (Delta only) 0: 10 Kbps 1: 20 Kbps 2: 50 Kbps 3: 100 Kbps 4: 125 Kbps	2

	Pr.	Parameter Name	Setting Range	Default
			5: 250 Kbps 6: 500 Kbps 7: 800 Kbps 8: 1 Mbps	
✎	09-72	Additional settings for communication card speed (for DeviceNet)	0: Standard DeviceNet In this mode, the baud rate can only be 100 Kbps, 125 Kbps or 250 Kbps in standard DeviceNet speed 1: Non-standard DeviceNet In this mode, DeviceNet baud rate can be the same as that for CANopen (0–8).	0
✎	09-75	Communication card IP configuration (for Modbus TCP)	0: Static IP 1: Dynamic IP (DHCP)	0
✎	09-76	Communication card IP address 1 (for Modbus TCP)	0–65535	0
✎	09-77	Communication card IP address 2 (for Modbus TCP)	0–65535	0
✎	09-78	Communication card IP address 3 (for Modbus TCP)	0–65535	0
✎	09-79	Communication card IP address 4 (for Modbus TCP)	0–65535	0
✎	09-80	Communication card address mask 1 (for Modbus TCP)	0–65535	0
✎	09-81	Communication card address mask 2 (for Modbus TCP)	0–65535	0
✎	09-82	Communication card address mask 3 (for Modbus TCP)	0–65535	0
✎	09-83	Communication card address mask 4 (for Modbus TCP)	0–65535	0
✎	09-84	Communication card gateway address 1 (for Modbus TCP)	0–65535	0
✎	09-85	Communication card gateway address 2 (for Modbus TCP)	0–65535	0
✎	09-86	Communication card gateway address 3 (for Modbus TCP)	0–65535	0
✎	09-87	Communication card gateway address 4 (for Modbus TCP)	0–65535	0
✎	09-88	Communication card password (Low word) (for Modbus TCP)	0–99	0
✎	09-89	Communication card password (High word) (for Modbus TCP)	0–99	0
✎	09-90	Reset communication card (for Modbus TCP)	0: Disable 1: Reset to defaults	0
✎	09-91	Additional settings for the communication card (for Modbus TCP)	bit0: Enable IP filter bit1: Enable internet parameters (1 bit). When the IP address is set, this bit is enabled. After updating the parameters for the communication card, this bit	0

Pr.	Parameter Name	Setting Range	Default
		changes to disabled. bit2: Enable login password (1 bit). When you enter the login password, this bit is enabled. After updating the parameters for the communication card, this bit changes to disabled.	
09-92	Communication card status (for Modbus TCP)	bit0: Enable password When the communication card is set with password; this bit is enabled. When the password is cleared; this bit is disabled.	0

10 Sensorless Motor Control Parameters

	Pr.	Parameter Name	Setting Range	Default
ϟ	10-08	Treatment for speed observer feedback fault	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop	2
ϟ	10-09	Detection time of speed observer feedback fault	0.0–10.0 sec. 0: Disable	1.0
ϟ	10-10	Speed observer stall level	0–120% 0: No function	115
ϟ	10-11	Detection time of speed observer stall	0.0–2.0 sec.	0.1
ϟ	10-12	Speed observer stall action	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop	2
ϟ	10-13	Speed observer slip range	0–50% 0: No function	50
ϟ	10-14	Detection time of speed observer slip	0.0–10.0 sec.	0.5
ϟ	10-15	Speed observer stall and slip error action	0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop	2
ϟ	10-31	I/F mode, current command	0–150% of motor rated current	40
ϟ	10-32	PM FOC sensorless speed estimator bandwidth	0.00–600.00 Hz	5.00
ϟ	10-33	PM FOC sensorless speed estimator bandwidth (low speed) (applied to 230V / 460V models)	0.00–600.00 Hz	1.00
ϟ	10-34	PM sensorless speed estimator low-pass filter gain	0.00–655.35	1.00
ϟ	10-35	AMR (Kp) gain (applied to 230V / 460V models)	0.00–3.00	1.00
ϟ	10-36	AMR (Ki) gain (applied to 230V / 460V models)	0.00–3.00	1.00
ϟ	10-39	Frequency to switch from I/F mode to PM sensorless mode	0.00–599.00 Hz	20.00
ϟ	10-40	Frequency to switch from PM sensorless mode to I/F mode	0.00–599.00 Hz	20.00
ϟ	10-41	I/F mode, Id current low-pass filter time	0.0–6.0 sec.	0.2
ϟ	10-42	Initial angle detection pulse value	0.0–3.0	1.0
ϟ	10-49	Zero voltage time during start-up	0.000–60.000 sec.	0.000
ϟ	10-51	Injection frequency	0–1200 Hz	500
ϟ	10-52	Injection magnitude	0.0–200.0 V 230V models: 0.0–100.0 V 460V models: 0.0–200.0 V 575V models: 0.0–200.0 V	 15.0 30.0 30.0

	Pr.	Parameter Name	Setting Range	Default
			690V models: 0.0–200.0 V	30.0
ϟ	10-53	PM initial rotor position detection method	0: Disable 1: Using I/F current command (Pr.10-31) to attract the rotor to zero degrees 2: High frequency injection 3: Pulse injection	0
ϟ	10-54	Magnetic flux linkage estimate low-speed gain (applied to 230V / 460V models)	10–1000%	100
ϟ	10-55	Magnetic flux linkage estimate high-speed gain (applied to 230V / 460V models)	10–1000%	100
ϟ	10-56	Kp of phase-locked loop (applied to 230V / 460V models)	10–1000%	100
ϟ	10-57	Ki of phase-locked loop (applied to 230V / 460V models)	10–1000%	100
ϟ	10-58	Mutual inductance gain compensation (applied to 230V / 460V models)	0.00–655.35	1.00

11 Advanced Parameters (Applied to 230V / 460V models)

	Pr.	Parameter Name	Setting Range	Default
	11-00	System control	bit0: Auto-tuning for ASR and APR bit6: 0 Hz linear-cross bit7: Saving or not saving the frequency	0000h
	11-01	Per-unit of system inertia	1–65535 (256 = 1PU)	256
✓	11-02	ASR1 / ASR2 switch frequency	0.00–599.00 Hz	7.00
✓	11-03	ASR1 low-speed bandwidth	1–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)	10
✓	11-04	ASR2 high-speed bandwidth	1–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)	10
✓	11-05	Zero-speed bandwidth	1–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)	10
✓	11-06	ASR 1 gain	0–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)	10
✓	11-07	ASR 1 integral time	0.000–10.000 sec.	0.100
✓	11-08	ASR 2 gain	0–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)	10
✓	11-09	ASR 2 integral time	0.000–10.000 sec.	0.100
✓	11-10	ASR gain of zero speed	0–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)	10
✓	11-11	ASR1 integral time of zero speed	0.000–10.000 sec.	0.100
✓	11-12	Gain for ASR speed feed forward	0–200%	0
✓	11-13	PDFF gain value	0–200%	30
✓	11-14	ASR output low pass filter time	0.000–0.350 sec.	0.008
✓	11-15	Notch filter depth	0–20 dB	0
✓	11-16	Notch filter frequency	0.0–6000.0 Hz	0.0
✓	11-17	Forward motor torque limit Quadrant I	0–500%	500
✓	11-18	Forward regenerative torque limit Quadrant II	0–500%	500
✓	11-19	Reverse motor torque limit Quadrant III	0–500%	500
✓	11-20	Reverse regenerative torque limit Quadrant IV	0–500%	500
✓	11-21	Flux weakening curve for motor 1 gain value	0–200%	90
✓	11-22	Flux weakening curve for motor 2 gain value	0–200%	90
✓	11-23	Flux weakening area speed response	0–150%	65

12 PUMP Parameters

Pr.	Parameter Name	Setting Range	Default
12-00	Circulation Control	0: No operation 1: Fixed time circulation (by time) 2: Fixed quantity circulation 3: Fixed quantity control 4: Fixed time circulation + fixed quantity circulation 5: Fixed time circulation + fixed quantity control	0
12-01	Number of Motors to be connected	1–8	1
12-02	Operating time for each motor (minutes)	0–65500 min.	0
12-03	Delay time due to the acceleration (or the increment) at motor switching (seconds)	0.0–3600.0 sec.	1.0
12-04	Delay time due to the deceleration (or the decrement) at motor switching (seconds)	0.0–3600.0 sec.	1.0
⚡ 12-05	Delay time due to fixed quantity circulation at motor switching (seconds)	0.0–3600.0 sec.	10.0
⚡ 12-06	Frequency when switching motors at fixed quantity circulation (Hz)	0.00–599.00 Hz	60.0
12-07	Action when fixed 1uantity circulation breaks down	0: Turn off all output 1: Motors powered by mains electricity continues to operate	0
⚡ 12-08	Frequency for stopping auxiliary motor (Hz)	0.00–599.00 Hz	0.00
12-09	Fixed quantity circulation output delay	1.0–3600.0 sec.	1.0
12-10	Motor 1 operation record (min./sec.)	Read only	Read Only
12-11	Motor 1 operation record (hour)	Read only	Read Only
12-12	Motor 2 operation record (min./sec.)	Read only	Read Only
12-13	Motor 2 operation record (hour)	Read only	Read Only
12-14	Motor 3 operation record (min./sec.)	Read only	Read Only
12-15	Motor 3 operation record (hour)	Read only	Read Only
12-16	Motor 4 operation record (min./sec.)	Read only	Read Only
12-17	Motor 4 operation record (hour)	Read only	Read Only

Pr.	Parameter Name	Setting Range	Default
12-18	Motor 5 operation record (min./sec.)	Read only	Read Only
12-19	Motor 5 operation record (hour)	Read only	Read Only
12-20	Motor 6 operation record (min./sec.)	Read only	Read Only
12-21	Motor 6 operation record (hour)	Read only	Read Only
12-22	Motor 7 operation record (min./sec.)	Read only	Read Only
12-23	Motor 7 operation record (hour)	Read only	Read Only
12-24	Motor 8 operation record (min./sec.)	Read only	Read Only
12-25	Motor 8 operation record (hour)	Read only	Read Only
12-26	Clear motor’s operation time	0: No function 1: Clear operation time for motor 1 2: Clear operation time for motor 2 3: Clear operation time for motor 3 4: Clear operation time for motor 4 5: Clear operation time for motor 5 6: Clear operation time for motor 6 7: Clear operation time for motor 7 8: Clear operation time for motor 8 10: Clear operation time for all motors	0
12-27	Priority for circulated operation	0: Terminal order 1: Minimum operation time	0

13 Application Parameters by Industry

Pr.	Parameter Name	Setting Range	Default
13-00	Industry Parameters combination	0: Disable 1: User-defined Parameter 2: Compressor (IM) 3: Fan 4: Pump 10: Air Handling Unit, AHU	0
13-01 | 13-99	Industry Parameters 1–99	0.00–655.35	0.00

14 Extension Card Parameter

	Pr.	Parameter Name	Setting Range	Default
✓	14-00	Extension card Input terminal selection (AI10)	0: Disable 1: Frequency command 4: PID target value 5: PID feedback signal 6: Thermistor (PTC) input value 11: PT100 thermistor input value 13: PID compensation amount	0
✓	14-01	Extension card Input terminal selection (AI11)		0
✓	14-08	Analog input filter time (AI10)	0.00–20.00 sec.	0.01
✓	14-09	Analog input filter time (AI11)	0.00–20.00 sec.	0.01
	14-10	Analog input 4–20mA signal loss selection (AI10)	0: Disable 1: Continue operation at the last frequency 2: Decelerate to 0 Hz 3: Stop immediately and display ACE	0
	14-11	Analog input 4–20mA signal loss selection (AI11)		0
✓	14-12	Extension card output terminal selection (AO10)	0: Output frequency (Hz) 1: Frequency command (Hz) 2: Motor speed (Hz) 3: Output current (rms) 4: Output voltage 5: DC bus voltage 6: Power factor 7: Power 9: AVI1 proportional 10: ACI proportional 11: AVI2 proportional 20: CANopen analog output 21: RS-485 analog output 22: Communication card analog output 23: Constant voltage output	0
✓	14-13	Extension card output terminal selection (AO11)		0
✓	14-14	Analog output 1 gain output (AO10)	0.0–500.0%	100.0
✓	14-15	Analog output 1 gain output (AO11)	0.0–500.0%	100.0
✓	14-16	Analog output 1 in REV direction (AO10)	0: Absolute value of output voltage 1: Reverse output 0 V; Forward output 0–10 V 2: Reverse output 5–0 V; Forward output 5–10 V	0
✓	14-17	Analog output 1 in REV direction (AO11)		0
✓	14-18	Extension card input selection (AI10)	0: 0–10 V (AVI10) 1: 0–20 mA (ACI10)	0

	Pr.	Parameter Name	Setting Range	Default
			2: 4–20 mA (ACI10)	
✎	14-19	Extension card input selection (AI11)	0: 0–10 V (AVI11) 1: 0–20 mA (ACI11) 2: 4–20 mA (ACI11)	0
	14-20	AO10 DC output setting level	0.00–100.00%	0.00
	14-21	AO11 DC output setting level	0.00–100.00%	0.00
✎	14-22	AO10 filter output time	0.00–20.00 sec.	0.01
✎	14-23	AO11 filter output time	0.00–20.00 sec.	0.01
✎	14-36	AO10 output selection	0: 0–10 V 1: 0–20 mA 2: 4–20 mA	0
✎	14-37	AO11 output selection		0

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Chapter 12 Descriptions of Parameter Settings

12-1 Description of parameter settings

00 Drive Parameters

✎ You can set this parameter during operation.

00-00 AC Motor Drive Identity Code

Default: Read only

Settings Read Only

00-01 AC Motor Drive Rated Current Display

Default: Read only

Settings Read Only

🕮 Pr.00-00 displays the AC motor drive identity code. Using the following specification table to check if Pr.00-01 setting is the rated current of the AC motor drive. Pr.00-01 corresponds to the identity code of the AC motor drive (Pr.00-00).

🕮 The default is the rated current for light duty. Set Pr.00-16 = 1 to display the rated current for normal duty.

230V Models								
Frame	A					B		
Power (kW)	0.75	1.5	2.2	3.7	5.5	7.5	11	15
Power (HP)	1	2	3	5	7.5	10	15	20
Identity code	4	6	8	10	12	14	16	18
Rated current for light duty [A]	5	7.5	10	15	21	31	46	61
Rated current for normal duty [A]	3	5	8	11	17	25	33	49
Frame	C			D		E		
Power (kW)	18.5	22	30	37	45	55	75	90
Power (HP)	25	30	40	50	60	75	100	125
Identity code	20	22	24	26	28	30	32	34
Rated current for light duty [A]	75	90	105	146	180	215	276	322
Rated current for normal duty [A]	65	75	90	120	146	180	215	255

460V Models															
Frame	A							B			C			D0	
Power (kW)	0.75	1.5	2.2	3.7	4.0	5.5	7.5	11	15	18.5	22	30	37	45	55
Power (HP)	1	2	3	5	5	7.5	10	15	20	25	30	40	50	60	75
Identity code	5	7	9	11	93	13	15	17	19	21	23	25	27	29	31
Rated current for light load [A]	3	4.2	5.5	8.5	10.5	13	18	24	32	38	45	60	73	91	110
Rated current for normal load [A]	2.8	3.0	4.0	6.0	9.0	10.5	12	18	24	32	38	45	60	73	91

460V Models																
Frame	D		E		F		G				H					
Power (kW)	75	90	110	132	160	185	200	220	250	280	315	355	400	500	560	630
Power (HP)	100	125	150	175	215	250	270	300	340	375	425	475	530	675	750	850
Identity code	33	35	37	39	41	43	486	45	487	47	49	51	53	55	59	61
Rated current for light duty [A]	150	180	220	260	310	370	395	460	481	530	616	683	770	930	1094	1212
Rated current for normal duty [A]	110	150	180	220	260	310	310	370	395	460	550	616	683	866	930	1094

575V Models							
Frame	A			B			
Power (kW)	1.5	2.2	3.7	5.5	7.5	11	15
Power (HP)	2	3	5	7.5	10	15	20
Identity code	505	506	507	508	509	510	511
Rated current for light duty [A]	3	4.3	6.7	9.9	12.1	18.7	24.2
Rated current for normal duty [A]	2.5	3.6	5.5	8.2	10	15.5	20

690V Models										
Frame	C				D		E			
Power (kW)	18.5	22	30	37	45	55	75	90	110	132
Power (HP)	25	30	40	50	60	75	100	125	150	175
Identity code	612	613	614	615	616	617	618	619	620	621
Rated current for light duty [A]	24	30	36	45	54	67	86	104	125	150
Rated current for normal duty [A]	20	24	30	36	45	54	67	86	104	125

Frame	F		G		H			
kW	160	200	250	315	400	450	560	630
HP	215	270	335	425	530	600	750	850
Identity code	622	686	687	626	628	629	631	632
Rated current for light duty [A]	180	220	290	350	430	465	590	675
Rated current for normal duty [A]	150	180	220	290	350	385	465	675

00-02 Parameter Reset

Default: 0

Settings 0: No Function

1: Write protection for parameters

5: Return kWh displays to 0

6: Reset PLC (including CANopen Master Index)

7: Reset CANopen Slave Index

9: Reset all parameters to defaults (base frequency at 50 Hz)

10: Reset all parameters to defaults (base frequency at 60 Hz)

- 1: All parameters are read only except Pr.00-02, Pr.00-07 and Pr.00-08. Set Pr.00-02 to 0 before changing other parameter settings.
- 5: You can return the kWh displayed value to 0 even during drive is operation. For example, you can set Pr.05-26–Pr.05-30 to 0.
- 6: Clear the internal PLC program (includes the related settings of PLC internal CANopen master)
- 7: Reset the related settings of CANopen slave.
- 9 or 10: Reset all parameters to defaults. If you have set a password (Pr.00-08), unlock the password (Pr.00-07) to clear the password you have set before you reset all parameters.
- For settings of 6, 7, 9 and 10, you must reboot the motor drive after you finish the setting.

✎ 00-03 Start-up Display

Default: 0

Settings 0: F (Frequency command)
1: H (Output frequency)
2: U (User-defined, see Pr.00-04)
3: A (Output current)

- Determines the start-up display page after power is applied to the drive. The user-defined contents display according to the Pr.00-04 settings.

✎ 00-04 Content of Multi-function Display

Default: 3

Settings 0: Display output current (A) (Unit: Amp)
1: Display counter value (c) (Unit: CNT)
2: Display the motor's actual output frequency (H) (Unit: Hz)
3: Display the drive's DC bus voltage (v) (Unit: V_{DC})
4: Display the drive's output voltage (E) (Unit: V_{AC})
5: Display the drive's output power angle (n) (Unit: deg)
6: Display the drive's output power in kW (P) (Unit: kW)
7: Display the motor speed rpm (Unit: rpm)
10: Display PID feedback (b) (Unit: %)
11: Display AVI1 analog input terminal signal (1.) (Unit: %)
12: Display ACI analog input terminal signal (2.) (Unit: %)
13: Display AVI2 analog input terminal signal (3.) (Unit: %)
14: Display the drive's IGBT temperature (i.) (Unit: °C)
15: Display the drive's capacitance temperature (c.) (Unit: °C)
16: The digital input status (ON/OFF) (i)
17: The digital output status (ON/OFF) (o)
18: Display multi-step speed (S)
19: The corresponding CPU digital input pin status (d)
20: The corresponding CPU digital output pin status (0.)
26: Ground Fault GFF (G.) (Unit: %)
27: DC bus voltage ripple (r.) (Unit: V_{DC})

28: Display PLC register D1043 data (C)
30: Display the output of User-defined (U)
31: Display Pr.00-05 user Gain (K)
34: Operation speed of fan (F.) (Unit: %)
36: Present operating carrier frequency of the drive (J.) (Unit: Hz)
38: Display the drive status (6.)
41: kWh display (J) (Unit: kWh)
42: PID target value (h) (Unit: %)
43: PID compensation (o.) (Unit: %)
44: PID output frequency (b.) (Unit: Hz)
45: Hardware ID
51: PMSVC torque offset
52: AI10%
53: AI11%
68: STO version (d)
69: STO checksum-high word (d)
70: STO checksum-low word (d)

- Explanation 1
- It can display negative values when setting analog input bias (Pr.03-03–03-10).

  Example: Assume that AVI1 input voltage is 0 V, Pr.03-03 is 10.0% and Pr.03-07 is 4 (Bias serves as the center).

  Explanation 2

  Example: If REV, MI1 and MI6 are ON, the following table shows the status of the terminals.

  Normally opened contact (N.O.), 0: OFF, 1: ON

Terminal	MI15	MI14	MI13	MI12	MI11	MI10	MI8	MI7	MI6	MI5	MI4	MI3	MI2	MI1	REV	FWD
Status	0	0	0	0	0	0	0	0	1	0	0	0	0	1	1	0

NOTE MI10–MI15 are the terminals for extension cards (Pr.02-26–02-31).

- The value is 0000 0000 1000 0110 in binary and 0086h in HEX. When Pr.00-04 is set to 16 or 19, the u page on the keypad displays “0086h”.
- The setting value 16 is ON / OFF status of digital input according to Pr.02-12 setting, and the setting value 19 is the corresponding CPU pin ON / OFF status of the digital input.
- You can set 16 to monitor the digital input ON / OFF status, and then set 19 to check if the circuit is normal.

Explanation 3

Assume that RY1: Pr.02-13 is set to 9 (Drive is ready). After the drive is powered on, if there is no other abnormal status, the contact is ON. The display status is shown as below.

Normally opened contact (N.O.):

Terminal	MO20	MO19	MO18	MO17	MO16	MO15	MO14	MO13	MO12	MO11	MO10	Reserved	Reserved	RY3	RY2	RY1
Status	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1

- If Pr.00-04 is set to 17 or 20, it displays in hexadecimal “0001h” with LED u page is ON in the keypad.

- The setting value 17 is ON / OFF status of digital output according to Pr.02-18 setting, and the setting value 20 is the corresponding CPU pin ON / OFF status of the digital output.
- You can set 17 to monitor the digital output ON / OFF status, and then set 20 to check if the circuit is normal.

Explanation 4

Setting value 25: when displayed value reaches 100.00%, the drive shows “oL” as an overload warning.

Explanation 5

Setting value 38:

bit 0: The drive is running forward.
bit 1: The drive is running backward.
bit 2: The drive is ready.
bit 3: Errors occurred on the drive.
bit 4: The drive is running.
bit 5: Warnings occurred on the drive.

✓ 00-05 Coefficient Gain in Actual Output Frequency

Default: 1.00

Settings 0.00–160.00

📖 Sets the user-defined unit coefficient gain. Set Pr.00-04 = 31 to display the calculation result on the screen (calculation = output frequency × Pr.00-05).

00-06 Firmware Version

Default: Read only

Settings Read only

✓ 00-07 Parameter Protection Password Input

Default: 0

Settings 0–65535
Display 0–4 (the number of password attempts allowed)

📖 This parameter allows you to enter your password (which is set in Pr.00-08) to unlock the parameter protection and to make changes to the parameter.

📖 To avoid problems in the future, be sure to write down the password after you set this parameter.

📖 Pr.00-07 and Pr.00-08 are used to prevent personnel from setting other parameters by accident.

📖 If you forget the password, clear the password setting by input 9999 and press the ENTER key, then enter 9999 again and press ENTER within 10 seconds. After decoding, all the settings return to default.

📖 When setting is under password protection, all the parameters read 0, except Pr.00-08.

✓ 00-08 Parameter Protection Password Setting

Default: 0

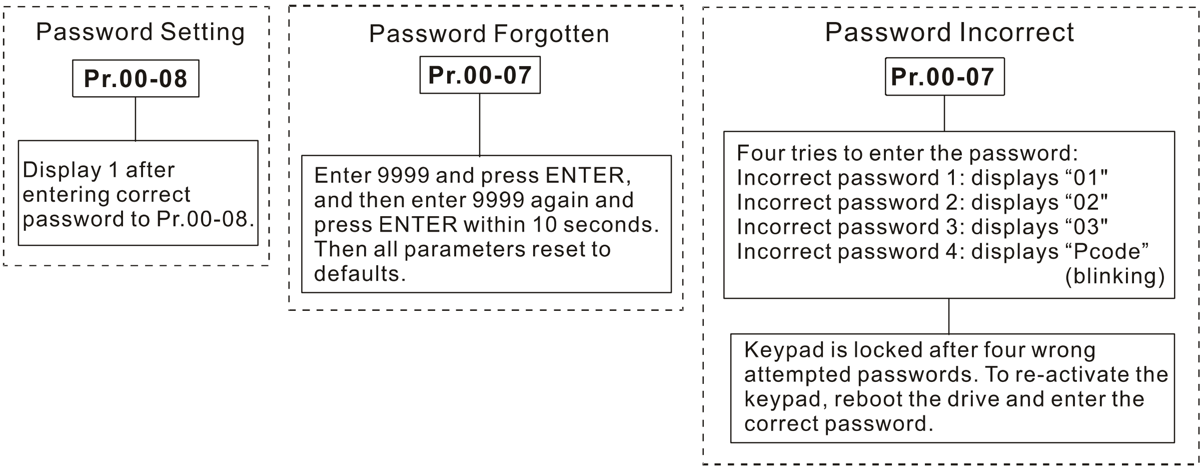
Settings 0–65535
0: No password protection or password entered correctly (Pr.00-07)
1: Password has been set

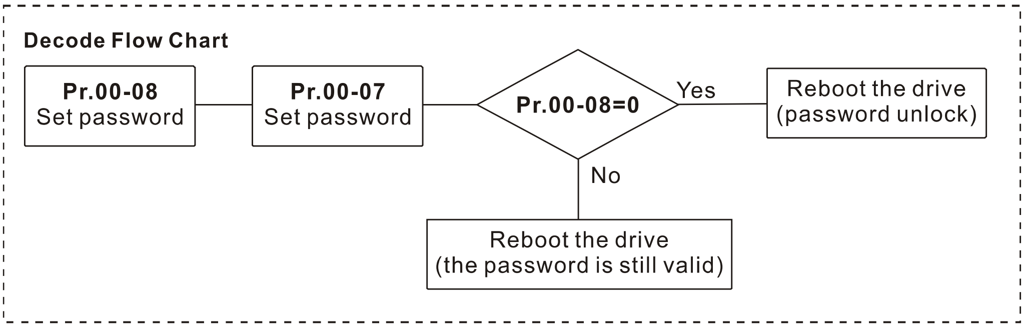
📖 This parameter sets the password protection. Password can be set directly the first time. After you set the password, the value of Pr.00-08 is 1, which means password protection is activated. At this time, if you want to change any of the parameter settings, you must enter the correct password in Pr.00-07 to deactivate the password temporarily, and this would make Pr.00-08 become 0. After you finish setting the parameters, reboot the motor drive and the password is activated again.

🕮 Entering the correct password in Pr.00-07 only temporarily deactivates the password. To permanently deactivate password protection, set Pr.00-08 to 0 manually. Otherwise, password protection is always reactivated after you reboot the motor drive.

🕮 The keypad copy function works only when the password protection is deactivated (temporarily or permanently), and password set in Pr.00-08 cannot be copied to the keypad. So when copying parameters from the keypad to the motor drive, set the password manually again in the motor drive to activate password protection.

- Password Decode Flow Chart


Password Setting
Pr.00-08
Display 1 after entering correct password to Pr.00-08.
Password Forgotten
Pr.00-07
Enter 9999 and press ENTER, and then enter 9999 again and press ENTER within 10 seconds. Then all parameters reset to defaults.
Password Incorrect
Pr.00-07
Four tries to enter the password:
Incorrect password 1: displays "01"
Incorrect password 2: displays "02"
Incorrect password 3: displays "03"
Incorrect password 4: displays "Pcode" (blinking)
Keypad is locked after four wrong attempted passwords. To re-activate the keypad, reboot the drive and enter the correct password.


Decode Flow Chart
Pr.00-08 Set password
Pr.00-07 Set password
Pr.00-08=0
Yes
Reboot the drive (password unlock)
No
Reboot the drive (the password is still valid)

00-11 Speed Control Mode

Default: 0

Settings 0: IMVF (IM V/F control)
2: IM / PM SVC (IM / PM space vector control)
6: PM Sensorless (PM FOC sensorless) (applied to 230V / 460V models)
8: SynRM Sensorless Control (applied to 230V / 460V models)

🕮 Determines the control method of the AC motor drive:

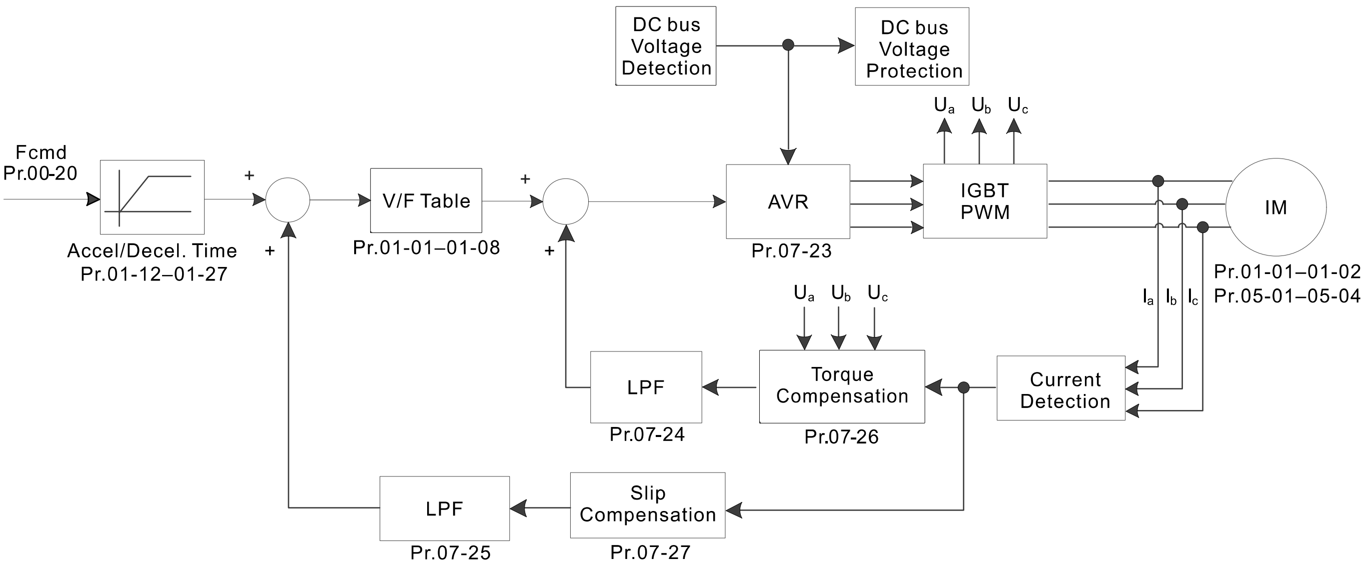
0: IM V/F control, you can set the proportion of V/F as required and control multiple motors simultaneously.

2: IM / PM space vector control, gets the optimal control by auto-tuning the motor parameters.

6: PM FOC sensorless, PM filed oriented sensorless vector control

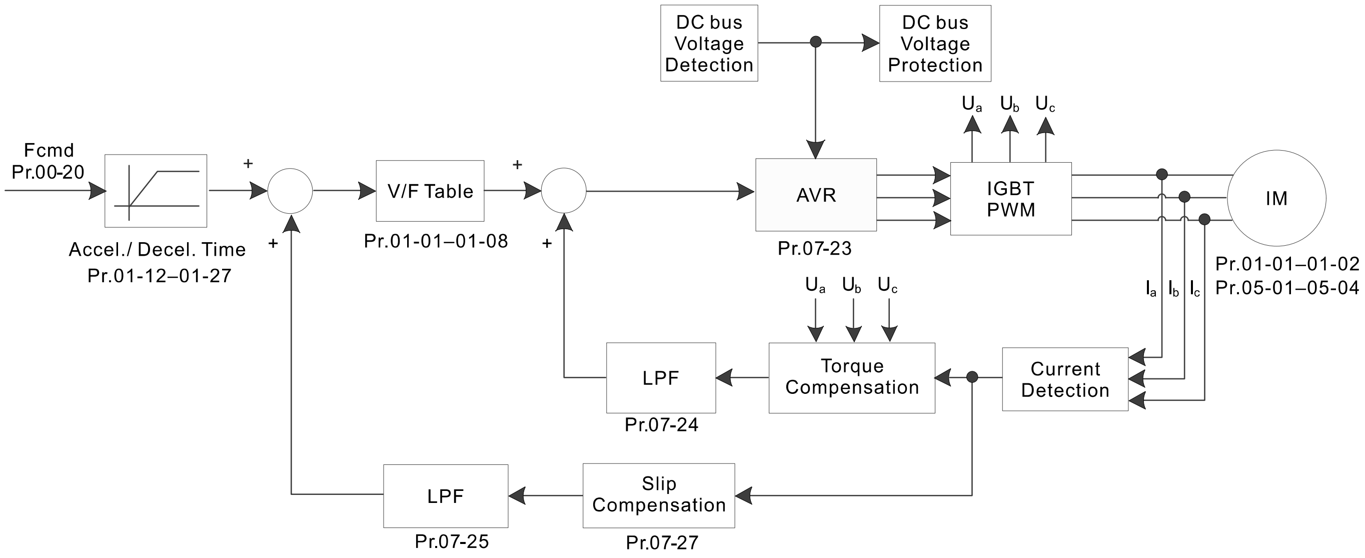
8: SynRM Sensorless, SynRM filed oriented sensorless vector control

📖 When you set Pr.00-11 to 0, the V/F control diagram is as follows:

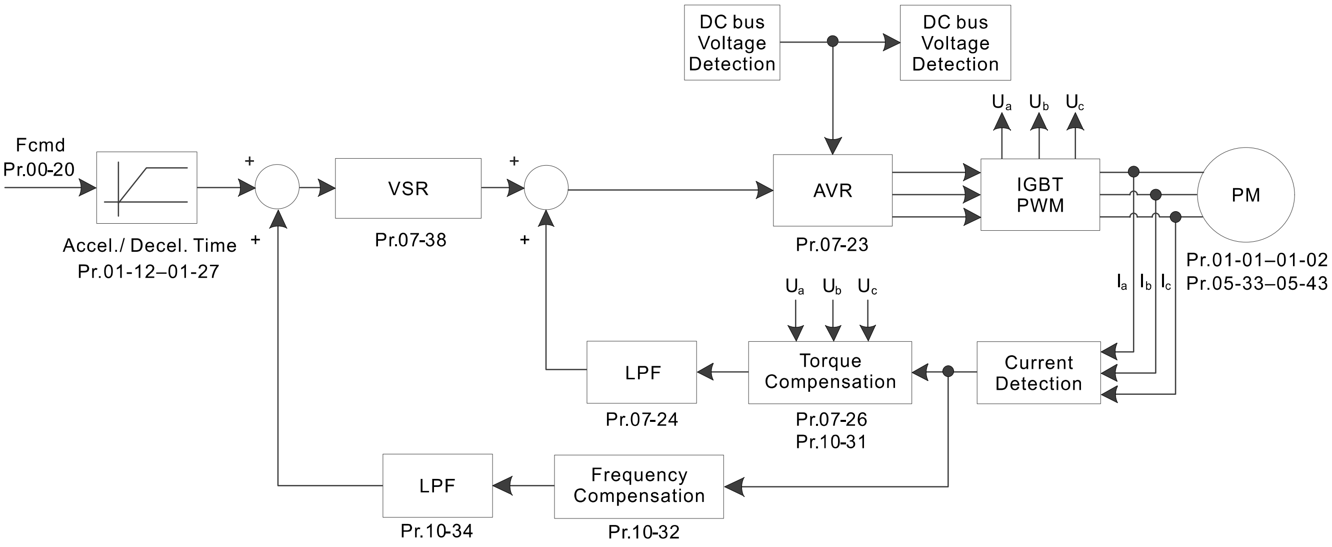


📖 When you set Pr.00-11 to 2, the space vector control diagram is as follows.

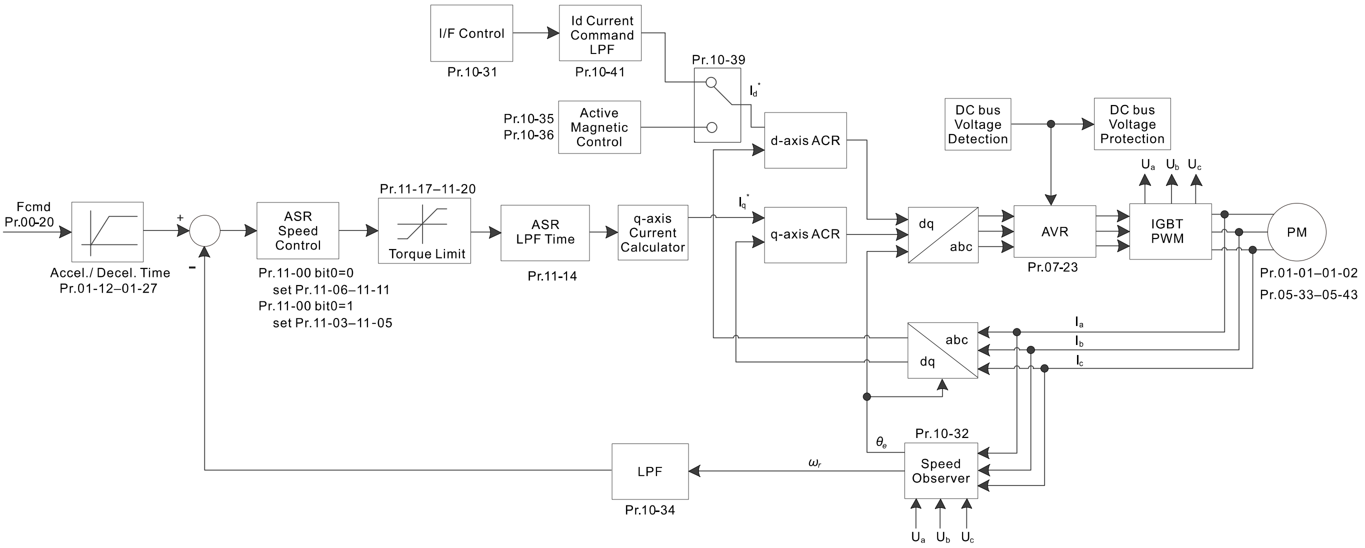
Induction Motor Space Vector Control (IMSVC)



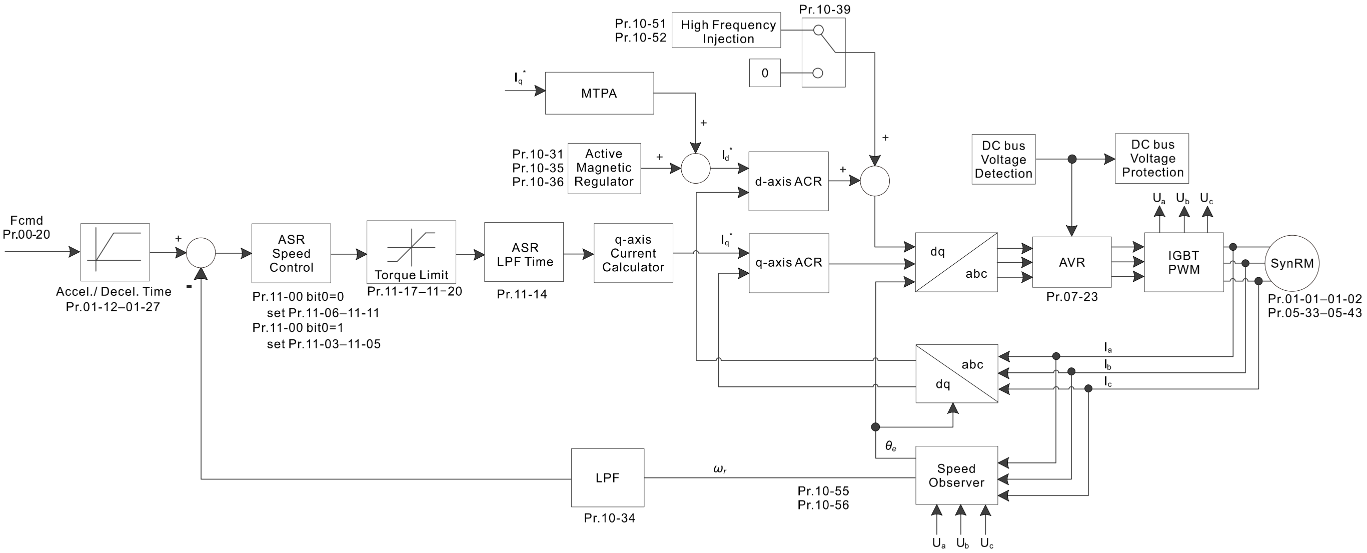
Permanent Magnetic Motor Space Vector Control (PMSVC)



📖 When you set Pr.00-11 to 6, PM FOC Sensorless control diagram is as follows:



📖 When you set Pr.00-11 to 8, SynRM Sensorless control diagram is as follows:



00-16 Load Selection

Default: 0

Settings 0: Light duty

1: Normal duty

📖 Light load (230V / 460V models): over-load ability is 120% rated output current in 60 seconds. Refer to Pr.00-17 for the setting of carrier frequency. Refer to Chapter 09 Specifications or Pr.00-01 for the rated current.

📖 Normal load (230V / 460V models): over-load ability is 120% rated output current in 60 seconds (160% rated output current in 3 seconds). Refer to Pr.00-17 for the setting of carrier frequency. Refer to Chapter 09 Specifications or Pr.00-01 for the rated current.

📖 Pr.00-01 varies with the setting value for Pr.00-16. The default value and maximum setting value for Pr.06-03 and Pr.06-04 also vary with the setting value for Pr.00-16.

00-17 Carrier Frequency

Default: Table below

Settings 2–15 kHz

This parameter determinates the PWM carrier frequency for the AC motor drive.

When you set Pr.00-11 = 8 (SynRM Sensorless control), the maximum setting value of carrier frequency is 8 kHz.

- 230V / 460V models:

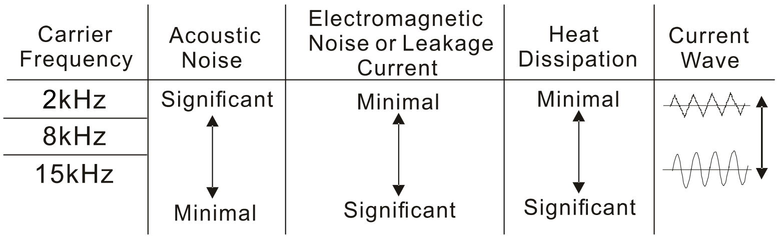
Light duty						
Control mode / Model	VF, SVC		PMFOC		SRMFOC	
	Settings	Default	Settings	Default	Settings	Default
VFD007–150CP23A/E VFD007–185CP43A/E	2–15 kHz	8 kHz	4–10 kHz	8 kHz	4–8 kHz	4 kHz
VFD185–450CP23A/E VFD220–750CP43A/E	2–10 kHz	6 kHz	4–10 kHz	6 kHz	4–8 kHz	4 kHz
VFD550–1100CP23A/E VFD900–6300CP43A/E	2–9 kHz	4 kHz	4–9 kHz	4 kHz	4–8 kHz	4 kHz

Normal duty						
Control mode / Model	VF, SVC		PMFOC		SRMFOC	
	Settings	Default	Settings	Default	Settings	Default
VFD007–150CP23A/E VFD007–185CP43A/E	2–15 kHz	8 kHz	4–10 kHz	8 kHz	4–8 kHz	4 kHz
VFD185–450CP23A/E VFD220–750CP43A/E	2–10 kHz	6 kHz	4–10 kHz	6 kHz	4–8 kHz	4 kHz
VFD550–1100CP23A/E VFD900–6300CP43A/E	2–9 kHz	4 kHz	4–9 kHz	4 kHz	4–8 kHz	4 kHz

- 575V / 690V models:

	Light duty		Normal duty	
Control mode / Model	VF, SVC		VF, SVC	
	Settings	Default	Settings	Default
VFD015–150CP53A	2–9 kHz	4 kHz	2–9 kHz	4 kHz
VFD185–5600CP63A	2–9 kHz	4 kHz	2–9 kHz	4 kHz
VFD6300CP63A	2–9 kHz	3 kHz	2–9 kHz	3 kHz*1

*1. Light duty / Normal duty: the default for 690V, 630 kW [850 HP] model is 3 kHz in VF / SVC mode.



From the table, you see that the PWM carrier frequency has significant influences on the electromagnetic noise, the AC motor drive heat dissipation, and the motor acoustic noise.

Therefore, if the surrounding noise is greater than the motor noise, lower the carrier frequency to reduce the temperature rise. Although the motor has quiet operation in the higher carrier frequency, consider the entire wiring and interference.

- When the carrier frequency is higher than the default, decrease the carrier frequency to protect the drive. Refer to Pr.06-55 for the related setting and details.

00-19 PLC Command Mask

Default: Read Only

Settings bit0: Control command is forced by PLC control
bit1: Frequency command is forced by PLC control

- Determines if the frequency command or control command is locked by PLC

00-20 Master Frequency Command Source (AUTO) / Source Selection of the PID Target

Default: 0

Settings 0: Digital keypad
1: RS-485 communication input
2: External analog input (Refer to Pr.03-00–Pr.03-02)
3: External UP/DOWN terminal (multi-function input terminals)
6: CANopen communication card
8: Communication card (does not include CANopen card)

- Set the master frequency source in AUTO mode.
- Pr.00-20 and Pr.00-21 are for settings the frequency source and operation source in AUTO mode. Pr.00-30 and Pr.00-31 are for settings the frequency source and operation source in HAND mode. You can switch the AUTO/HAND mode with the keypad KPC-CC01 or the multi-function input terminal (MI).
- The default for the frequency source or operation source is AUTO mode. It returns to AUTO mode whenever you cycle the power. If you use a multi-function input terminal to switch between AUTO and HAND mode, the highest priority is the multi-function input terminal. When the external terminal is OFF, the drive does not accept any operation signal and cannot execute JOG.

00-21 Operation Command (AUTO) Source

Default: 0

Settings 0: Digital keypad
1: External terminals
2: RS-485 communication input
3: CANopen communication card
5: Communication card (does not include CANopen card)

- Determines the operation frequency source in the AUTO mode.
- When you control the operation command by the keypad KPC-CC01, keys RUN, STOP and JOG (F1) are valid.

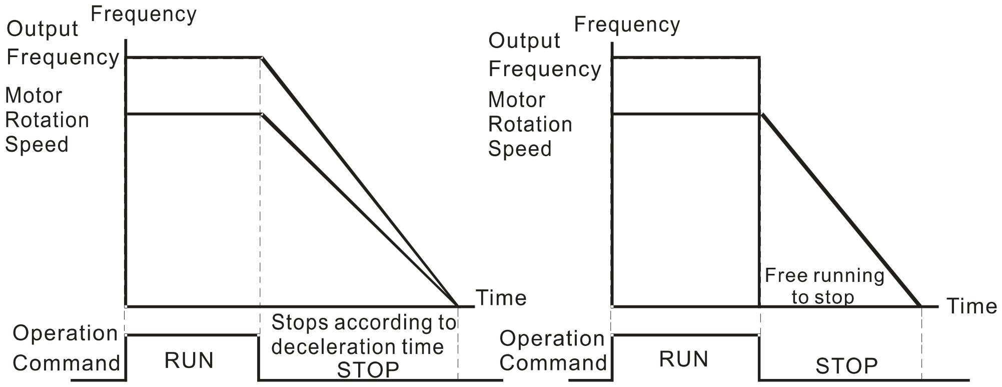
00-22 Stop Method

Default: 0

Settings 0: Ramp to stop

1: Coast to stop

Determines how the motor is stopped when the drive receives the STOP command.



Ramp to Stop and Coast to Stop

1. **Ramp to stop:** the AC motor drive decelerates to 0 or the minimum output frequency (Pr.01-07) according to the set deceleration time, and then to stop.
2. **Coast to stop:** the AC motor drive stops output immediately, and the motor coasts to stop according to the load inertia.
   - Use “ramp to stop” for the safety of personnel, or to prevent material from being wasted in applications where the motor must stop immediately after the drive stops. You must set the deceleration time accordingly.
   - If idling is allowed, or the load inertia is large, use “coast to stop”. For example, blowers, punching machines and pumps

00-23 Motor Direction Control

Default: 0

Settings 0: Enable forward / reverse

1: Disable reverse

2: Disable forward

Enables the motor to run in the forward and reverse direction. You can use it to prevent a motor from running in a direction that would cause injure or damage to the equipment, especially when only on running direction is allowed for the motor load.

00-24 Digital Operator (Keypad) Frequency Command Memory

Default: Read only

Settings Read only

If the keypad is the frequency command source, when Lv or Fault occurs, this parameter stores the current frequency command.

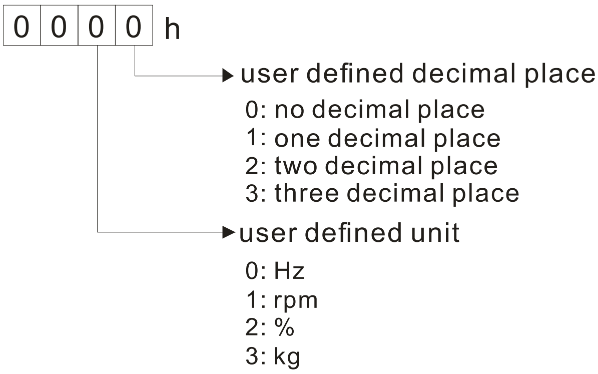
00-25 User-Defined Characteristics

Default: 0

Settings
- bit0–3: user-defined decimal place
  - 0000b: no decimal place
  - 0001b: one decimal place
  - 0010b: two decimal places
  - 0011b: three decimal places
- bit4–15: user-defined unit
  - 000xh: Hz
  - 001xh: rpm
  - 002xh: %
  - 003xh: kg
  - 004xh: m/s
  - 005xh: kW
  - 006xh: HP
  - 007xh: ppm
  - 008xh: 1/m
  - 009xh: kg/s
  - 00Axh: kg/m
  - 00Bxh: kg/h
  - 00Cxh: lb/s
  - 00Dxh: lb/m
  - 00Exh: lb/h
  - 00Fxh: ft/s
  - 010xh: ft/m
  - 011xh: m
  - 012xh: ft
  - 013xh: degC
  - 014xh: degF
  - 015xh: mbar
  - 016xh: bar
  - 017xh: Pa
  - 019xh: mWG
  - 01Axh: inWG
  - 01Bxh: ftWG
  - 01Cxh: psi
  - 01Cxh: psi
  - 01Dxh: atm
  - 01Exh: L/s
  - 01Fxh: L/m
  - 020xh: L/h

021xh: m3/s
022xh: m3/h
023xh: GPM
024xh: CFM
xxxxh: Hz

- bit0–3: the displayed units for the control frequency F page and user-defined (Pr.00-04 = d10, PID feedback) and the displayed number of decimal places for Pr.00-26 (supports up to three decimal places).
- bit4–15: the displayed units for the control frequency F page, user-defined (Pr.00-04 = d10, PID feedback) and Pr.00-26.



- You must convert the setting value to decimal when using the keypad to set parameters.

Example: Assume that the user-defined unit is inWG and user-defined decimal place is the third decimal point. According to the information above, the corresponding unit to inWG is 01Axh (x is the set decimal point), and the corresponding unit to the third decimal place is 0003h, then inWG and the third decimal point displayed in hexadecimal is 01A3h, that is 419 in decimal value. Thus, set Pr.00-25 = 419 to complete the setting.

00-26 Maximum User-Defined Value

Default: 0

Settings 0: Disable
0–65535 (when Pr.00-25 is set to no decimal place)
0.0–6553.5 (when Pr.00-25 is set to one decimal place)
0.00–655.35 (when Pr.00-25 is set to two decimal places)
0.000–65.535 (when Pr.00-25 is set to three decimal places)

- When Pr.00-26 is NOT set to 0, the user-defined value is enabled. After selecting the displayed unit and number of decimal places with Pr.00-25, the setting value of Pr.00-26 corresponds to Pr.01-00 (drive's maximum operating frequency).

Example: When the frequency set in Pr.01-00 = 60.00 Hz, the maximum user-defined value for Pr.00-26 is 100.0%. This also means that Pr.00-25 is set as 0021h.

NOTE Set Pr.00-25 before using Pr.00-26. After you finish setting, when Pr.00-26 is not 0, the displayed unit on the keypad shows correctly according to Pr.00-25 settings.

00-27 User-Defined Value

Default: Read only

Settings Read only

- Pr.00-27 displays the user-defined value when Pr.00-26 is not set to 0.
- The user-defined value is valid only when Pr.00-20 (frequency source) is set to the digital keypad or to RS-485 communication.

✎ 00-28 Switching from AUTO Mode to HAND Mode

Default: 0

Settings
- bit0: Sleep function control bit
  - 0: Cancel sleep function
  - 1: Sleep function and AUTO mode are the same
- bit1: Control bit unit
  - 0: Displaying unit in Hz
  - 1: Same unit as the AUTO mode
- bit2: PID control bit
  - 0: Cancel PID control
  - 1: PID control and AUTO mode are the same.
- bit3: Frequency source control bit
  - 0: Frequency source set up by parameter, if the multi-step speed is activated, then multi-step speed has the priority.
  - 1: Frequency command set up by Pr.00-30, regardless of whether the multi-step speed is activated.

00-29 LOCAL / REMOTE Selection

Default: 0

Settings
- 0: Standard HOA function
- 1: When switching between local and remote, the drive stops
- 2: When switching between local and remote, the drive runs with REMOTE settings for frequency and operating status
- 3: When switching between local and remote, the drive runs with LOCAL setting for frequency and operating status
- 4: When switching between local and remote, the drive runs with LOCAL settings when switched to Local and runs with REMOTE settings when switched to Remote for frequency and operation status.

- The default for Pr.00-29 is 0, that is, the standard HOA (Hand-Off-Auto) function. Set the AUTO and HAND frequency and operation source with Pr.00-20, Pr.00-21 and Pr.00-30, Pr.00-31. Use digital keypad (KPC-CC01) or multi-function input terminal to set MIx = 41 and 42 (AUTO / HAND mode).
- When you set the external terminal (MI) to 41 and 42 (AUTO / HAND mode), Pr.00-29 = 1, 2, 3, 4 are disabled. The external terminal has the highest command priority, and Pr.00-29 functions in standard HOA mode.

- If Pr.00-29 is not set to 0, the Local / Remote function is enabled, and the top right corner of digital keypad (firmware version 1.021 and above) displays “LOC” or “REM”. Set the REMOTE frequency and operation source with Pr.00-20 and Pr.00-21. Set the LOCAL frequency and operation source with Pr.00-30 and Pr.00-31. Select or switch Local / Remote mode with the digital keypad or set the multi-function input terminal MIx = 56. The AUTO key of the digital keypad is for the REMOTE function, and HAND key is for the LOCAL function.
- When you set the external terminal (MI) to 56 for LOC / REM mode selection, if you set Pr.00-29 to 0, then the external terminal function is disabled.
- When you set the external terminal (MI) to 56 for LOC / REM mode selection, if Pr.00-29 is not set to 0, then AUTO / HAND key is disabled, and the external terminal has the highest command priority.
- The comparison between the setting of each mode and the PLC address:

PLC address / Mode	HOA mode		LOC / REM mode		HOA mode
	HAND-ON	AUTO-ON	LOC-ON	REM-ON	OFF
M1090 =	0	0	0	0	1
M1091 =	1	0	0	0	0
M1092 =	0	1	0	0	0
M1100 =	0	0	1	0	0
M1101 =	0	0	0	1	0

00-30 Master Frequency Command Source (HAND)

Default: 0

Settings 0: Digital keypad
1: RS-485 communication input
2: External analog input (refer to Pr.03-00–Pr.03-02)
3: External UP/DOWN terminal
6: CANopen communication card
8: Communication card (does not include CANopen card)

- Determines the master frequency source in HAND mode.

00-31 Operation Command Source (HAND)

Default: 0

Settings 0: Digital keypad
1: External terminals
2: RS-485 serial communication input
3: CANopen communication card
5: Communication card (does not include CANopen card)

- Sets the operation frequency source in HAND mode.
- Use Pr.00-20 and Pr.00-21 to set the frequency source and the operation source in AUTO mode, and use Pr.00-30 and Pr.00-31 to set the frequency source and operation source in HAND mode. Select or switch AUTO / HAND mode by using the digital keypad KPC-CC01 or setting the multi-function input terminal (MI).
- The default for the frequency source or operation source is AUTO mode. It returns to AUTO

mode whenever you cycle the power. If you use a multi-function input terminal to switch AUTO / HAND mode, the multi-function input terminal has the highest priority. When the external terminal is OFF, the drive does not accept any operation signal and cannot execute JOG.

✓ 00-32 Digital Keypad STOP Function

Default: 0

Settings 0: STOP key disabled
1: STOP key enabled

📖 Valid when the operation command source is note the digital keypad (Pr.00-21 ≠ 0). When Pr.00-21 = 0, the STOP key on the digital keypad is not affected by this parameter.

✓ 00-37 Over-modulation Gain

Default: 100

Settings 80–120

📖 When the motor operates in the flux-weakening region or voltage saturation region it can be that a higher voltage output is required. Increase Pr.00-37 to increase the output RMS voltage. Increasing the over-modulation gain reduces the output current and enhances the motor efficiency. However, note that low-frequency harmonics created by the six-step square-wave modulation may occur if the gain is too large.

📖 How to use Pr.00-37:
Gradually increase Pr.00-37 setting value to check if the output current reduces and the operation performance improves for an optimal over-modulation gain value.

✓ 00-48 Display Filter Time (Current)

Default: 0.100

Settings: 0.001–65.535 sec.

📖 Minimizes the current fluctuation displayed by the digital keypad.

✓ 00-49 Display Filter Time (Keypad)

Default: 0.100

Settings: 0.001–65.535 sec

📖 Minimizes the value fluctuation displayed by the digital keypad.

00-50 Software Version (date)

Default: Read only

Settings: Read only

📖 Displays the current drive software version by date.

01 Basic Parameters

⚡ You can set this parameter during operation.

⚡ **01-00** Maximum Operation Frequency

Default: 60.00 / 50.00

Settings 50.00–599.00 Hz
230V models: setting range for / including 55 kW: 0.00–400.00 Hz
460V models: setting range for / including 90 kW: 0.00–400.00 Hz
575V / 690V models: 599.00 Hz

🕮 Determines the AC motor drive's maximum operation frequency range. All the AC motor drive frequency command sources (analog inputs 0–10 V, 4–20 mA, 0–20 mA, ±10 V) are scaled to correspond to the output frequency range.

Minimum Carrier Frequency Requirement	Maximum Operation Frequency (IM VF/ IM SVC)
2k	200 Hz
3k	300 Hz
4k	400 Hz
5k	500 Hz
6k	599 Hz
230V models 55 kW and above: the maximum operation frequency is 400 Hz (the carrier frequency should be set at least 4k) 460V models 90 kW and above: the maximum operation frequency is 400 Hz (the carrier frequency should be set at least 4k) 575V / 690V models: maximum operation frequency is 599 Hz	

01-01 Rated / Base Frequency of Motor 1

01-35 Rated / Base Frequency of Motor 2

Default: 60.00 / 50.00

Settings 0.00–599.00 Hz

🕮 Set this parameter according to the motor's rated frequency on the motor nameplate. If the motor's rated frequency is 60 Hz, set this parameter to 60. If the motor's rated frequency is 50 Hz, set this parameter to 50.

01-02 Rated / Base Voltage of Motor 1

01-36 Rated / Base Voltage of Motor 2

Default: 220.0/400.0/
575.0/660.0

Settings 230V models: 0.0–255.0 V
460V models: 0.0–510.0 V
575V models: 0.0–637.0 V
690V models: 0.0–765.0 V

🕮 Set this parameter according to the rated voltage on the motor nameplate. If the motor's rated voltage is 220 V, set this parameter to 220.0. If the motor's rated voltage is 200 V, set this parameter to 200.0.

🕮 There are many motor types in the market and the power system for each country is also different. The economical and convenient solution is to install an AC motor drive. Then there is no problem using the motor with different voltage and frequency inputs, and the motor drive can improve the original motor characteristics and useful life.

01-03 Mid-point Frequency 1 of Motor 1

Default: 3.00 / 3.00 /
0.0 / 0.0

Settings 230V models: 0.00–599.00 Hz
460V models: 0.00–599.00 Hz
575V models: 0.00–599.00 Hz
690V models: 0.00–599.00 Hz

✎ 01-04 Mid-point Voltage 1 of Motor 1

Default: 11.0 / 22.0 /
0.0 / 0.0

Settings 230V models: 0.0–240.0 V
460V models: 0.0–480.0 V
575V models: 0.0–637.0 V
690V models: 0.0–720.0 V

690V, 185 kW and above models: 10.0

01-37 Mid-point Frequency 1 of Motor 2

Default: 3.00

Settings 0.00–599.00 Hz

✎ 01-38 Mid-point Voltage 1 of Motor 2

Default: 11.0 / 22.0 /
0.0 / 0.0

Settings 230V models: 0.0–240.0 V
460V models: 0.0–480.0 V
575V models: 0.0–637.0 V
690V models: 0.0–720.0 V

690V, 185 kW and above models: 10.0

01-05 Mid-point Frequency 2 of Motor 1

Default: 1.50

Settings 0.00–599.00 Hz

✎ 01-06 Mid-point Voltage 2 of Motor 1

Default: 5.0 / 10.0 /
0.0 / 0.0

Settings 230V models: 0.0–240.0 V
460V models: 0.0–480.0 V
575V models: 0.0–637.0 V
690V models: 0.0–720.0 V

690V, 185 kW and above models: 2.0

01-39 Mid-point Frequency 2 of Motor 2

Default: 1.50

Settings 0.00–599.00 Hz

⚡ 01-40 Mid-point Voltage 2 of Motor 2

Default: 5.0 / 10.0 /
0.0 / 0.0

Settings 230V models: 0.0–240.0 V
460V models: 0.0–480.0 V
575V models: 0.0–637.0 V
690V models: 0.0–720.0 V

690V, 185 kW and above models: 2.0

01-07 Minimum Output Frequency of Motor 1

Default: 1.50

Settings 0.00–599.00 Hz

⚡ 01-08 Minimum Output Voltage of Motor 1

Default: 1.0 / 2.0 /
0.0 / 0.0

Settings 230V models: 0.0–240.0 V
460V models: 0.0–480.0 V
575V models: 0.0–637.0 V
690V models: 0.0–720.0 V

01-41 Minimum Output Frequency of Motor 2

Default: 0.50

Settings 0.00–599.00 Hz

⚡ 01-42 Minimum Output Voltage of Motor 2

Default: 1.0 / 2.0 /
0.0 / 0.0

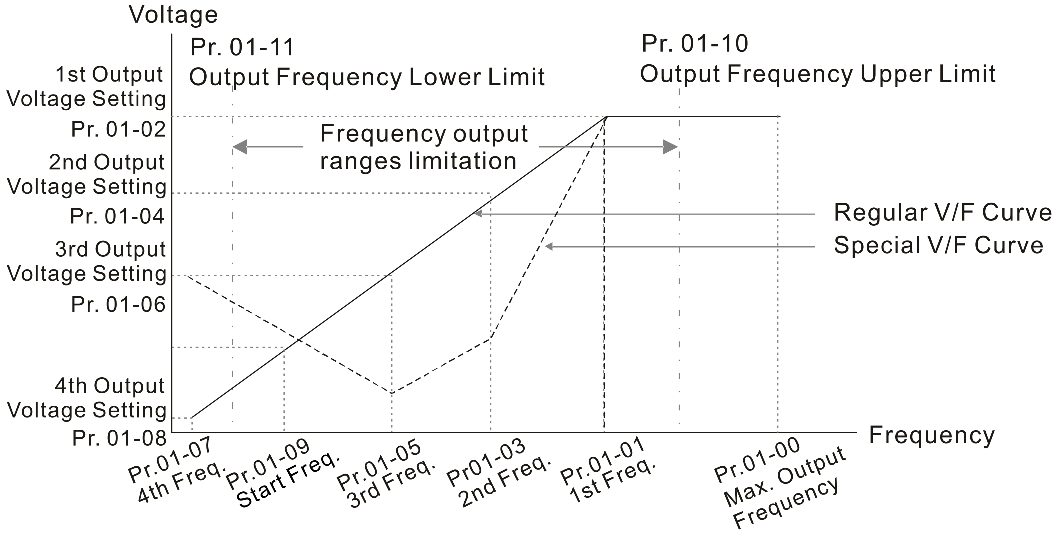
Settings 230V models: 0.0–240.0 V
460V models: 0.0–480.0 V
575V models: 0.0–637.0 V
690V models: 0.0–720.0 V

📖 You usually set the V/F curve according to the motor's allowable loading characteristics. Pay special attention to the motor's heat dissipation, dynamic balance, and bearing lubrication when the loading characteristics exceed the loading limit of the motor.

📖 There is no limit for the voltage setting, but a high voltage at a low frequency may cause motor damage, overheating, and trigger the stall prevention or the over-current protection; therefore, use low voltage at low frequency to prevent motor damage or drive error.

📖 Pr.01-35 to Pr.01-42 is the V/F curve for motor 2. When setting the multi-function input terminals [Pr.02-01–02-08 and Pr.02-26–Pr.02-31 (extension card)] to 14, the AC motor drive acts with the second V/F curve.

📖 The diagram below shows the V/F curve for motor 1. You can use the same V/F curve for motor 2.

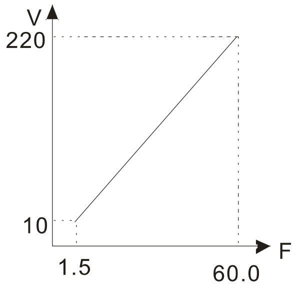

Voltage
Pr. 01-11
Output Frequency Lower Limit
Pr. 01-10
Output Frequency Upper Limit
1st Output Voltage Setting Pr. 01-02
2nd Output Voltage Setting Pr. 01-04
3rd Output Voltage Setting Pr. 01-06
4th Output Voltage Setting Pr. 01-08
Frequency output ranges limitation
Regular V/F Curve
Special V/F Curve
Frequency
Pr.01-07 4th Freq.
Pr.01-09 Start Freq.
Pr.01-05 3rd Freq.
Pr01-03 2nd Freq.
Pr.01-01 1st Freq.
Pr.01-00 Max. Output Frequency

V/F Curve and The Related Parameters

Common settings of the V/F curve:

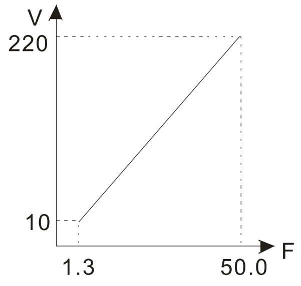
(1) General purpose

Motor spec. 60Hz



Pr.	Setting
01-00	60.0
01-01	60.0
01-02	220.0
01-03 01-05	1.50
01-04 01-06	10.0
01-07	1.50
01-08	10.0

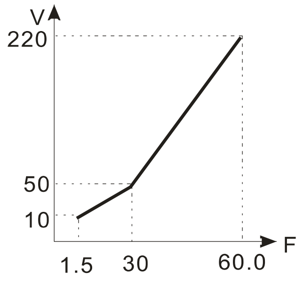
Motor spec. 50Hz



Pr.	Setting
01-00	50.0
01-01	50.0
01-02	220.0
01-03 01-05	1.30
01-04 01-06	10.0
01-07	1.30
01-08	10.0

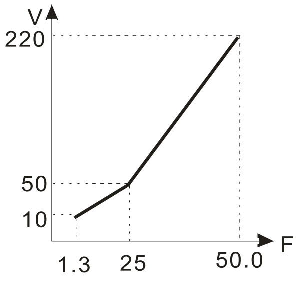
(2) For fan and hydraulic machinery

Motor spec. 60Hz



Pr.	Setting
01-00	60.0
01-01	60.0
01-02	220.0
01-03 01-05	30.0
01-04 01-06	50.0
01-07	1.50
01-08	10.0

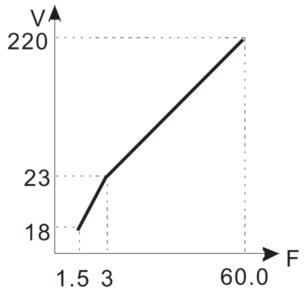
Motor spec. 50Hz



Pr.	Setting
01-00	50.0
01-01	50.0
01-02	220.0
01-03 01-05	25.0
01-04 01-06	50.0
01-07	1.30
01-08	10.0

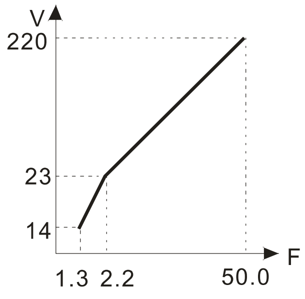
(3) High starting torque

Motor spec. 60Hz



Pr.	Setting
01-00	60.0
01-01	60.0
01-02	220.0
01-03 01-05	3.00
01-04 01-06	23.0
01-07	1.50
01-08	18.0

Motor spec. 50Hz



Pr.	Setting
01-00	50.0
01-01	50.0
01-02	220.0
01-03 01-05	2.20
01-04 01-06	23.0
01-07	1.30
01-08	14.0

01-09 Start-Up Frequency

Default: 0.50

Settings 0.00–599.00 Hz

- When the starting frequency is larger than the Minimum Output Frequency, the drives' frequency output starts when the starting frequency reaches the F command. Refer to the following diagram for details.

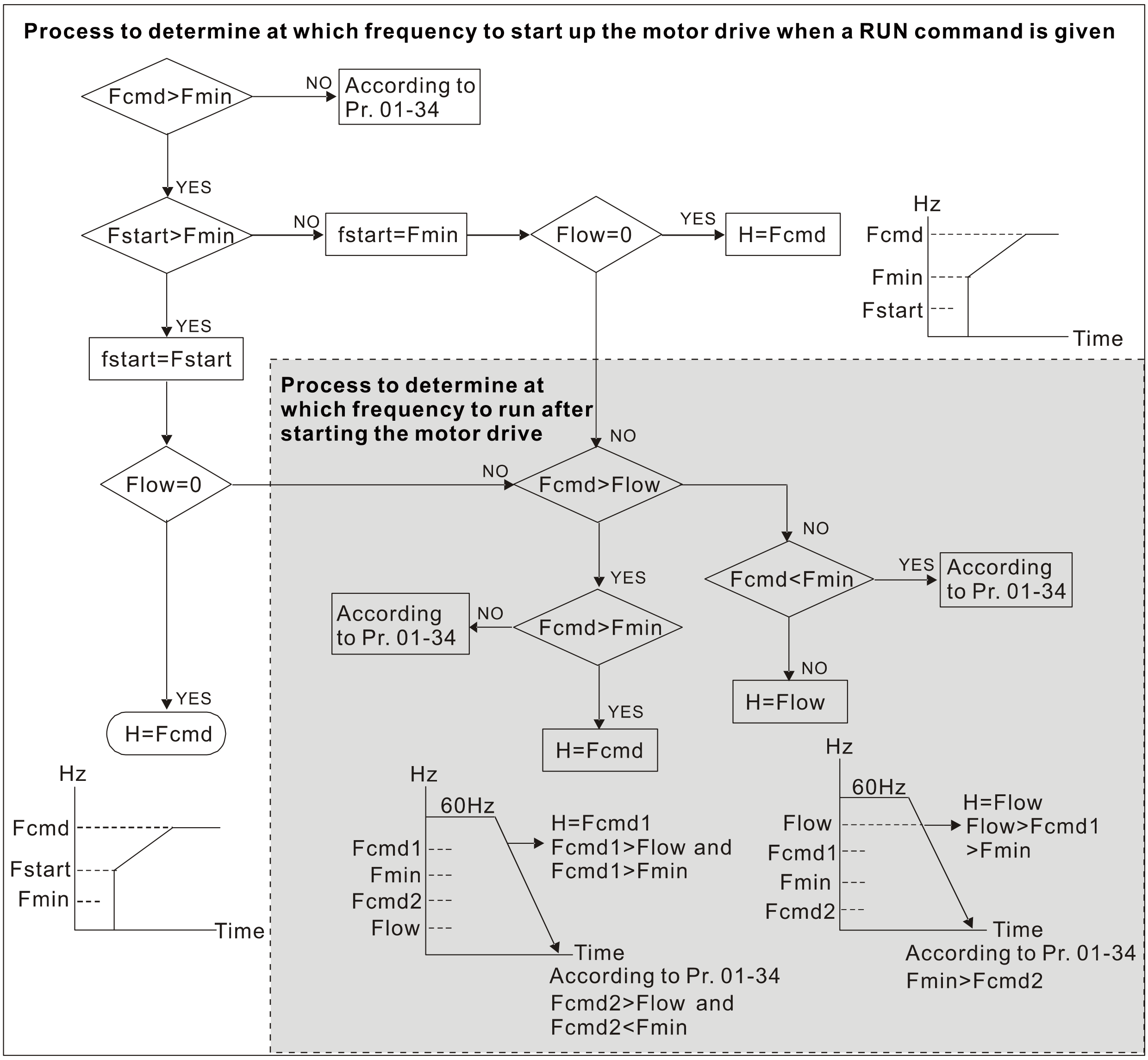
  Fcmd: frequency command

  Fstart: start-up frequency (Pr.01-09)

  fstart: actual start-up frequency of the drive

  Fmin: 4th output frequency setting (Pr.01-07 / Pr.01-41)

  Flow: output frequency lower limit (Pr.01-11)



- When Fcmd > Fmin and Fcmd < Fstart:

  If Flow < Fcmd, the drive runs directly by Fcmd.

  If Flow ≥ Fcmd, the drive runs with Fcmd, and then rises to Flow according to acceleration time.

- The drive's output frequency goes directly to 0 when decelerating to Fmin.

✓ 01-10 Output Frequency Upper Limit

Default: 599.00

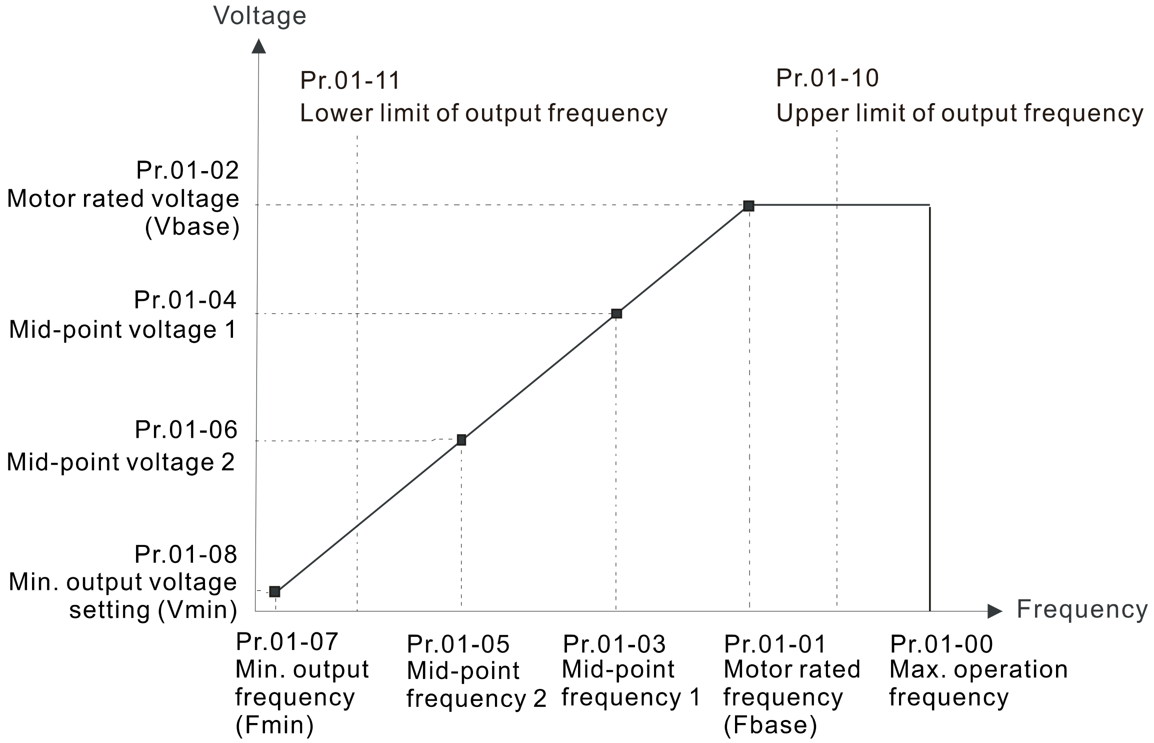
Settings 0.00–599.00 Hz

✓ 01-11 Output Frequency Lower Limit

Default: 0.00

Settings 0.00–599.00 Hz

- If the output frequency setting is higher than the upper limit (Pr.01-10), the drive runs with the upper limit frequency. If the output frequency setting is lower than the lower limit (Pr.01-11) but higher than the minimum output frequency (Pr.01-07), the drive runs with the lower limit frequency. Set the upper limit frequency > the lower limit frequency (Pr.01-10 setting value must be > Pr.01-11 setting value).
- If the slip compensation function (Pr.07-27) is enabled for the drive, the drive's output frequency may exceed the Frequency command.



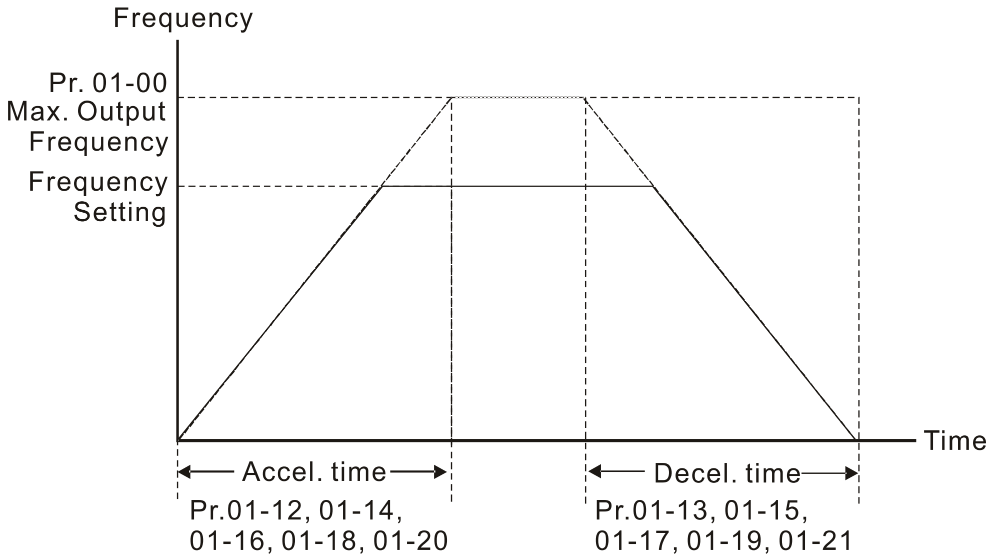
- When the drive starts, it operates according to the V/F curve and accelerates from the minimum output frequency (Pr.01-07) to the setting frequency. It is not limited by the lower output frequency settings.
- Use the frequency upper and lower limit settings to prevent operator misuse, overheating caused by the motor's operating at a too low frequency, or mechanical wear due to a too high operation frequency.
- If the frequency upper limit setting is 50 Hz and the frequency setting is 60 Hz, the maximum operation frequency is 50 Hz.
- If the frequency lower limit setting is 10 Hz and the minimum operation frequency setting (Pr.01-07) is 1.5 Hz, then the drive operates at 10 Hz when the Frequency command is higher than Pr.01-07 but lower than 10 Hz. If the Frequency command is lower than Pr.01-07, the drive is in ready status without output.

ϟ 01-12 Acceleration Time 1
ϟ 01-13 Deceleration Time 1
ϟ 01-14 Acceleration Time 2
ϟ 01-15 Deceleration Time 2
ϟ 01-16 Acceleration Time 3
ϟ 01-17 Deceleration Time 3
ϟ 01-18 Acceleration Time 4
ϟ 01-19 Deceleration Time 4
ϟ 01-20 JOG Acceleration Time
ϟ 01-21 JOG Deceleration Time

Default: 10.00
Default: 60.00 / 60.0 (22 kW models and above)
Default: 80.00 / 80.0 (160 kW models and above)

Settings Pr.01-45 = 0: 0.00–600.00 seconds
Pr.01-45 = 1: 0.0–6000.0 seconds

- The acceleration time determines the time required for the AC motor drive to ramp from 0.00 Hz to the maximum operation frequency (Pr.01-00). The deceleration time determines the time required for the AC motor drive to decelerate from the maximum operation frequency (Pr.01-00) down to 0.00 Hz.
- The acceleration and deceleration time are invalid when using Pr.01-44 Auto-acceleration and Auto-deceleration Setting
- Select the Acceleration / Deceleration time 1, 2, 3, 4 with the multi-function input terminals settings. The defaults are Acceleration Time 1 and Deceleration Time 1.
- With the enabled torque limits and stall prevention functions, the actual acceleration and deceleration time are longer than the above action time.
- Note that setting the acceleration and deceleration time too short may trigger the drive's protection function (Pr.06-03 Over-current Stall Prevention during Acceleration or Pr.06-01 Over-voltage Stall Prevention), and the actual acceleration and deceleration time are longer than this setting.
- Note that setting the deceleration time too short may cause motor damage or trigger drive protection due to over-current during the drive's deceleration or over-voltage.
- Use suitable brake resistor (refer to Section 07 Optional Accessories) to decelerate in a short time and prevent over-voltage.
- When you enable Pr.01-24–Pr.01-27 (S-curve acceleration and deceleration begin and arrival time), the actual acceleration and deceleration time are longer than the setting.



Acceleration / Deceleration Time

✎ 01-22 JOG Frequency

Default: 6.00

Settings 0.00–599.00 Hz

📖 You can use both the external terminal JOG and F1 key on the optional keypad KPC-CC01 to set the JOG function. When the JOG command is ON, the AC motor drive accelerates from 0 Hz to the JOG frequency (Pr.01-22). When the JOG command is OFF, the AC motor drive decelerates from the JOG frequency to stop. The JOG acceleration and deceleration time (Pr.01-20, Pr.01-21) are the time to accelerate from 0.0 Hz to JOG frequency (Pr.01-22).

You cannot execute the JOG command when the AC motor drive is running. When the JOG command is executing, other operation commands are invalid.

✎ 01-23 Switch Frequency between First and Fourth Accel. / Decel.

Default: 0.00

Settings 0.00–599.00 Hz

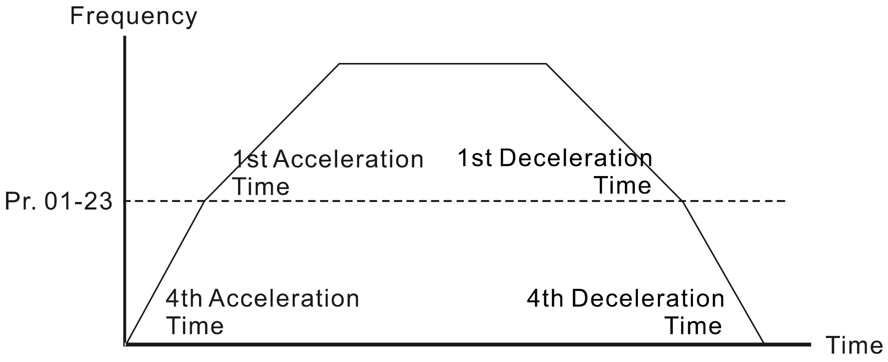
📖 This function does not require the external terminal switching function; it switches the acceleration and deceleration time automatically according to the Pr.01-23 setting. If you set the external terminal, the external terminal has priority over Pr.01-23.

📖 Use this parameter to set the switch frequency between acceleration and deceleration slope. The First / Fourth Accel. / Decel. slope is calculated by the Max. Operation Frequency (Pr.01-00) / acceleration / deceleration time.

Example: When the Max. Operation Frequency (Pr.01-00) = 80 Hz, and Switch Frequency between First and Fourth Accel. / Decel. (Pr.01-23) = 40 Hz:

a. If Acceleration Time 1 (Pr.01-02) = 10 sec., Acceleration Time 4 (Pr.01-18) = 6 sec., then the acceleration time is 3 sec. for 0–40 Hz and 5 sec. for 40–80 Hz.

b. If Deceleration Time 1 (Pr.01-13) = 8 sec., Deceleration Time 4 (Pr.01-19) = 2 sec., then the deceleration time is 4 sec. for 80–40 Hz and 1 sec. for 40–0 Hz.



1st/4th Acceleration/Deceleration Frequency Switching

✓ **01-24** S-curve for Acceleration Begin Time 1

✓ **01-25** S-curve for Acceleration Arrival Time 2

✓ **01-26** S-curve for Deceleration Begin Time 1

✓ **01-27** S-curve for Deceleration Arrival Time 2

Default: 0.20

Settings Pr.01-45 = 0: 0.00–25.00 seconds

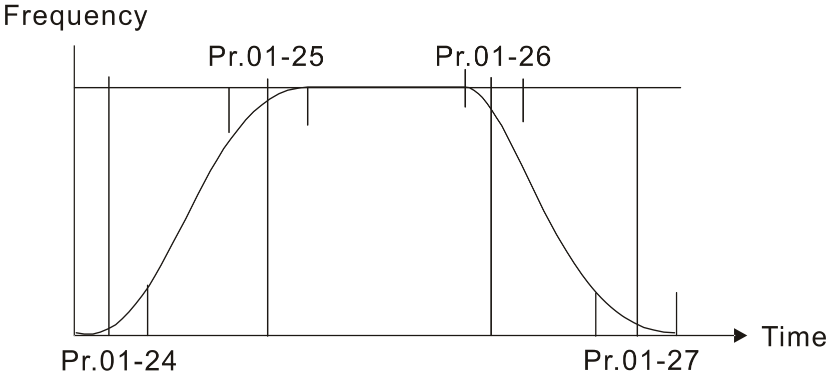
Pr.01-45 = 1: 0.0–250.0 seconds

📖 Using an S-curve gives the smoothest transition between speed changes. The acceleration and deceleration curve adjusts the acceleration and deceleration S-curve. When enabled, the drive produces a different acceleration and deceleration curve according to the acceleration and deceleration time.

📖 The S-curve function is invalid when you set the acceleration and deceleration time to 0.

📖 When Pr.01-12, Pr.01-14, Pr.01-16, Pr.01-18 ≥ Pr.01-24 and Pr.01-25,
the actual acceleration time = Pr.01-12, Pr.01-14, Pr.01-16, Pr.01-18 + (Pr.01-24 + Pr.01-25) / 2

📖 When Pr.01-13, Pr.01-15, Pr.01-17, Pr.01-19 ≥ Pr.01-26 and Pr.01-27,
the actual deceleration time = Pr.01-13, Pr.01-15, Pr.01-17, Pr.01-19 + (Pr.01-26 + Pr.01-27) / 2



01-28 Skip Frequency 1 (Upper Limit)

01-29 Skip Frequency 1 (Lower Limit)

01-30 Skip Frequency 2 (Upper Limit)

01-31 Skip Frequency 2 (Lower Limit)

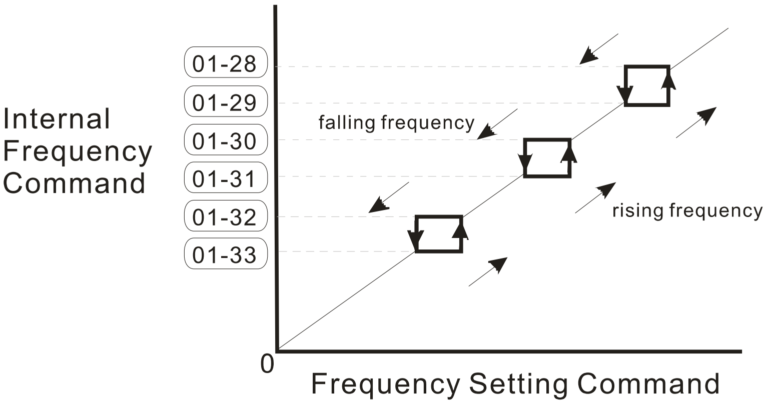
01-32 Skip Frequency 3 (Upper Limit)

01-33 Skip Frequency 3 (Lower Limit)

Default: 0.00

Settings 0.00–599.00 Hz

- Sets the AC motor drive's skip frequency. The drive's frequency setting skips these frequency ranges. However, the frequency output is continuous. There are no limits for these six parameters and you can combine them. Pr.01-28 does not need to be greater than Pr.01-29; Pr.01-30 does not need to be greater than Pr.01-31; Pr.01-32 does not need to be greater than Pr.01-33. You can set Pr.01-28–01-33 as you required. There is no size distinction among these six parameters.
- These parameters set the skip frequency ranges for the AC motor drive. You can use this function to avoid frequencies that cause mechanical resonance. The skip frequencies are useful when a motor has resonance vibration at a specific frequency bandwidth. Skipping this frequency avoids the vibration. There are three frequency skip zones available.
- You can set the frequency command (F) within the range of skip frequencies. Then the output frequency (H) is limited to the lower limit of skip frequency ranges.
- During acceleration and deceleration, the output frequency still passes through the skip frequency ranges.

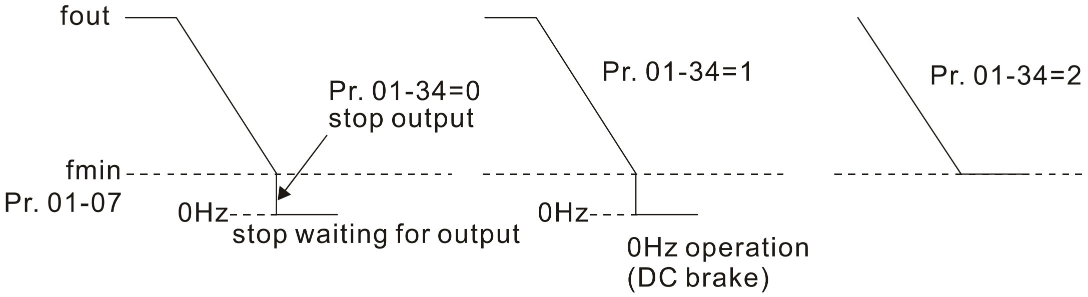


01-34 Zero-speed Mode

Default: 0

Settings 0: Output waiting
1: Zero-speed operation
2: Minimum frequency (Refer to Pr.01-07 and Pr.01-41)

- When the drive's Frequency command is lower than Fmin (Pr.01-07 or Pr.01-41), the drive operates according to this parameter.
- 0: the AC motor drive is in waiting mode without voltage output from terminals U, V, W.
- 1: the drive executes the DC brake by Vmin (Pr.01-08 and Pr.01-42) in V/F and SVC modes.
- 2: the AC motor drive runs using Fmin (Pr.01-07, Pr.01-41) and Vmin (Pr.01-08, Pr.01-42) in V/F and SVC modes.
- In V/F and SVC modes

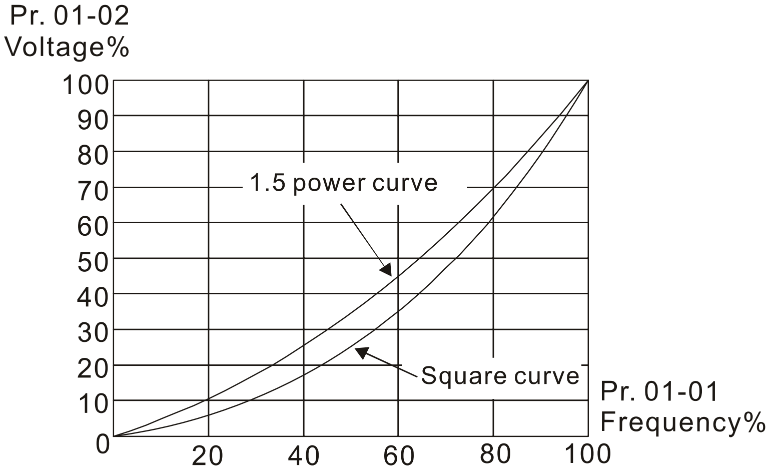


01-43 V/F Curve Selection

Default: 0

Settings 0: V/F curve determined by Pr.01-00–01-08
1: V/F curve to the power of 1.5
2: V/F curve to the power of 2
3: 60 Hz, voltage saturation in 50 Hz
4: 72 Hz, voltage saturation in 60 Hz
5: 50 Hz, decrease gradually with cube
6: 50 Hz, decrease gradually with square
7: 60 Hz, decrease gradually with cube
8: 60 Hz, decrease gradually with square
9: 60 Hz, medium starting torque
10: 60 Hz, high starting torque
11: 60 Hz, medium starting torque
12: 60 Hz, high starting torque
13: 90 Hz, voltage saturation in 60 Hz
14: 120 Hz, voltage saturation in 60 Hz
15: 180 Hz, voltage saturation in 60 Hz

- When setting to 0, refer to Pr.01-01–01-08 for the motor 1 V/F curve. For motor 2, refer to Pr.01-35–01-42.
- When setting to 1 or 2, the second and third voltage frequency setting are invalid.
- If the load of the motor is a variable torque load (torque is in direct proportion to the rotating speed, such as the load of a fan or a pump), the load torque is low at low rotating speed. You can decrease the input voltage appropriately to make the magnetic field of the input current smaller and reduce flux loss and iron loss for the motor to increase efficiency.
- When you set the V/F curve to high power, it has lower torque at low frequency, and the drive is not suitable for rapid acceleration and deceleration. Do NOT use this parameter for rapid acceleration and deceleration.

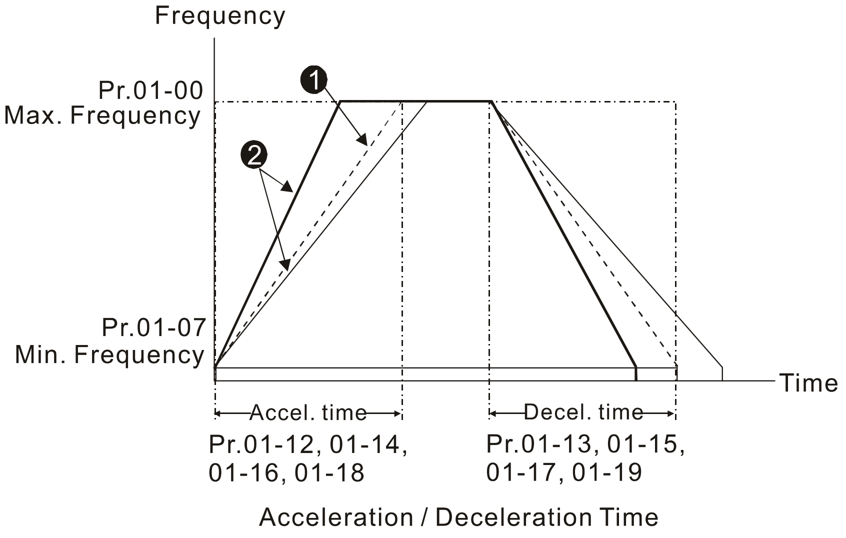


01-44 Auto-acceleration and Auto-deceleration Setting

Default: 0

Settings 0: Linear acceleration and deceleration
1: Auto-acceleration and linear deceleration
2: Linear acceleration and auto-deceleration
3: Auto-acceleration and auto-deceleration
4: Stall prevention by auto-acceleration and auto-deceleration (limited by Pr.01-12–Pr.01-21)

- 0 (linear acceleration and linear deceleration): the drive accelerates and decelerates according to the setting for Pr.01-12–01-19.
- 1 or 2 (auto / linear acceleration and auto / linear deceleration): the drive auto-tunes the acceleration and deceleration to effectively reduce the mechanical vibration during the load start-up and stop and make the auto-tuning process more easier. It does not stall during acceleration and does not need a brake resistor during deceleration to stop. It can also improve operation efficiency and save energy.
- 3 (auto-acceleration and auto-deceleration-decelerating by the actual load): the drive auto-detects the load torque and automatically accelerates from the fastest acceleration time and smoothest start-up current to the setting frequency. During deceleration, the drive automatically determines the loaded regenerative energy to steadily and smoothly stop the motor in the fastest deceleration time.
- 4 (stall prevention by auto-acceleration and deceleration–reference to the acceleration and deceleration time settings): if the acceleration and deceleration time are within a reasonable range, the actual acceleration and deceleration time refer to Pr.01-12–01-19 settings. If the acceleration and deceleration time are too short, the actual acceleration and deceleration time are greater than the acceleration and deceleration time settings.



❶ Optimize the acceleration / deceleration time when Pr.01-44 is set to 0.
❷ Optimize the acceleration / deceleration time which load needs actually when Pr.01-44 is set to 3.

01-45 Time Unit for Acceleration and Deceleration and S Curve

Default: 0

Settings 0: Unit 0.01 sec.
1: Unit 0.1 sec.

✎ 01-46 CANopen Quick Stop Time

Default: 1.00

Settings Pr.01-45 = 0: 0.00–600.00 sec.
Pr.01-45 = 1: 0.0–6000.0 sec.

🕮 Sets the time required to decelerate from the maximum operation frequency (Pr.01-00) to 0.00 Hz through the CANopen control.

01-49 Deceleration Method Selection

Default: 0

Settings 0: Normal deceleration
1: Over voltage energy restriction
2: Traction energy control (TEC)
3: Electromagnetic energy traction control

🕮 Different control modes for Pr.01-49:

Setting / Control mode	Induction Motor (IM)		Permanent Magnet Synchronous Motor (PM)			Synchronous Reluctance Motor (SynRM)
	VF	SVC	PMSVC	PMFOC	HFI	FOC
0: Normal deceleration	✓	✓	✓	✓	✓	✓
1: Over-voltage energy restriction	✓					
2: Traction energy control (TEC)	✓					
3: Electromagnetic energy traction control	✓					

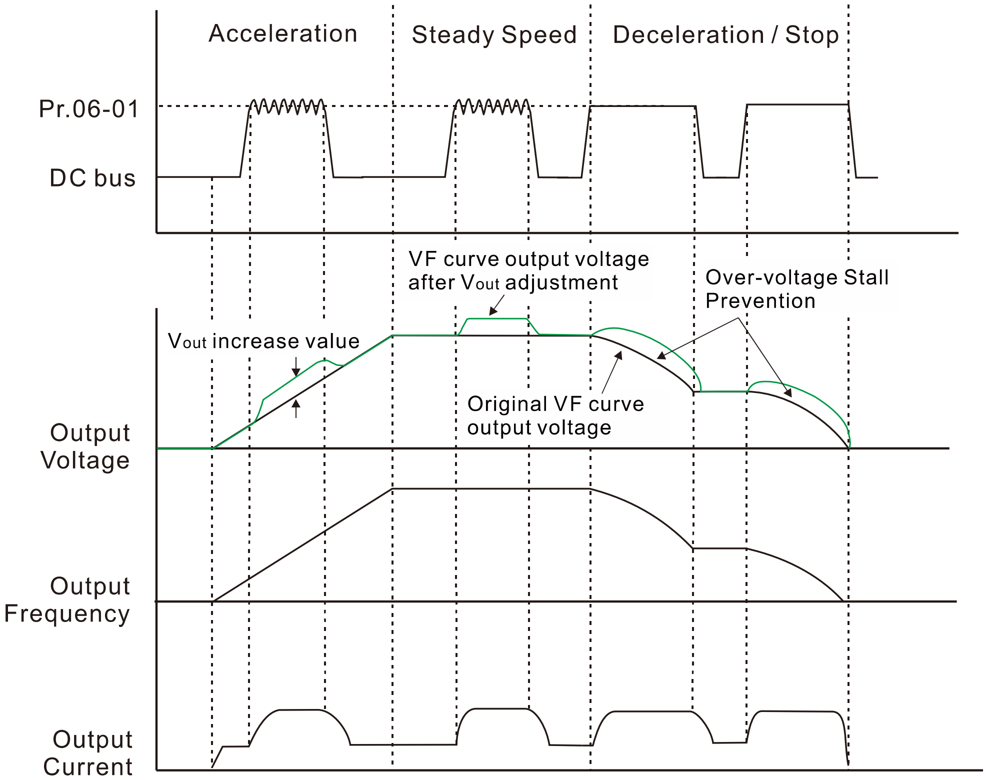
🕮 0: The drive decelerates or stops based on the original deceleration time settings. Use this setting when brake resistors are used.

🕮 1: During deceleration, the drive controls the motor according to Pr.06-01 (Over-voltage Stall Prevention) setting and the regenerative DC bus voltage. When the regenerative DC bus voltage reaches 95% of Pr.06-01, the controller is enabled. If Pr.06-01 = 0, the drive controls on the basis of the working voltage and regenerative DC bus voltage instead. When using this method, the drive decelerates according to the deceleration time setting. However, the actual deceleration time is equal to or larger than the deceleration setting time.

🕮 2: During deceleration, the drive controls the motor according Pr.06-01 (Over-voltage Stall Prevention) setting and the regenerative DC bus voltage. When the regenerative DC bus voltage reaches 95% of Pr.06-01, the drive dynamically adjusts the output frequency and output voltage to consume the regenerative energy. Use this method when the deceleration time that is set to fulfill the system requirement for application triggers over-voltage.

🕮 3: During operation (acceleration / steady speed / deceleration), the drive adjusts the output voltage according to the amount of regenerative energy and consumes the regenerative energy timely to reduce the risk of over-voltage. Moreover, you can also use Pr.01-50 (Electromagnetic Traction Energy Consumption Coefficient) to adjust the drive's output voltage strength.

- If you use the electromagnetic energy traction control (Pr.01-49 = 3) during linear deceleration (no triggering of over-voltage stall prevention), you can enhance the output current by increasing the output voltage (V_{out}) to further suppress the regenerative DC bus voltage that is prompt to rise. Using this function with Pr.06-02 = 1 (Smart Over-voltage Stall Prevention) can achieve a smoother and faster deceleration.



- Electromagnetic energy traction control activates in the following three conditions:
  1. Activates when DC bus is larger than the over-voltage stall prevention level (Pr.06-01) during acceleration and deactivates once Pr.06-01 is disabled.
  2. Activates when DC bus is larger than the over-voltage stall prevention level (Pr.06-01) during steady operation and deactivates once Pr.06-01 is disabled.
  3. Activates during deceleration (including stop) and deactivates once acceleration occurs or deceleration is stopped.
- When Pr.01-49 = 3, Pr.06-02 = 1 (Smart Over-voltage Stall Prevention) is automatically set to increase the stability during deceleration.

⚡ 01-50 Electromagnetic Traction Energy Consumption Coefficient

Default: 0.50

Settings 0.00–5.00

- During acceleration / steady speed / deceleration, the drive will dynamically adjust the output voltage based on the DC bus voltage level in order to prevent the drive from tripping on over-voltage. The output voltage is adjusted based on this parameter setting.
- The drive's output current and the efficiency of regenerative energy consumption increase when Pr.01-50 is increased. When Pr.01-50 is decreased, also the drive's output current and the

efficiency of regenerative energy consumption will decrease.

- When setting Pr.01-50, pay attention to the drive’s output current. The drive’s output current must be lower than 80% of the motor’s rated current to prevent the motor from overheating.

✓ **01-51** Flux-weakening Overload Stall Prevention Time (applied to 230V / 460V models)

Default: 1.00

Settings 0.00–600.00 sec.

- This parameter is only valid when Pr.00-11 = 8 (SynRM Sensorless Control Mode).
- When the drive operates in flux-weakening zone, and the motor decelerates due to its sudden loading increment, adjust the setting for this parameter.

02 Digital Input / Output Parameter

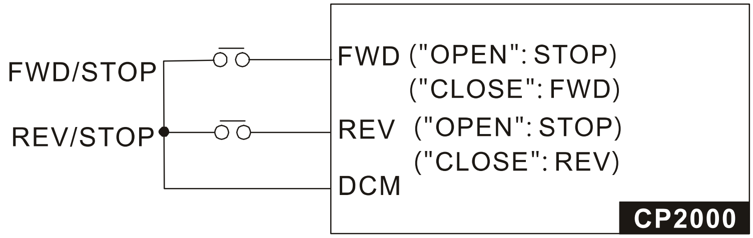
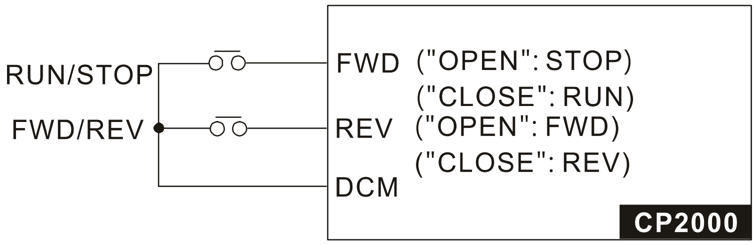
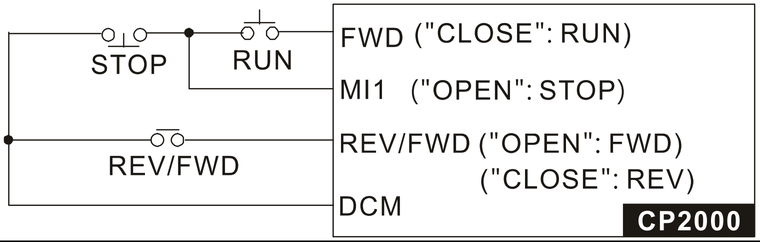
⚡ You can set this parameter during operation.

02-00 Two-wire / Three-wire Operation Control

Default: 0

Settings 0: Two-wire mode 1, power on for operation control
1: Two-wire mode 2, power on for operation control
2: Three-wire, power on for operation control

📖 This parameter sets the configuration of the terminals (Pr.00-21 = 1 or Pr.00-31 = 1) which control the operation. There are three different control modes listed in the following table.

Pr.02-00	Control Circuits of the External Terminal
Setting value: 0 Two-wire operation control FWD/STOP REV/STOP	 FWD/STOP REV/STOP FWD ("OPEN": STOP) ("CLOSE": FWD) REV ("OPEN": STOP) ("CLOSE": REV) DCM CP2000
Setting value: 1 Two-wire operation control RUN/STOP REV/FWD	 RUN/STOP FWD/REV FWD ("OPEN": STOP) ("CLOSE": RUN) REV ("OPEN": FWD) ("CLOSE": REV) DCM CP2000
Setting value: 2 Three-wire operation control	 STOP RUN REV/FWD FWD ("CLOSE": RUN) MI1 ("OPEN": STOP) REV/FWD ("OPEN": FWD) ("CLOSE": REV) DCM CP2000

02-01 Multi-function Input Command 1 (MI1)

Default: 1

02-02 Multi-function Input Command 2 (MI2)

Default: 2

02-03 Multi-function Input Command 3 (MI3)

Default: 3

02-04 Multi-function Input Command 4 (MI4)

Default: 4

02-05 Multi-function Input Command 5 (MI5)

02-06 Multi-function Input Command 6 (MI6)

02-07 Multi-function Input Command 7 (MI7)

02-08 Multi-function Input Command 8 (MI8)

02-26 Input terminal of I/O extension card (MI10)

02-27 Input terminal of I/O extension card (MI11)

02-28 Input terminal of I/O extension card (MI12)

02-29 Input terminal of I/O extension card (MI13)

02-30 Input terminal of I/O extension card (MI14)

02-31 Input terminal of I/O extension card (MI15)

Default: 0

Settings

0: No function
1: Multi-step speed command 1
2: Multi-step speed command 2
3: Multi-step speed command 3
4: Multi-step speed command 4
5: Reset
6: JOG operation [by external control or KPC-CC01 (optional)]
7: Acceleration / deceleration speed inhibit
8: 1st and 2nd acceleration / deceleration time selection
9: 3rd and 4th acceleration / deceleration time selection
10: External Fault (EF) input (Pr.07-20)
11: Base Block (B.B.) input from external
12: Output stop
13: Cancel the setting of auto-acceleration / auto-deceleration time
14: Switch between motor 1 and motor 2
15: Rotating speed command from AVI1
16: Rotating speed command from ACI
17: Rotating speed command from AVI2
18: Forced to stop (Pr.07-20)
19: Frequency up command
20: Frequency down command
21: PID function disabled
22: Clear the counter
23: Input the counter value (MI6)
24: FWD JOG command
25: REV JOG command
28: Emergency stop (EF1)
29: Signal confirmation for Y-connection
30: Signal confirmation for ∆-connection
38: Disable write EEPROM function
40: Force coasting to stop
41: HAND switch
42: AUTO switch
49: Enable drive

50: Slave dEb action to execute
51: Selection for PLC mode bit0
52: Selection for PLC mode bit1
53: Trigger CANopen quick stop
54: UVW output electromagnetic valve switch
55: Brake release
56: Local / Remote Selection
58: Enable fire mode with RUN command
59: Enable fire mode without RUN command
60: Disable all the motors
61: Disable Motor 1
62: Disable Motor 2
63: Disable Motor 3
64: Disable Motor 4
65: Disable Motor 5
66: Disable Motor 6
67: Disable Motor 7
68: Disable Motor 8
69: Preheating command

🕮 This parameter selects the functions for each multi-function terminal.

🕮 Pr.02-26–Pr.02-31 are entity input terminals only when extension cards are installed; otherwise, there are virtual terminals. For example, when using the multi-function extension card EMC-D42A, Pr.02-26–Pr.02-29 are defined as the corresponded parameters for MI10–MI13. In this case, Pr.02-30–Pr.02-31 are virtual terminals.

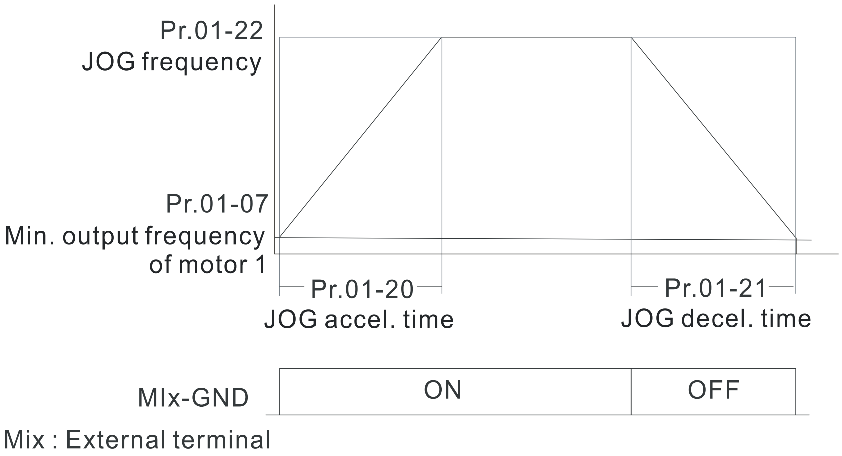
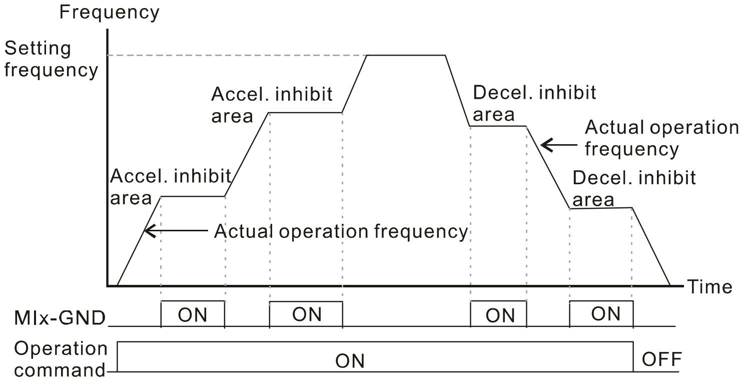
🕮 When Pr.02-12 is defined as virtual terminal, use digital keypad KPC-CC01 or communication method to change its status (0: ON; 1: OFF) of bit8–15.

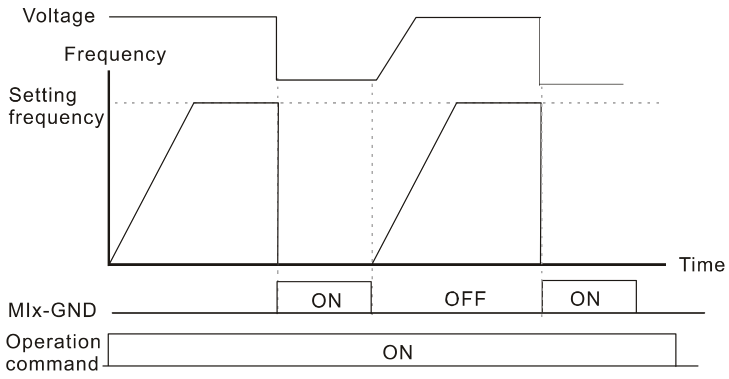
🕮 If Pr.02-00 is set to three-wire operation control, terminal MI1 is for the STOP contact. The function set previously for this terminal is automatically invalid.

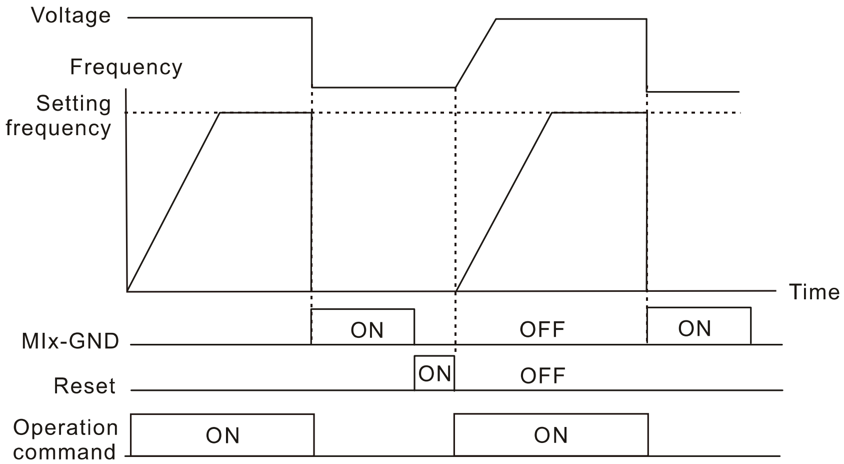
Summary of function settings

Take the normally opened contact (N.O.) for example, ON: contact is closed, OFF: contact is open

Settings	Functions	Descriptions
0	No Function	
1	Multi-step speed command 1	You can set 15 steps of speed or 15 positions with the digital status of these four terminals. You can use 16-steps of speed if you include the master speed when setting as 15 steps of speed (refer to Parameter Group 04 Multi-step Speed Parameters.)
2	Multi-step speed command 2	
3	Multi-step speed command 3	

Settings	Functions	Descriptions
4	Multi-step speed command 4	
5	Reset	Use this terminal to reset the drive after clearing a drive fault.
6	JOG operation [by external control or KPC-CC01 (optional)]	This function is valid when the source of the operation command is the external terminals. The JOG operation executes when the drive stops completely. While running, you can still change the operation direction, and the STOP key on the keypad* and the STOP command from communications are valid. Once the external terminal receives the OFF command, the motor stops in the JOG deceleration time. Refer to Pr.01-20–01-22 for details. *: This function is valid when Pr.00-32 is set to 1.  Pr.01-22 JOG frequency Pr.01-07 Min. output frequency of motor 1 Pr.01-20 JOG accel. time Pr.01-21 JOG decel. time MIx-GND ON OFF Mix : External terminal
7	Acceleration / deceleration speed inhibit	When you enable this function, the drive stops acceleration or deceleration immediately. After you disable this function, the AC motor drive starts to accelerate or decelerate from the inhibit point.  Frequency Setting frequency Accel. inhibit area Accel. inhibit area Actual operation frequency Decel. inhibit area Actual operation frequency Decel. inhibit area Time MIx-GND ON ON ON ON Operation command ON OFF
8	1st and 2nd acceleration / deceleration time selection	You can select the acceleration and deceleration time of the drive with this function, or from the digital status of the terminals; there are four acceleration and deceleration selection.

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>9</td><td>3rd and 4th acceleration / deceleration time selection</td><td><table>
<tr><td>MIx=9</td><td>MIx=8</td><td>Accel./Decel.</td></tr>
<tr><td>OFF</td><td>OFF</td><td>1st Accel./Decel.</td></tr>
<tr><td>OFF</td><td>ON</td><td>2nd Accel./Decel.</td></tr>
<tr><td>ON</td><td>OFF</td><td>3rd Accel./Decel.</td></tr>
<tr><td>ON</td><td>ON</td><td>4th Accel./Decel.</td></tr>
</table></td></tr>
<tr><td>10</td><td>External Fault (EF) Input</td><td>For external fault input, the drive decelerates according to the Pr.07-20 setting, and the keypad shows “EF” (It shows the fault record when an external fault occurs). The drive keeps running until the fault is cleared (terminal status restored) after RESET.</td></tr>
<tr><td>11</td><td>Base block (B.B.) input from external</td><td>ON: the output of the drive stops immediately. The motor is in free run and the keypad displays the B.B. signal. Refer to Pr.07-08 for details.</td></tr>
<tr><td>12</td><td>Output Stop</td><td>ON: the output of the drive stops immediately and the motor is in free run status. The drive is in output waiting status until the switch is turned to OFF, and then the drive restarts and runs to the current setting frequency.
 </td></tr>
<tr><td>13</td><td>Cancel the setting of auto-acceleration / auto-deceleration time</td><td>Set Pr.01-44 to one of the 01–04 setting modes before using this function. When this function is enabled, OFF is for auto mode and ON is for linear acceleration / deceleration.</td></tr>
<tr><td>14</td><td>Switch between motor 1 and motor 2</td><td>ON: use parameters for motor 2.
OFF: use parameters for motor 1.</td></tr>
<tr><td>15</td><td>Rotating speed command from AVI1</td><td>ON: force the source of the drive’s frequency to be AVI1. (If the rotating speed commands are set to AVI1, ACI and AVI2 at the same time, the priority is AVI1 > ACI > AVI2)</td></tr>
<tr><td>16</td><td>Rotating speed command form ACI</td><td>ON: force the source of the drive’s frequency to be ACI. (If the rotating speed commands are set to AVI1, ACI and AVI2 at the same time. The priority is AVI1 > ACI > AVI2)</td></tr>
<tr><td>17</td><td>Rotating speed command form AVI2</td><td>ON: force the source of the drive’s frequency to be AVI2. (If the rotating speed commands are set to AVI1, ACI and AVI2 at the same time. The priority is AVI1 > ACI > AVI2)</td></tr>
<tr><td>18</td><td>Forced to stop (Pr.07-20)</td><td>ON: the drive ramps to stop according to the Pr.07-20 setting.</td></tr>
</table>

Settings	Functions	Descriptions
19	Frequency Up command	ON: the frequency of the drive increases or decreases by one unit. If this function remains ON continuously, the frequency increases or decreases according to Pr.02-09 / Pr.02-10. The Frequency command returns to zero when the drive stops, and the displayed frequency is 0.0 Hz. If you select Pr.11-00, bit7 = 1, the frequency is not saved.
20	Frequency Down command	
21	PID function disabled	ON: the PID function is disabled.
22	Clear the counter	ON: the current counter value is cleared and displays “0”. The drive counts up when this function is disabled.
23	Input the counter value	ON: the counter value increases by one. Use the function with Pr.02-19.
24	FWD JOG command	This function is valid when the source of the operation command is external terminal. ON: the drive executes forward JOG.
25	REV JOG command	This function is valid when the source of the operation command is external terminal. ON: the drive executes reverse JOG.
28	Emergency stop (EF1)	ON: the output of the drive stops immediately, displays “EF1” on the keypad, and the motor is in the free run status. The drive keeps running until the fault is cleared after you press RESET on the keypad (EF: External Fault).  Voltage Frequency Setting frequency Time MIx-GND ON OFF ON Reset ON OFF Operation command ON ON
29	Signal confirmation for Y-connection	When the control mode is V/F, ON: the drive operates by the first V/F.
30	Signal confirmation for ∆-connection	When the control mode is V/F, ON: the drive operates by the second V/F.
38	Disable writing EEPROM function (parameters memory disable)	ON: writing to EEPROM is disabled. Changed parameters are not saved after power off
40	Force coasting to stop	ON: during operation, the motor coasts to stop.

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>41</td><td>HAND switch</td><td rowspan="2">1. When the MI terminal switches to OFF, it executes a STOP command. Therefore, if the MI terminal switches to OFF during operation, the drive stops.
2. Use the optional keypad KPC-CC01 to switch between HAND and AUTO. The drive stops first, and then switches to HAND or AUTO status.
3. The optional digital keypad KPC-CC01 displays the current status of the drive (HAND/OFF/AUTO).
<table><tr><th></th><th>bit1</th><th>bit0</th></tr><tr><td>OFF</td><td>0</td><td>0</td></tr><tr><td>AUTO</td><td>0</td><td>1</td></tr><tr><td>HAND</td><td>1</td><td>0</td></tr><tr><td>OFF</td><td>1</td><td>1</td></tr></table></td></tr>
<tr><td>42</td><td>AUTO switch</td></tr>
<tr><td>49</td><td>Enable drive</td><td>When the drive is enabled, the RUN command is valid.
When the drive is disabled, the RUN command is invalid.
When drive is operating, the motor coasts to stop.
This function varies with MOx = 45.</td></tr>
<tr><td>50</td><td>Slave dEb action to execute</td><td>Enter the message setting in this parameter when the master triggers dEb. This ensures that the slave also triggers dEb, then the master and slave stop simultaneously.</td></tr>
<tr><td>51</td><td>Selection for PLC mode (bit0)</td><td rowspan="2"><table><tr><th>PLC status</th><th>bit1</th><th>bit0</th></tr><tr><td>Disable PLC function (PLC 0)</td><td>0</td><td>0</td></tr><tr><td>Trigger PLC to operation (PLC 1)</td><td>0</td><td>1</td></tr><tr><td>Trigger PLC to stop (PLC 2)</td><td>1</td><td>0</td></tr><tr><td>No function</td><td>1</td><td>1</td></tr></table></td></tr>
<tr><td>52</td><td>Selection for PLC mode (bit1)</td></tr>
<tr><td>53</td><td>Trigger CANopen quick stop</td><td>When this function is enabled under CANopen control, it changes to Quick Stop. Refer to Section 15 CANopen Overview for more details.</td></tr>
<tr><td>54</td><td>UVW output electromagnetic valve switch</td><td>This function allows receiving confirmation signals when the output is controlled through the UVW magnetic switch.</td></tr>
<tr><td>55</td><td>Brake release</td><td>When Pr.02-56 ≠ 0, connect the brake release signal to multi-function input terminals. When the brake is opened, and the drive does not receive its confirming signal, the Brk error occurs.</td></tr>
<tr><td>56</td><td>LOCAL / REMOTE Selection</td><td>Use Pr.00-29 to select LOCAL / REMOTE mode (refer to Pr.00-29). When Pr.00-29 is not set to 0, the digital keypad KPC-CC01 displays the LOC / REM status. (KPC-CC01 firmware version 1.021 and above).
<table><tr><th></th><th>bit 0</th></tr><tr><td>REM</td><td>0</td></tr><tr><td>LOC</td><td>1</td></tr></table></td></tr>
</table>

Settings	Functions	Descriptions
58	Enable fire mode **with** RUN Command	Enable this function under fire mode to force the drive to run (while there **is** RUN command).
59	Enable fire mode **without** RUN Command	Enable this function under fire mode to force the drive to run (while there **is not** a RUN command).
60	Disable all the motors	ON: when the multi-motor circulative control is enable, all motors coast to stop.
61	Disable Motor 1	These functions work with multi-motor circulative control, motor 1 to 8 can be set to coast to stop. If any of Auxiliary Motor 1 to Motor 8 is out of order or under maintenance, enable this terminal to bypass that motor.
62	Disable Motor 2	
63	Disable Motor 3	
64	Disable Motor 4	
65	Disable Motor 5	
66	Disable Motor 6	
67	Disable Motor 7	
68	Disable Motor 8	
69	Preheating Command	ON: if the preheating function is open and drive is in STOP status, the preheating function is executed; until the contact status changes to OFF, or the drive status turns to RUN and stops the preheating function. Refer to Pr.02-72–02-73 for detail.

✓ 02-09 UP/DOWN Key Mode

Default: 0

Settings 0: Up / Down by the acceleration or deceleration time

1: Up / Down constant speed (Pr.02-10)

✓ 02-10 Constant speed, Acceleration or Deceleration Speed of the UP/DOWN Key

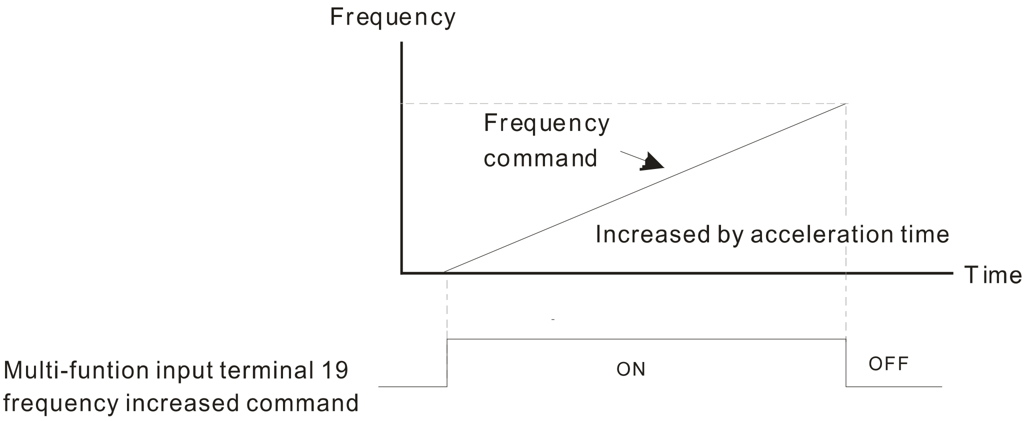
Default: 0.001

Settings 0.001–1.000 Hz/ms

🕮 Use when the multi-function input terminals are set to 19, 20 (Frequency UP / DOWN command). The frequency increases or decreases according to Pr.02-09 and Pr.02-10.

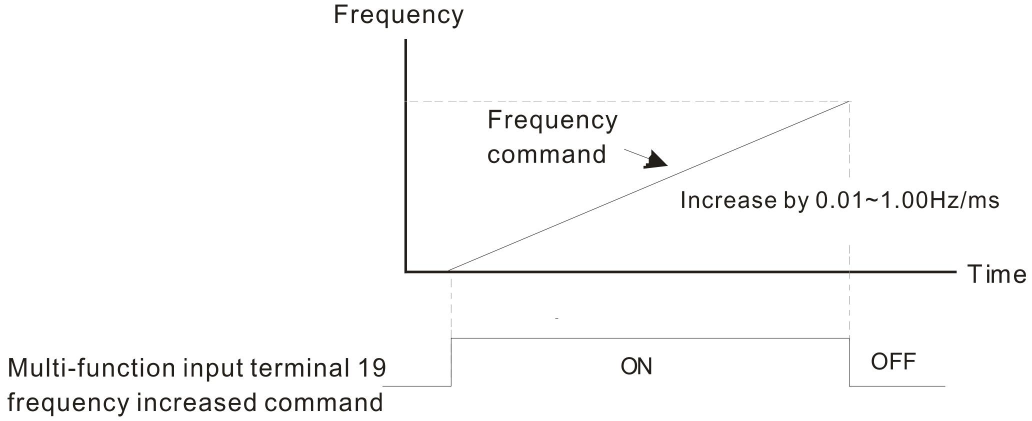
🕮 When Pr.02-09 is set to 0:

The increasing or decreasing Frequency command (F) operates according to the setting for acceleration or deceleration time (refer to Pr.01-12–Pr.01-19)


Frequency
Frequency command
Increased by acceleration time
Time
Multi-funtion input terminal 19 frequency increased command
ON
OFF

- When Pr.02-09 is set to 1:

  The increasing or decreasing Frequency command (F) operates according to the setting for Pr.02-10 (0.01–1.00 Hz/ms).


Frequency
Frequency command
Increase by 0.01~1.00Hz/ms
Time
Multi-function input terminal 19 frequency increased command
ON
OFF

✓ 02-11 Multi-function Input Response Time

Default: 0.005

Settings 0.000–30.000 sec.

- Use this parameter to set the response time of the digital input terminals FWD, REV and MI1–MI8.
- This function is to delay and confirm the digital input terminal signal. The time for delay is also the time for confirmation. The confirmation prevents interference that could cause error in the input to the digital terminals. But in the meanwhile, it delays the response time though confirmation improves accuracy.

✓ 02-12 Multi-function Input Mode Selection

Default: 0000h

Settings 0000h–FFFFh (0: N.O.; 1: N.C.)

- The parameter setting is in hexadecimal.
- This parameter sets the status of the multi-function input signal (0: normally open ; 1: normally closed) and it is not affected by the status of SINK / SOURCE.
- bit2–bit15 correspond to MI1–MI14.
- The default for bit0 is FWD terminal, and the default for bit1 is REV terminal. You cannot use this parameter to change the input mode.
- You can change the terminal ON / OFF status through communications.

  For example, MI1 is set to 1 (multi-step speed command 1) and MI2 is set to 2 (multi-step speed command 2). Then the forward + second step speed command = $1001_2 = 9_{10}$. As long as Pr.02-12 = 9 is set through communications, there is no need to wire any multi-function terminal to run forward with the second step speed.

bit15	bit14	bit13	bit12	bit11	bit10	bit9	bit8	bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
MI15	MI14	MI13	MI12	MI11	MI10	MI8	MI7	MI6	MI5	MI4	MI3	MI2	MI1	REV	FWD

02-13 Multi-function Output 1 (Relay1)

Default: 11

02-14 Multi-function Output 2 (Relay2)

Default: 1

02-15 Multi-function Output 3 (Relay3)

Default: 66

02-36 Output Terminal of I/O Extension Card (MO10) or (RA10)

02-37 Output Terminal of I/O Extension Card (MO11) or (RA11)

02-38 Output Terminal of I/O Extension Card (RA12)

02-39 Output Terminal of I/O Extension Card (RA13)

02-40 Output Terminal of I/O Extension Card (RA14)

02-41 Output Terminal of I/O Extension Card (RA15)

02-42 Output Terminal of I/O Extension Card (MO16 Virtual Terminal)

02-43 Output Terminal of I/O Extension Card (MO17 Virtual Terminal)

02-44 Output Terminal of I/O Extension Card (MO18 Virtual Terminal)

02-45 Output Terminal of I/O Extension Card (MO19 Virtual Terminal)

02-46 Output Terminal of I/O Extension Card (MO20 Virtual Terminal)

Default: 0

Settings

0: No function
1: Indication during RUN
2: Operation speed reached
3: Desired frequency reached 1 (Pr.02-22)
4: Desired frequency reached 2 (Pr.02-24)
5: Zero speed (Frequency command)
6: Zero speed including STOP (Frequency command)
7: Over-torque 1 (Pr.06-06–06-08)
8: Over-torque 2 (Pr.06-09–06-11)
9: Drive is ready
10: Low voltage warning (Lv) (Pr.06-00)
11: Malfunction indication
12: Mechanical brake release (Pr.02-32)
13: Overheat warning (Pr.06-15)
14: Software brake signal indication (Pr.07-00)
15: PID feedback error (Pr.08-13, Pr.08-14)
16: Slip error (oSL)
17: Count value reached, does not return to 0 (Pr.02-20)
18: Count value reached, returns to 0 (Pr.02-19)
19: External interrupt B.B. input (Base Block)
20: Warning output
21: Over-voltage

22: Over-current stall prevention
23: Over-voltage stall prevention
24: Operation mode
25: Forward command
26: Reverse command
27: Output when current ≥ Pr.02-33
28: Output when current < Pr.02-33
29: Output when frequency ≥ Pr.02-34
30: Output when frequency < Pr.02-34
31: Y-connection for the motor coil
32: △ -connection for the motor coil
33: Zero speed (actual output frequency)
34: Zero speed including stop (actual output frequency)
35: Error output selection 1 (Pr.06-23)
36: Error output selection 2 (Pr.06-24)
37: Error output selection 3 (Pr.06-25)
38: Error output selection 4 (Pr.06-26)
40: Speed reached (including stop)
44: Low current output (use with Pr.06-71–Pr.06-73)
45: UVW output electromagnetic valve switch
46: Master dEb output
50: Output control for CANopen
51: Analog output control for RS-485 interface (InnerCOM / Modbus)
52: Output control for communication cards
53: Fire mode indication
54: Bypass fire mode indication
55: Motor 1 output
56: Motor 2 output
57: Motor 3 output
58: Motor 4 output
59: Motor 5 output
60: Motor 6 output
61: Motor 7 output
62: Motor 8 output
66: SO output logic A
67: Analog input level reached
68: SO output logic B
69: Preheating output indication

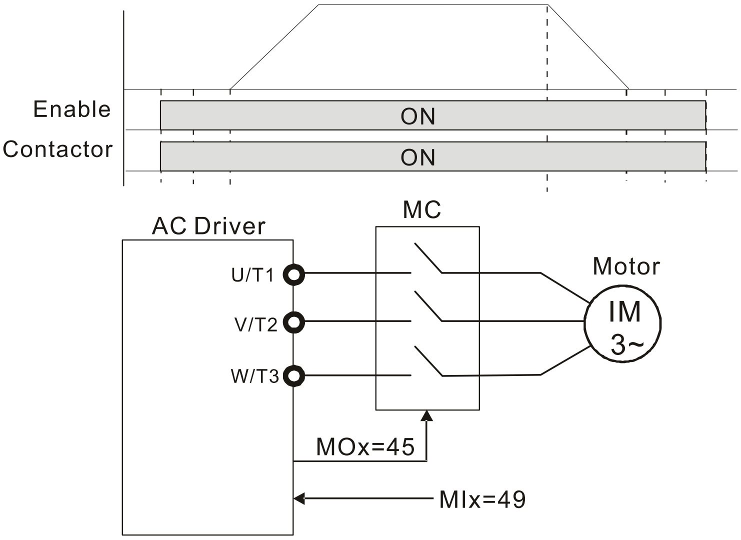
- 🕮 Use this parameter to set the function of the multi-function terminals.
- 🕮 Pr.02-36–Pr.02-41 requires additional extension cards to display the parameters, the choices of optional cards are EMC-D42A and EMC-R6AA.
- 🕮 The optional card EMC-D42A provides two output terminals, use with Pr.02-36–Pr.02-37.

- 🕮 The optional card EMC-R6AA provides six output terminals, use with Pr.02-36–Pr.02-41.
- 🕮 MO16–MO20 are virtual terminals, set the status of bit11–15 of Pr.02-18 to control these virtual terminals.

Summary of function settings

Take the normally open contact (N.O.) for example, ON: contact is closed, OFF: contact is open

Settings	Functions	Descriptions
0	No function	
1	Indication during RUN	Active when the drive is not in STOP.
2	Operation speed reached	Active when output frequency of the drive reaches the setting frequency.
3	Desired frequency reached 1 (Pr.02-22)	Active when the desired frequency (Pr.02-22) reached.
4	Desired frequency reached 2 (Pr.02-24)	Active when the desired frequency (Pr.02-24) reached.
5	Zero Speed (frequency command)	Active when frequency command = 0 (the drive must be in RUN status)
6	Zero Speed, includes Stop (frequency command)	Active when frequency command = 0 or stopped.
7	Over-torque 1	Active when the drive detects over-torque. Pr.06-07 sets the over-torque detection level, and Pr.06-08 sets the over-torque detection time. Refer to Pr.06-06–Pr.06-08.
8	Over-torque 2	Active when the drive detects over-torque. Pr.06-10 sets the over-torque detection level, and Pr.06-11 sets the over-torque detection time. Refer to Pr.06-09–06-11.
9	Drive is ready	Active when the drive is ON with no error detected.
10	Low voltage warning (Lv)	Active when the DC bus voltage is too low (refer to Pr.06-00 Low Voltage Level).
11	Malfunction indication	Active when fault occurs (except Lv stop).
12	Mechanical brake release (Pr.02-32)	Active when the drive runs after the set delayed time for Pr.02-32. This function must be used with DC brake function.
13	Overheat warning	Active when IGBT or heat sink overheats, to prevent the drive from shutting down due to overheating (refer to Pr.06-15).
14	Software brake signal indication	Active when the soft brake function is ON (refer to Pr.07-00).
15	PID feedback error	Active when the PID feedback signal error is detected.
16	Slip Error (oSL)	Active when the slip error is detected.
17	Count value reached, does not return to 0 (Pr.02-20)	When the drive executes external counter, this contact is active if the count value is equal to the setting value for Pr.02-20. This contact is not active when the setting value for Pr.02-20 > Pr.02-19.
18	Counter value reached, returns to 0 (Pr.02-19)	When the drive executes the external counter, this contact is active if the count value is equal to the setting value for Pr.02-19.
19	External interrupt B.B. input (Base Block)	Active when external interrupt (B.B.) stop output occurs in the drive.
20	Warning output	Active when a warning is detected.
21	Over-voltage	Active when over-voltage is detected. (Refer to over-voltage descriptions in Chapter 14 Fault Codes for action levels.)
22	Over-current stall prevention	Active when over-current stall prevention is detected.
23	Over-voltage stall prevention	Active when over-voltage stall prevention is detected.

Settings	Functions	Descriptions
24	Operation mode indication	Active when the operation command is not controlled by external terminal. (Pr.00-21 ≠ 0)
25	Forward command	Active when the operation direction is forward.
26	Reverse command	Active when the operation direction is reverse.
27	Output when current ≥ Pr.02-33	Active when the current is ≥ Pr.02-33.
28	Output when current < Pr.02-33	Active when the current is < Pr.02-33
29	Output when frequency ≥ Pr.02-34	Active when the frequency is ≥ Pr.02-34.
30	Output when frequency < Pr.02-34	Active when the frequency is < Pr.02-34.
31	Y-connection for the motor coil	Active when Pr.05-24 = 1, the frequency output is lower than Pr.05-23 minus 2 Hz, and the time is longer than Pr.05-25.
32	∆-connection for the motor coil	Active when Pr.05-24 = 1, the frequency output is higher than Pr.05-23 plus 2 Hz, and the time is longer than Pr.05-25.
33	Zero speed (actual output frequency)	Active when the actual output frequency is 0 (the drive is in RUN mode).
34	Zero speed including stop (actual output frequency)	Active when the actual output frequency is 0 or stopped.
35	Error output selection 1 (Pr.06-23)	Active when Pr.06-23 is ON.
36	Error output selection 2 (Pr.06-24)	Active when Pr.06-24 is ON.
37	Error output selection 3 (Pr.06-25)	Active when Pr.06-25 is ON.
38	Error output selection 4 (Pr.06-26)	Active when Pr.06-26 is ON.
40	Speed reached (including STOP)	Active when the output frequency reaches the setting frequency or stopped.
44	Low current output	This function needs to be used with Pr.06-71–Pr.06-73
45	UVW output electromagnetic valve switch	Use this function with external terminal input = 49 (drive enabled) and external terminal output = 45 (electromagnetic valve enabled), and then the electromagnetic valve is ON or OFF according to the status of the drive.  Enable Contactor ON ON AC Driver MC Motor U/T1 V/T2 W/T3 IM 3~ MOx=45 MIx=49

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>46</td><td>Master dEb output</td><td>When dEb rises at master, MO sends a dEb signal to the slave. Output the message when the master triggers dEb. This ensures that the slave also triggers dEb. Then slave follows the deceleration time of the master to stop simultaneously with the master.</td></tr>
<tr><td>50</td><td>Output control for CANopen</td><td>Control the multi-function output terminals through CANopen.
To control RY2, set Pr.02-14 = 50.
The mapping table of the CANopen DO is shown in the following table:
<table>
<tr><th>Physical terminal</th><th>Setting of related parameters</th><th>Attribute</th><th>Corresponding Index</th></tr>
<tr><td>RY1</td><td>Pr.02-13 = 50</td><td>RW</td><td>The bit0 at 2026-41</td></tr>
<tr><td>RY2</td><td>Pr.02-14 = 50</td><td>RW</td><td>The bit1 at 2026-41</td></tr>
<tr><td>RY3</td><td>Pr.02-15 = 50</td><td>RW</td><td>The bit2 at 2026-41</td></tr>
<tr><td>MO10/RY10</td><td>Pr.02-36 = 50</td><td>RW</td><td>The bit5 at 2026-41</td></tr>
<tr><td>MO11/RY11</td><td>Pr.02-37 = 50</td><td>RW</td><td>The bit6 at 2026-41</td></tr>
<tr><td>RY12</td><td>Pr.02-38 = 50</td><td>RW</td><td>The bit7 at 2026-41</td></tr>
<tr><td>RY13</td><td>Pr.02-39 = 50</td><td>RW</td><td>The bit8 at 2026-41</td></tr>
<tr><td>RY14</td><td>Pr.02-40 = 50</td><td>RW</td><td>The bit9 at 2026-41</td></tr>
<tr><td>RY15</td><td>Pr.02-41 = 50</td><td>RW</td><td>The bit10 at 2026-41</td></tr>
</table>
Refer to Section 15-3-5 for more information.</td></tr>
<tr><td>51</td><td>Analog output control for RS-485 interface</td><td>For RS-485 interface (InnerCOM / Modbus) communication control output.
<table>
<tr><th>Physical terminal</th><th>Setting of related parameters</th><th>Attribute</th><th>Corresponding Index</th></tr>
<tr><td>RY1</td><td>Pr.02-13 = 51</td><td>RW</td><td>The bit0 at 2640h</td></tr>
<tr><td>RY2</td><td>Pr.02-14 = 51</td><td>RW</td><td>The bit1 at 2640h</td></tr>
<tr><td>MO1</td><td>Pr.02-16 = 51</td><td>RW</td><td>The bit3 at 2640h</td></tr>
<tr><td>MO2</td><td>Pr.02-17 = 51</td><td>RW</td><td>The bit 4 at 2640h</td></tr>
<tr><td>MO10/RA10</td><td>Pr.02-36 = 51</td><td>RW</td><td>The bit5 at 2640h</td></tr>
<tr><td>MO11/RA11</td><td>Pr.02-37 = 51</td><td>RW</td><td>The bit6 at 2640h</td></tr>
<tr><td>RY12</td><td>Pr.02-38 = 51</td><td>RW</td><td>The bit7 at 2640h</td></tr>
<tr><td>RY13</td><td>Pr.02-39 = 51</td><td>RW</td><td>The bit8 at 2640h</td></tr>
<tr><td>RY14</td><td>Pr.02-40 = 51</td><td>RW</td><td>The bit9 at 2640h</td></tr>
<tr><td>RY15</td><td>Pr.02-41 = 51</td><td>RW</td><td>The bit10 at 2640h</td></tr>
</table></td></tr>
<tr><td>52</td><td>Output control for communication cards</td><td>Control the output through communication cards (CMC-EIP01, CMC-PN01 and CMC-DN01)
<table>
<tr><th>Physical terminal</th><th>Setting of related parameters</th><th>Attribute</th><th>Corresponding Index</th></tr>
<tr><td>RY1</td><td>Pr.02-13 = 52</td><td>RW</td><td>The bit0 at 2640</td></tr>
<tr><td>RY2</td><td>Pr.02-14 = 52</td><td>RW</td><td>The bit1 at 2640</td></tr>
<tr><td>RY3</td><td>Pr.02-15 = 52</td><td>RW</td><td>The bit2 at 2640</td></tr>
<tr><td>MO10/RY10</td><td>Pr.02-36 = 52</td><td>RW</td><td>The bit5 at 2640</td></tr>
<tr><td>MO11/RY11</td><td>Pr.02-37 = 52</td><td>RW</td><td>The bit6 at 2640</td></tr>
<tr><td>RY12</td><td>Pr.02-38 = 52</td><td>RW</td><td>The bit7 at 2640</td></tr>
<tr><td>RY13</td><td>Pr.02-39 = 52</td><td>RW</td><td>The bit8 at 2640</td></tr>
<tr><td>RY14</td><td>Pr.02-40 = 52</td><td>RW</td><td>The bit9 at 2640</td></tr>
<tr><td>RY15</td><td>Pr.02-41 = 52</td><td>RW</td><td>The bit10 at 2640</td></tr>
</table></td></tr>
<tr><td>53</td><td>Fire mode indication</td><td>This function is enabled when setting 58 or 59 is enabled.</td></tr>
<tr><td>54</td><td>Bypass fire mode indication</td><td>The contact works when bypass function is enabled in the fire mode.</td></tr>
<tr><td>55</td><td>Motor 1 output</td><td rowspan="4">When setting multi-motor circulative function, the multi-function output terminal automatically sets up Pr.02-13–Pr.02-15 and Pr.02-36–Pr.02-40 in accordance with the setting for Pr.12-01.</td></tr>
<tr><td>56</td><td>Motor 2 output</td></tr>
<tr><td>57</td><td>Motor 3 output</td></tr>
<tr><td>58</td><td>Motor 4 output</td></tr>
</table>

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>59</td><td>Motor 5 output</td><td rowspan="4"></td></tr>
<tr><td>60</td><td>Motor 6 output</td></tr>
<tr><td>61</td><td>Motor 7 output</td></tr>
<tr><td>62</td><td>Motor 8 output</td></tr>
<tr><td>66</td><td>SO output logic A (N.O.)</td><td rowspan="2">
<table>
<tr><th rowspan="2">Status of drive</th><th colspan="2">Status of safety output</th></tr>
<tr><th>N.O. (MOx = 66)</th><th>N.C. (MOx = 68)</th></tr>
<tr><td>Normal</td><td>Broken circuit (Open)</td><td>Short circuit (Close)</td></tr>
<tr><td>STO</td><td>Short circuit (Close)</td><td>Broken circuit (Open)</td></tr>
<tr><td>STL1–STL3</td><td>Short circuit (Close)</td><td>Broken circuit (Open)</td></tr>
</table>
</td></tr>
<tr><td>68</td><td>SO output logic B (N.C.)</td></tr>
<tr><td>67</td><td>Analog input level reached</td><td>The multi-function output terminals operate when the analog input level is between the high level and the low level.
Pr.03-44: Select one of the analog signal channels (AVI1, ACI, and AVI2) to be compared.
Pr.03-45: The high level for the analog input, default is 50.00%
Pr.03-46: The low level for the analog input, default is 10.00%.
If analog input > Pr.03-45, the multi-function output terminal operates.
If analog input < Pr.03-46, the multi-function output terminal stops output.</td></tr>
<tr><td>69</td><td>Preheating output indication</td><td>Active when the preheating is detected.</td></tr>
</table>

🕮 Add Remote IO function to directly control the drive's AO / DO and read current AI / DI status through the standard Modbus, the corresponding indexes of 26xx is as following:

	bit15	bit14	bit13	bit12	bit11	bit10	bit9	bit8	bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
2600h	MI15	MI14	MI13	MI12	MI11	MI10	MI8	MI7	MI6	MI5	MI4	MI3	MI2	MI1	REV	FWD
2640h	-	-	-	-	-	MO15	MO14	MO13	MO12	MO11	MO10	-	-	RY3	RY2	RY1
2660h	AVI1		-	-	-	-	-	-	-	-	-	-	-	-	-	-
2661h	ACI		-	-	-	-	-	-	-	-	-	-	-	-	-	-
2662h	AVI2		-	-	-	-	-	-	-	-	-	-	-	-	-	-
266Ah	AI10		-	-	-	-	-	-	-	-	-	-	-	-	-	-
266Bh	AI11		-	-	-	-	-	-	-	-	-	-	-	-	-	-
26A0h	AFM1			-	-	-	-	-	-	-	-	-	-	-	-	-
26A1h	AFM2			-	-	-	-	-	-	-	-	-	-	-	-	-
26AAh	AO10			-	-	-	-	-	-	-	-	-	-	-	-	-
26ABh	AO11			-	-	-	-	-	-	-	-	-	-	-	-	-

In addition, the AI and DI values can be read directly, while DO and AO must be controlled by Modbus under corresponding parameter function. The related parameter definition is as following:

DO

Terminal	Pr. Setting	Direct control the index corresponded to Modbus
RY1	Pr.02-13 = 51	bit0 of 2640h
RY2	Pr.02-14 = 51	bit1 of 2640h
RY3	Pr.02-15 = 51	bit2 of 2640h
MO10 / RY10	Pr.02-36 = 51	bit5 of 2640h
MO11 / RY11	Pr.02-37 = 51	bit6 of 2640h
RY12	Pr.02-38 = 51	bit7 of 2640h
RY13	Pr.02-39 = 51	bit8 of 2640h
RY14	Pr.02-40 = 51	bit9 of 2640h
RY15	Pr.02-41 = 51	bit10 of 2640h

AO

Terminal	Pr. Setting	Direct control the index corresponded to Modbus
AFM1	Pr.03-20 = 21	The value of 26A0h
AFM2	Pr.03-23 = 21	The value of 26A1h

Terminal	Pr. Setting	Direct control the index corresponded to Modbus
AFM10	Pr.14-12 = 21	The value of 26AAh
AFM11	Pr.14-13 = 21	The value of 26ABh

02-18 Multi-function Output Direction

Default: 0000h

Settings 0000h–FFFFh (0: N.O.; 1: N.C.)

- This parameter is in hexadecimal.
- This parameter is set by a bit. If a bit is 1, the corresponding multi-function output acts in an opposite way.

  Example: Assume Pr.02-13 = 1 (indication when the drive is operating). If the output is positive, the bit is set to 0, and then Relay is ON when the drive runs and is OFF when the drive stops. On the contrary, if the output is negative, and the bit is set to 1, then the Relay is OFF when the drive runs and is ON when the drive stops.

bit15	bit14	bit13	bit12	bit11	bit10	bit9	bit8	bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
MO20	MO19	MO18	MO17	MO16	MO15	MO14	MO13	MO12	MO11	MO10	Reserved		RY3	RY2	RY1

02-19 Terminal Counting Value Reached (return to 0)

Default: 0

Settings 0–65500

- You can set the input point for the counter using the multi-function terminal MI6 as a trigger terminal (set Pr.02-06 to 23). When counting is completed, the specified multi-function output terminal is activated (Pr.02-13, Pr.02-14, Pr.02-36, Pr.02-37 are set to 18), and Pr.02-19 cannot be set to 0 at this time.

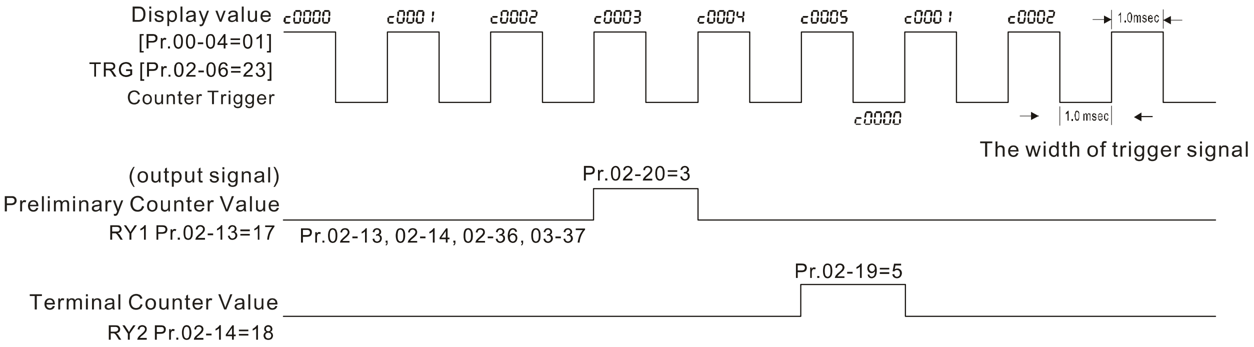
  Example: When the displayed value is c5555, the drive count is 5,555 times. If the displayed value is c5555•, the actual count value is 55,550–55,559.

02-20 Preliminary Counting Value Reached (does not return to 0)

Default: 0

Settings 0–65500

- When the count value counts from 1 to reach this value, the corresponding multi-function output terminal is activated (Pr. 02-13, Pr.02-14, Pr.02-36, Pr.02-37 are set to 17). You can use this parameter as the end of counting to make the drive run from the low speed to stop.



✓ **02-22** Desired Frequency Reached 1

✓ **02-24** Desired Frequency Reached 2

Default: 60.00 / 50.00

Settings 0.00–599.00 Hz

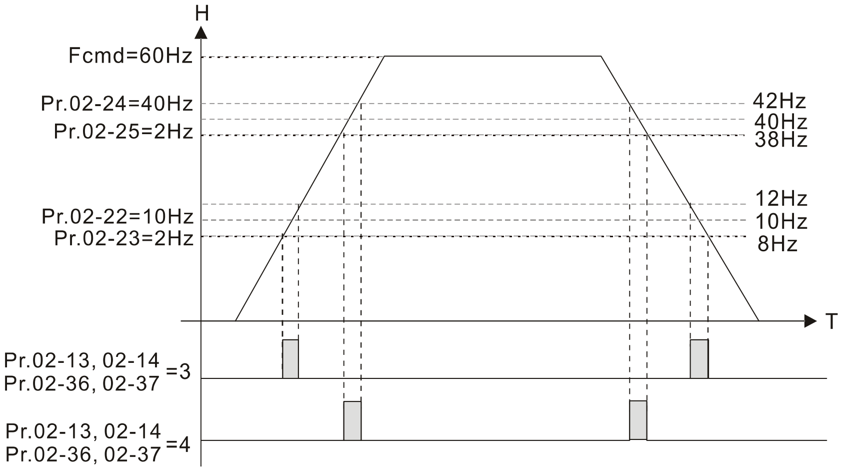
✓ **02-23** The Width of the Desired Frequency Reached 1

✓ **02-25** The Width of the Desired Frequency Reached 2

Default: 2.00

Settings 0.00–599.00 Hz

🕮 Once the output speed (frequency) reaches the desired speed (frequency), if the corresponding multi-function output terminal is set to 3–4 (Pr.02-13, Pr.02-14, Pr.02-36, and Pr.02-37), this multi-function output terminal is “closed”.

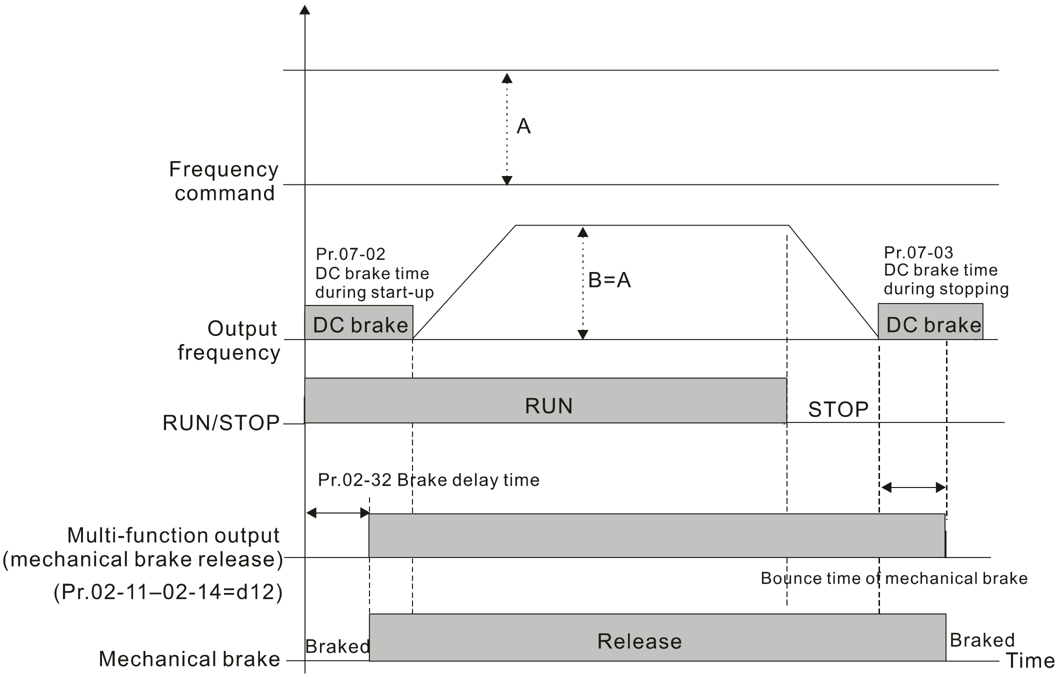


02-32 Brake Delay Time

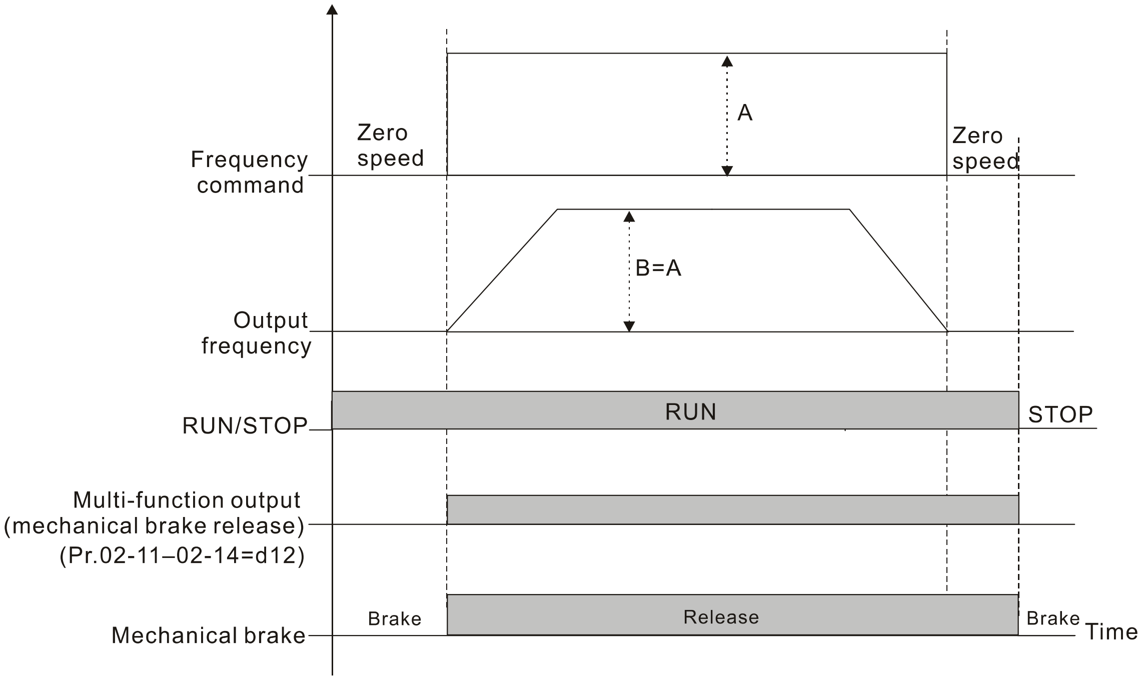
Default: 0.000

Settings 0.000–65.000 sec.

🕮 When the AC motor drive runs after the setting delay time of Pr.02-32, the corresponding multi-function output terminal (12: mechanical brake release) is “closed”. The function must be used with DC brake.



🕮 This parameter is invalid if it is used without DC brake. Refer to the following operation timing.



✔ 02-33 Output Current Level Setting for Multi-function Output Terminals

Default: 0

Settings 0–150%

🕮 When the drive outputs current higher than or equal to Pr.02-33 (≥ Pr.02-33), the multi-function output parameters active (Pr.02-13, Pr.02-14, and Pr.02-15 are set to 27).

🕮 When the drive outputs current lower than Pr.02-33 (< Pr.02-33), the multi-function output parameters active (Pr.02-13, Pr.02-14, and Pr.02-15 are set to 28).

✔ 02-34 Output Frequency Setting for Multi-function Output Terminals

Default: 3.00

Settings 0.00–599.00 Hz

🕮 When the drive outputs frequency higher than or equal to Pr.02-34 (actual output frequency H ≥ Pr.02-34), the multi-function terminals active (Pr.02-13, Pr.02-14 and Pr.02-15 are set to 29).

🕮 When the drive outputs frequency lower than Pr.02-34 (actual output frequency H < Pr.02-34), the multi-function terminals active (Pr.02-13, Pr.02-14 and Pr.02-15 are set to 30).

✔ 02-35 External Operation Control Selection after Reset and Activate

Default: 0

Settings 0: Disable
1: Drive runs if the RUN command remains after reset or re-boot

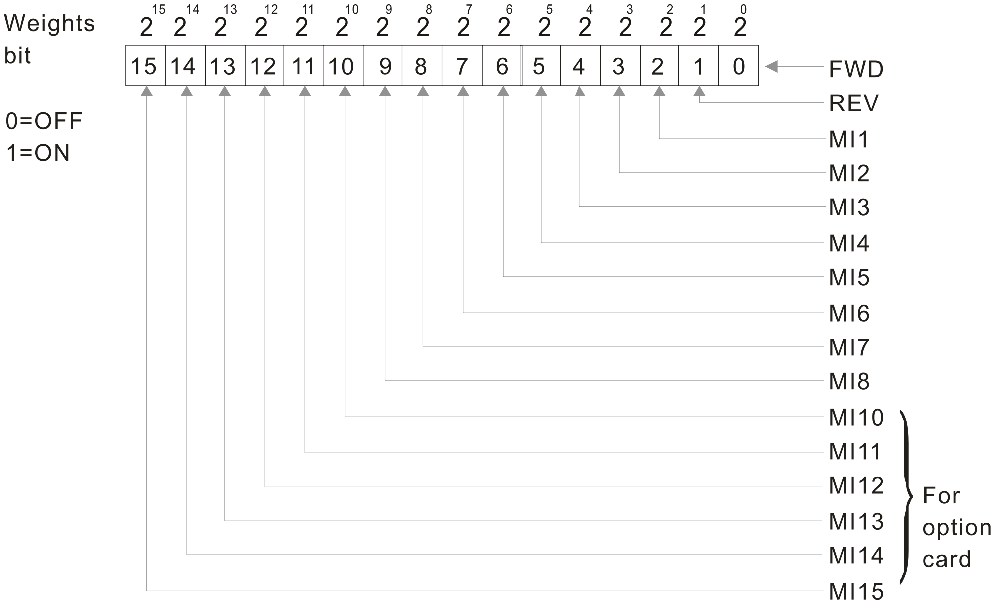
🕮 Setting 1: **The drive automatically executes the RUN command under the following circumstances, pay extra attention on this.**

- Status 1: After the drive is **powered on** and **the external terminal for RUN stays ON**, the drive runs.
- Status 2: After clearing a fault once a fault is detected and the external terminal for RUN stays ON, you can run the drive by pressing the RESET key.

02-50 Display the Status of Multi-function Input Terminal

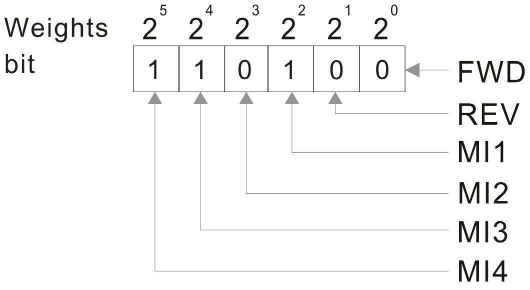
Default: Read only

Settings Monitoring status of multi-function input terminal



Example:

When Pr.02-50 displays 0034h (hex), (that is, the value is 110100 (binary), it means that MI1, MI3 and MI4 are ON.



0=OFF
1=ON

Settings

$= \text{bit5}\times 2^5+\text{bit4}\times 2^4+\text{bit2}\times 2^2$

$= 1\times 2^5+1\times 2^4+1\times 2^2$

$=32+16+4 =52$

NOTE

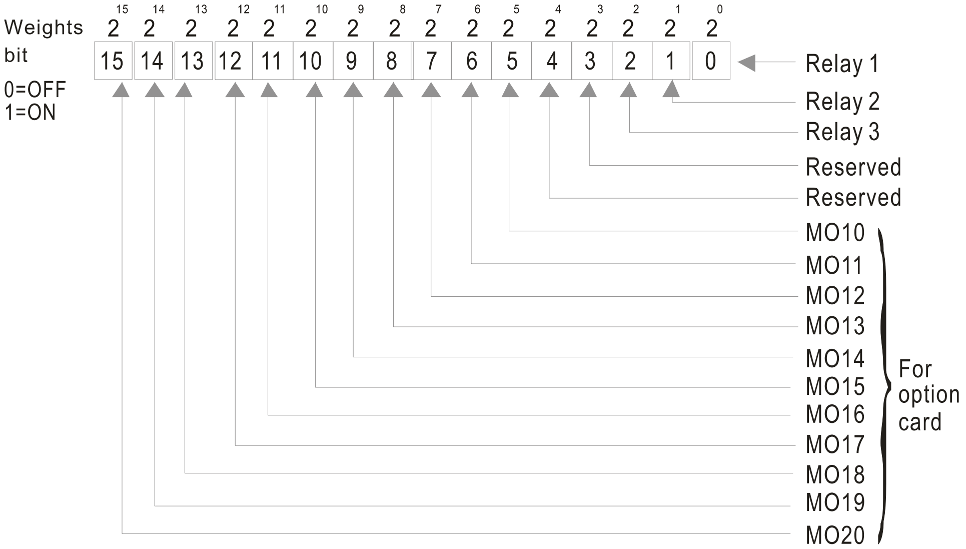
$2^5=32$ $2^4=16$ $2^3=8$ $2^2=4$

$2^1=2$ $2^0=1$

02-51 Display the Status of Multi-function Output Terminal

Default: Read only

Settings Monitoring status of multi-function output terminal



NOTE

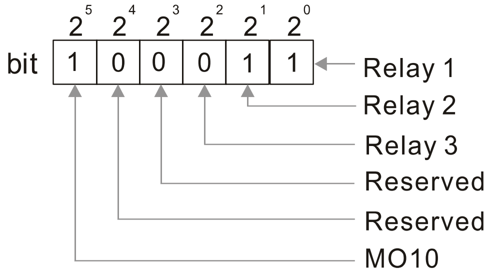
$2^7=128$ $2^6=64$

$2^5=32$ $2^4=16$ $2^3=8$

$2^2=4$ $2^1=2$ $2^0=1$

📖 Example:

When Pr.02-51 displays 0023h (hex) (that is, the value is 100011 (binary)), it means that RY1, RY2 and MO10 are ON.



0=OFF
1=ON
Settings
$=bit5 \times 2^5+bit1 \times 2^1 + bit0 \times 2^0$
$=1 \times 2^5+1 \times 2^1 + 1 \times 2^0$
$=32 + 2 + 1$
$=35$

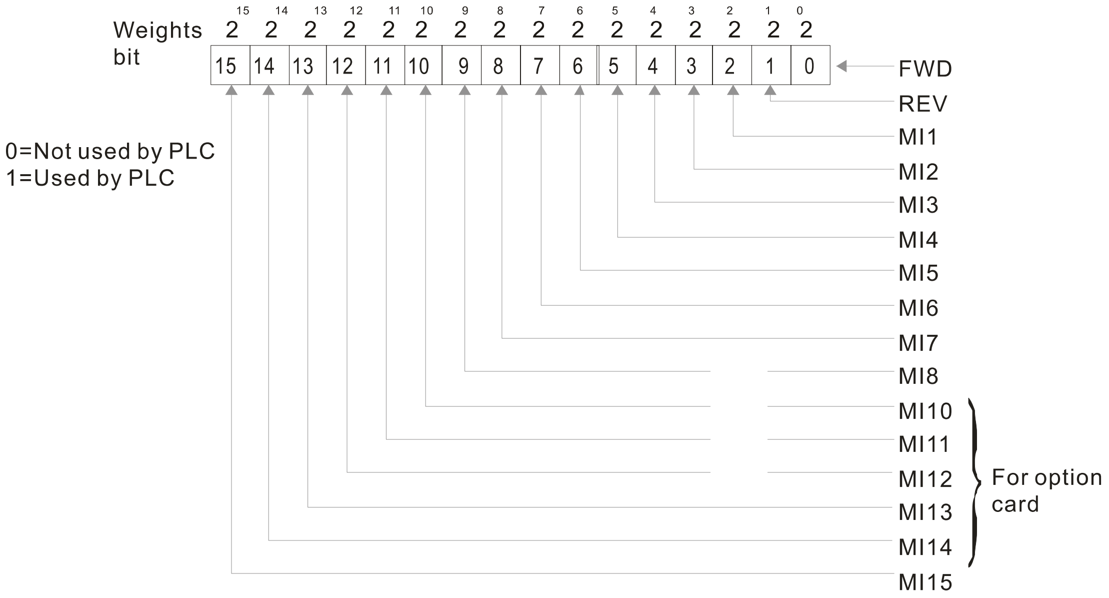
NOTE
2^5=32 2^4=16 2^3=8 2^2=4
2^1=2 2^0=1

02-52 Display the External Multi-function Input Terminals Used by PLC

Default: Read only

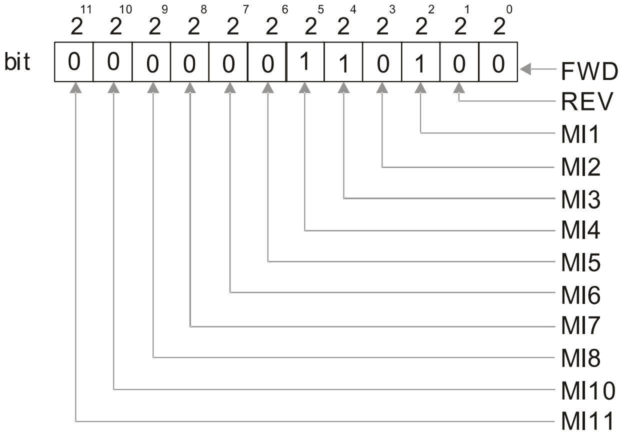
Settings Monitoring status of PLC external output terminal

📖 Pr.02-52 displays the external multi-function input terminals that used by PLC.



📖 Example:

When Pr.02-52 displays 0034h (hex) (that is, the value is 110100 (binary)), it means that MI1, MI3 and MI4 are used by PLC.



0=Not used by PLC
1=Used by PLC
Display value
$= bit5 \times 2^5+bit4 \times 2^4+bit2 \times 2^2$
$= 1 \times 2^5+1 \times 2^4+1 \times 2^2$
$=32+16+4=52$

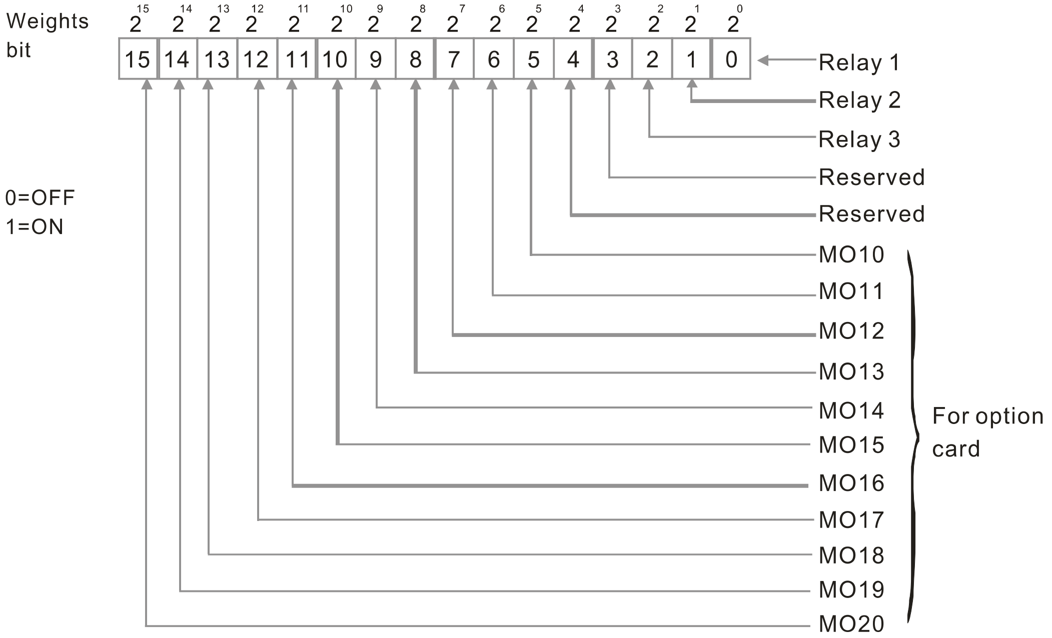
Note
2^{14}=16384 2^{13}=8192 2^{12}=4096
2^{11}=2048 2^{10}=1024 2^9=512
2^8=256 2^7=128 2^6=64
2^5=32 2^4=16 2^3=8
2^2=4 2^1=2 2^0=1

02-53 Display the External Multi-function Output Terminals Used by PLC

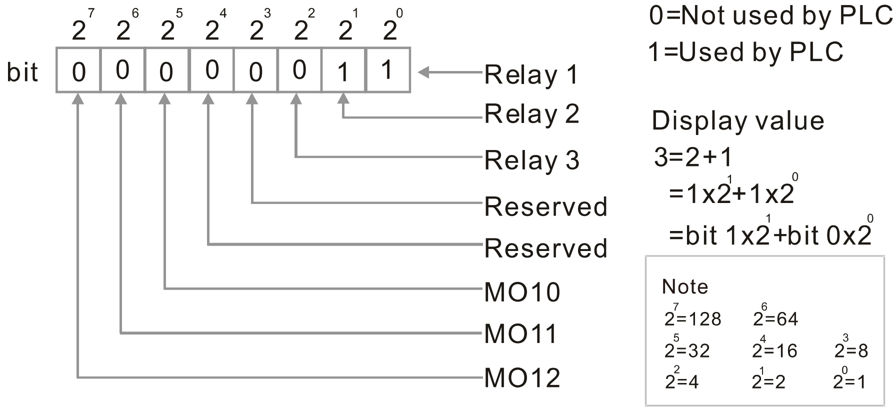
Default: Read only

Settings	Monitoring status of PLC external multi-function output terminal

📖 Pr.02-53 displays the external multi-function output terminal that used by PLC.



📖 Example:
When Pr.02-53 displays 0003h (hex) (that is, the value is 0011 (binary)), it means that RY1 and RY2 are used by PLC.



02-54 Display the Frequency Command Executed by External Terminal

Default: Read only

Settings	0.00–599.00 Hz (Read only)

📖 When you set the source of the Frequency command as the external terminal, if Lv or Fault occurs, the external terminal Frequency command is saved in this parameter.

02-70 IO Card Types

Default: Read only

Settings	1: EMC-BPS01
	4: EMC-D611A
	5: EMC-D42A
	6: EMC-R6AA
	11: EMC-A22A

02-72 Preheating Output Current Level

Default: 0

Settings 0–100%

When a motor drive is not in operation (STOP) and is placed in a cold and humid environment, enabling the preheating function to output DC current to heat up the motor drive can prevent the invasion of humidity into the motor drive, which creates condensation affects the normal function of the motor drive.

Sets the output current level from the motor drive to the motor after enabling the preheating. The percentage of the preheating DC current is 100% of the rated current of the motor drive (Pr.05-01, Pr.05-13 and Pr.05-34). When setting this parameter, slowly increase the percentage to reach the sufficient preheating temperature.

02-73 Preheating Output Cycle

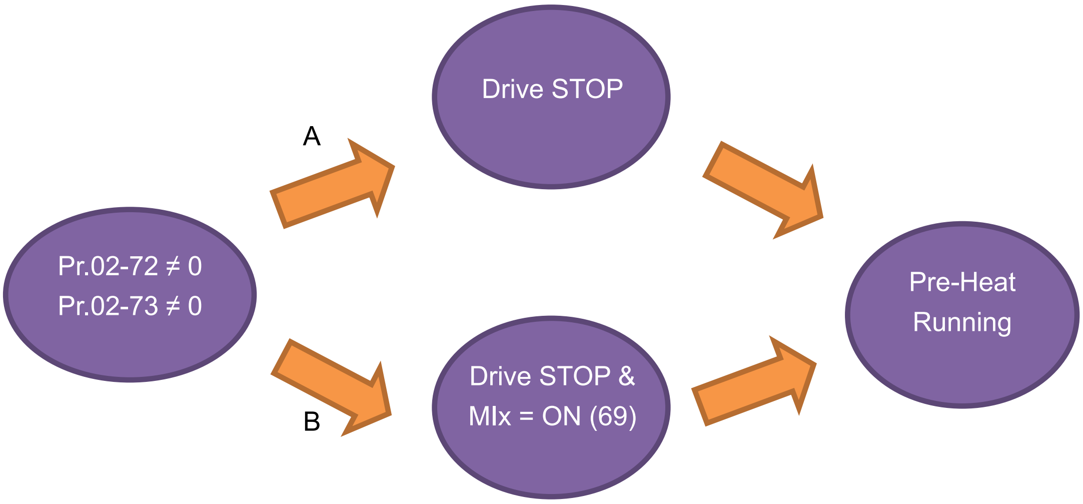
Default: 0

Settings 0–100%

Sets the output current cycle of preheating. 0–100% corresponds to 0–10 seconds. When set to 0%, there is no output current. When set to 100%, there is a continuous output. For example, when set to 50%, a cycle of preheating goes from OFF (5 seconds) to ON (5 seconds), and vice versa.

Related Parameters of Preheating

Parameter	Description	Setting Range	Explanation
Pr.02-72	Output current level of preheating	0–100% (rated current of the motor) 0% No output	Output current level of preheating
Pr.02-73	Output cycle of preheating	0–100% (0–10 sec.) 0% No output 100% Continuous output	Output cycle of preheating
Pr.02-01–08 Pr.02-26–31	Multi-input function commands (MFI)	69 Preheating command	Enable or disable the preheating
Pr.02-13–15 Pr.02-36–46	Multi-output function commands (MFO)	69 Output command of preheating	Indication of the preheating

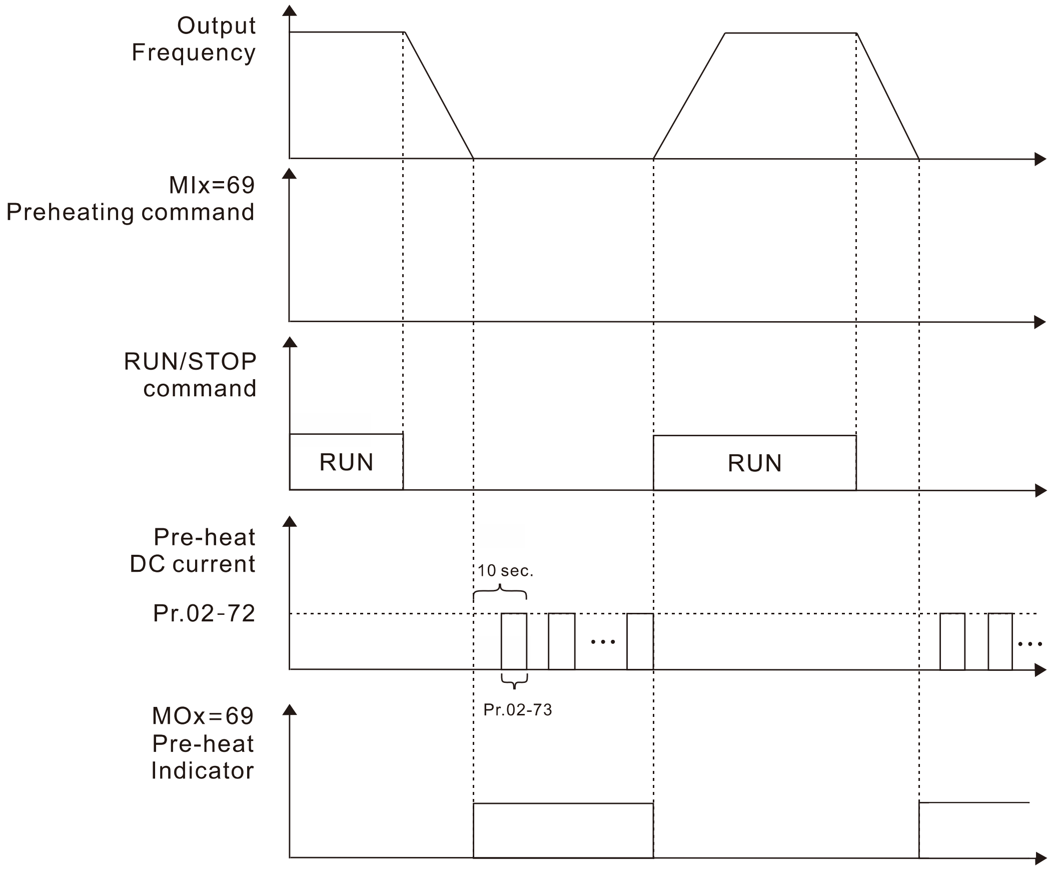


- Enable preheating: When Pr.02-72 and Pr.02-73 are NOT set to zero.
- Preheating function A: If Pr.07-72 and Pr.07-23 are set before the motor drive stops operation (STOP), preheating is enabled right after the motor drive stops. However, if Pr.07-72 and Pr.07-73 are set after the motor drives stops operation, preheating is not enabled. Preheating is enabled only when the motor drive stops again or restarts.
- Preheating function B: When the motor drive is in operation (RUN) or stops operating (STOP), set Pr.02-72 and Pr.02-73 between 1–100% and set MIx = 69 and MIx = ON. Preheating is enabled whenever the motor drive stops; no matter the motor drive is in operation (RUN) or stops operating (STOP).
- Preheating priority: if preheating function A and B are both enabled, function B takes priority.

Sequential Diagram of the Preheating Function:

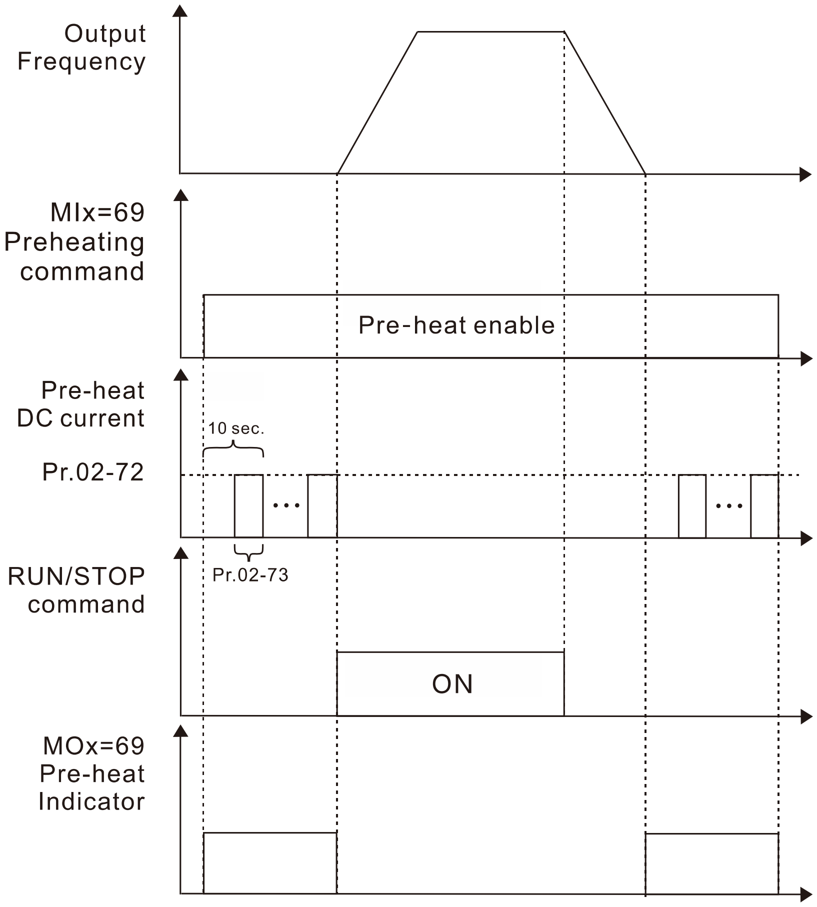
1. Setting parameters to enable preheating (Function A)

   Set Pr.02-72 and Pr.02-73 not equal to zero (50% in the diagram) and stop running the motor drive, then preheating is enabled to output DC current. At the same time, MOx (Output Command of Preheating) is ON (MOx = 69). Once the drive is rebooted, the preheating function is enabled right away. The sequence of preheating goes from OFF (5 seconds) to ON (5 seconds). When the motor is in operation (RUN), the preheating function is OFF even it is enabled. Meanwhile, MOx is OFF (MOx = 69) and the preheating is enabled when the motor drive stops.



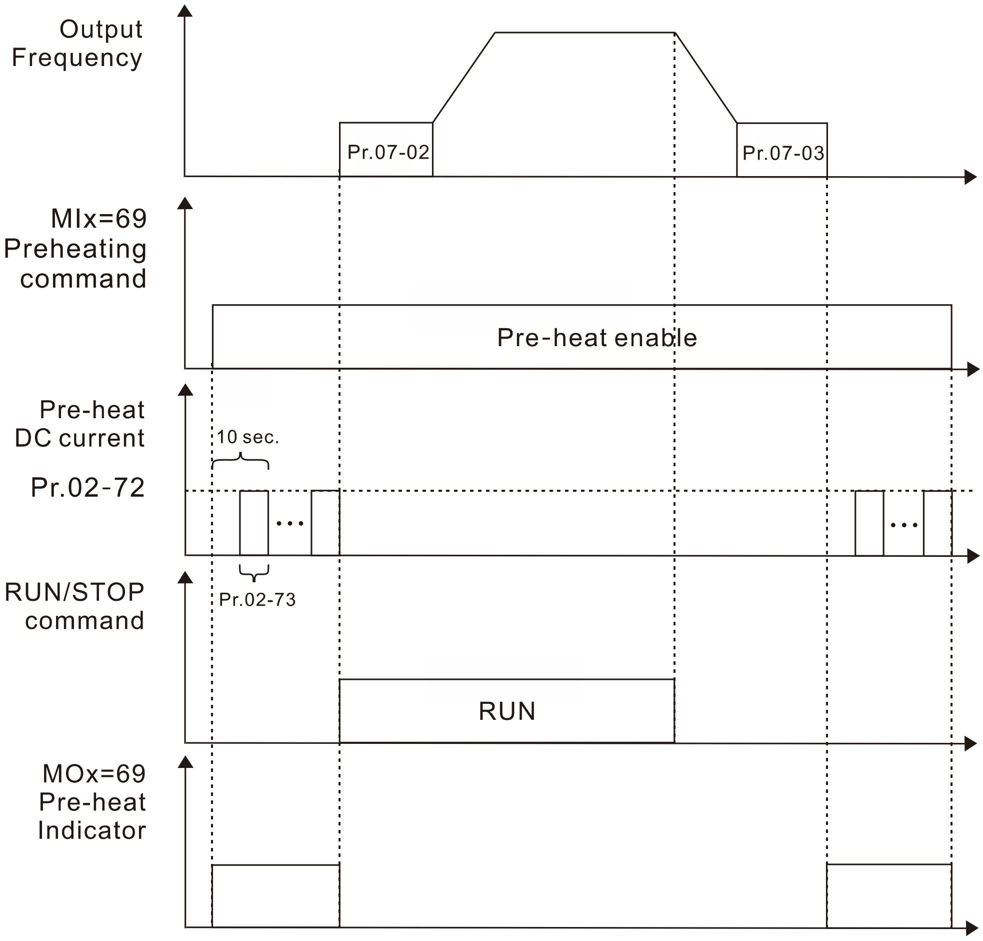
2. Enable preheating via multi-input terminals (Function B)

Set Pr.02-72 and Pr.02-73 (50% in the diagram) not equal to zero and set MIx = 69, and MIx = ON, then Function B takes priority to enable / disable preheating on the motor drive. At the same time, enabling preheating by parameters is automatically invalid. If, at this moment, the motor drive is already STOP, the preheating function is enabled to output DC current and the MOx (Output Command of Preheating) is ON (MOx = 69). The sequence of preheating goes from OFF (5 seconds) to ON (5 seconds). When the motor is in operation (RUN), the preheating function is OFF even it is enabled. Meanwhile, MOx is OFF (MOx = 69) and the preheating is enabled when the motor drive stops.



3. Enable DC brake function

DC brake and preheating are enabled at the same time. The motor drive operates with the same logic described above for preheating. The only difference is that no matter the motor drive is in operation (RUN) or stops operating (STOP), DC brake enables first. When the motor drive stops, preheating is activated.



03 Analog Input / Output Parameter

✎ You can set this parameter during operation.

✎ **03-00** AVI1 Analog Input Selection

Default: 1

✎ **03-01** ACI Analog Input Selection

Default: 0

✎ **03-02** AVI2 Analog Input Selection

Default: 0

Settings
0: No function
1: Frequency command
4: PID target value
5: PID feedback signal
6: Thermistor (PTC) input value
11: PT100 thermistor input value
13: PID compensation value

📖 When you use analog input as the PID reference target input, you must set Pr.00-20 to 2 (external analog input).

Setting method 1: Pr.03-00–03-02 set 1 as PID reference target input.

If the setting value 1 and setting value 4 exist at the same time, the AVI1 input has highest priority to become the PID reference target input value.

📖 When you use analog input as the PID compensation value, you must set Pr.08-16 to 1 (source of PID compensation value is analog input). You can see the compensation value with Pr.08-17.

📖 When using the Frequency command, the corresponding value for 0– ±10 V / 4–20 mA is 0–maximum output frequency (Pr.01-00).

📖 If the settings for Pr.03-00–Pr.03-02 are the same, the AVI1 input has highest priority.

✎ **03-03** AVI1 Analog Input Bias

Default: 0.0

Settings -100.0–100.0%

📖 Sets the corresponding AVI1 voltage for the external analog input 0.

✎ **03-04** ACI Analog Input Bias

Default: 0.0

Settings -100.0–100.0%

📖 Sets the corresponding ACI current for the external analog input 0.

✎ **03-05** AVI2 Analog Voltage Input Bias

Default: 0.0

Settings -100.0–100.0%

📖 Sets the corresponding AVI2 voltage for the external analog input 0.

📖 The corresponding external input voltage / current signal and the set frequency is 0–10 V (4–20 mA) corresponds to 0–maximum frequency (Pr.01-00).

03-07 AVI1 Positive / Negative Bias Mode

03-08 ACI Positive / Negative Bias Mode

03-09 AVI2 Positive / Negative Bias Mode

Default: 0

Settings 0: No bias

1: Lower than or equal to bias

2: Greater than or equal to bias

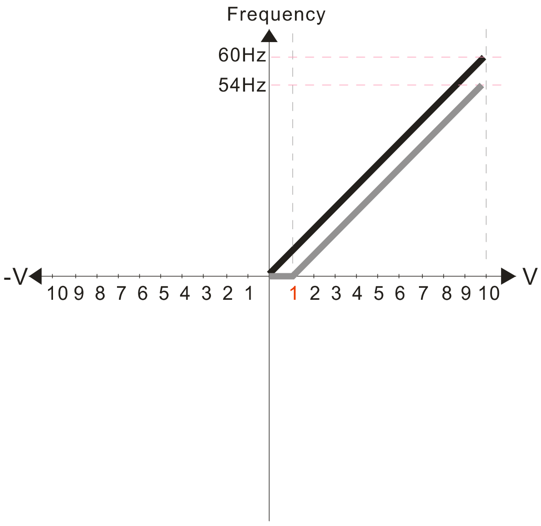
3: The absolute value of the bias voltage while serving as the center

4: Serve bias as the center

Using negative bias to set the frequency greatly reduces the noise interference. In a noisy environment, do NOT use signals less than 1 V to set the drive's operation frequency.

In the diagram below: Black line: Curve with no bias. Gray line: curve with bias

Diagram 1



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)

0: No bias

1: Lower than or equal to bias

2: Greater than or equal to bias

3: The absolute value of the bias voltage while serving as the center

4: Serve bias as the center

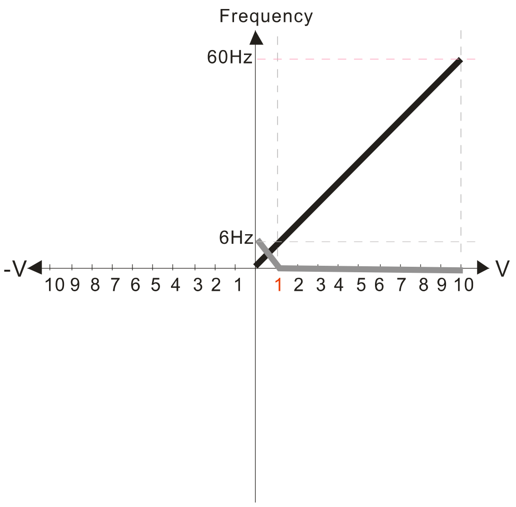
Pr.03-10 (Analog Frequency Command for Reverse Run)

0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.

1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Pr.03-11 Analog Input Gain (AVI1)= 100%

Diagram 2



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)

0: No bias

1: Lower than or equal to bias

2: Greater than or equal to bias

3: The absolute value of the bias voltage while serving as the center

4: Serve bias as the center

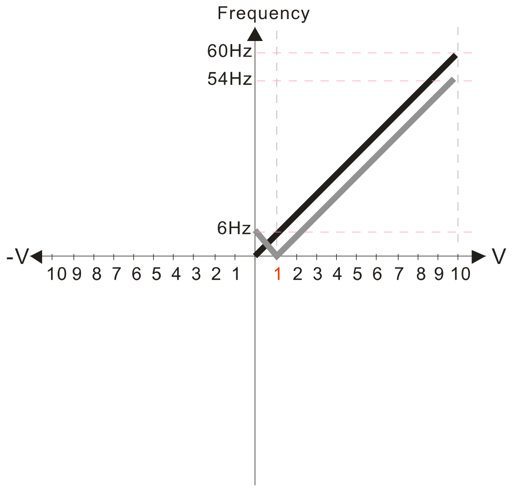
Pr.03-10 (Analog Frequency Command for Reverse Run)

0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.

1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Pr.03-11Analog Input Gain (AVI1)=100%

Diagram 3



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)

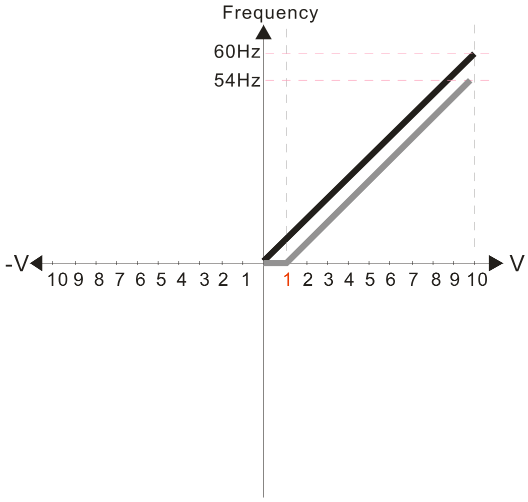
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-10 (Analog Frequency Command for Reverse Run)

0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.
1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 4



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)

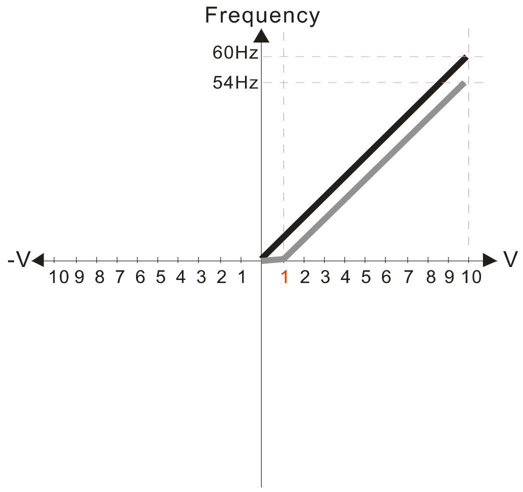
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-10 (Analog Frequency Command for Reverse Run)

0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.
1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 5



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)

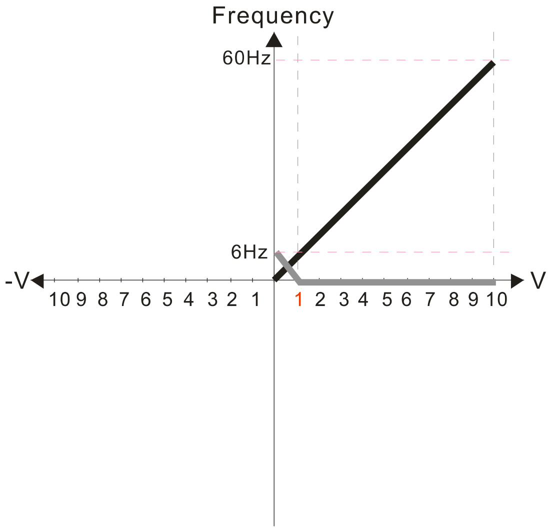
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-10 (Analog Frequency Command for Reverse Run)

0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.
1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Pr.03-11 Analog Input Gain (AVI1)= 100%

Diagram 6



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)
- 0: No bias
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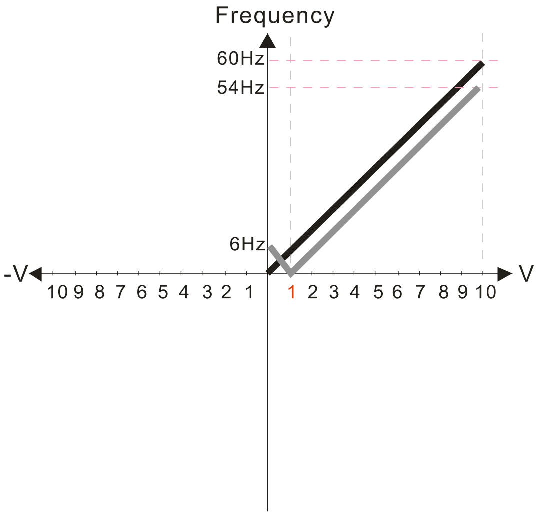
Pr.03-11Analog Input Gain (AVI1)= 100%

Diagram 7



Pr.03-03=10%

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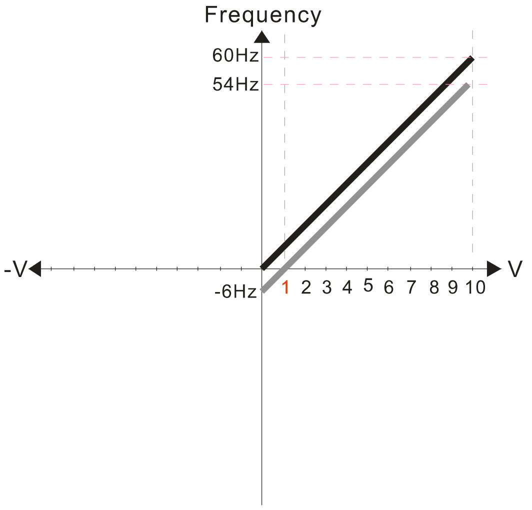
Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 8



Pr.03-03=10%

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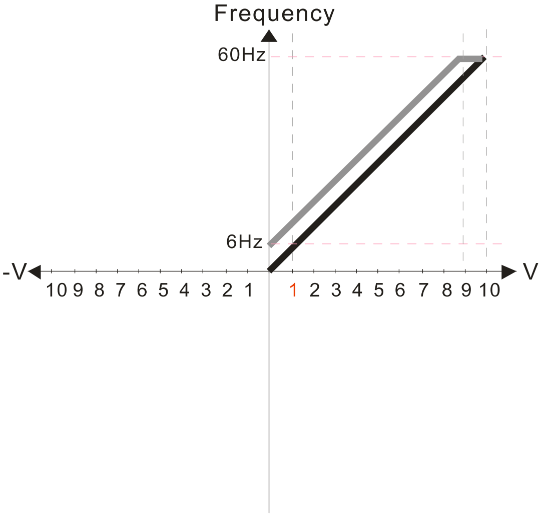
Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 9



Pr.03-03=-10%

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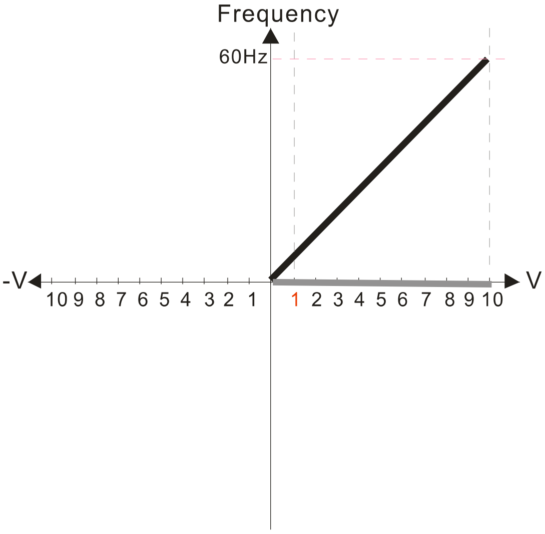
Pr.03-11 Analog Input Gain (AVI1)= 100%

Diagram 10



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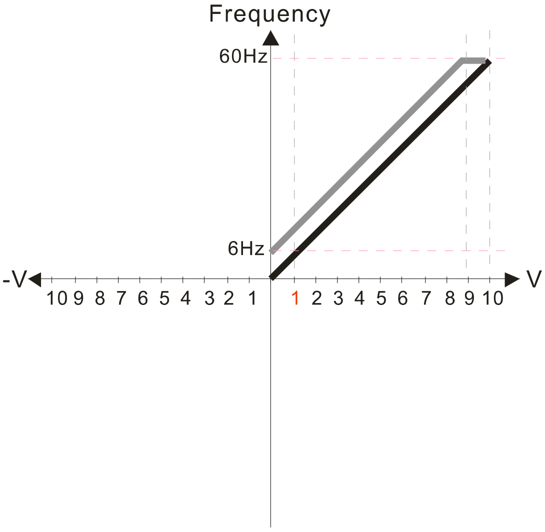
Pr.03-11 Analog Input Gain (AVI1)= 100%

Diagram 11



Pr.03-03=-10%

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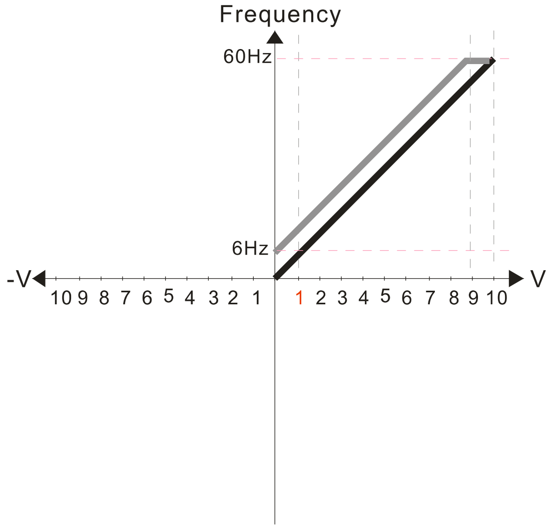
Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 12



Pr.03-03=-10%

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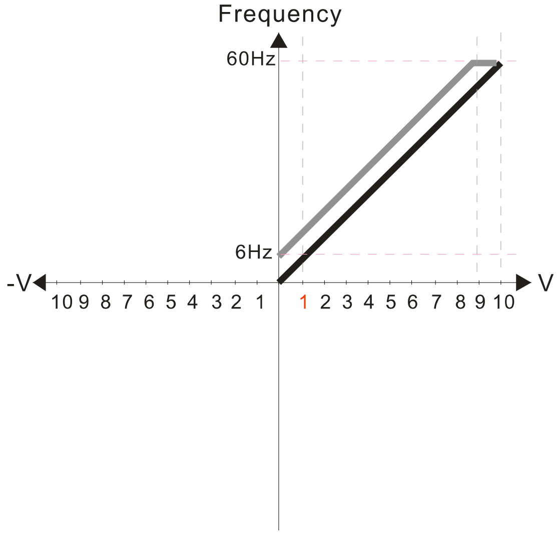
Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 13



Pr.03-03=-10%

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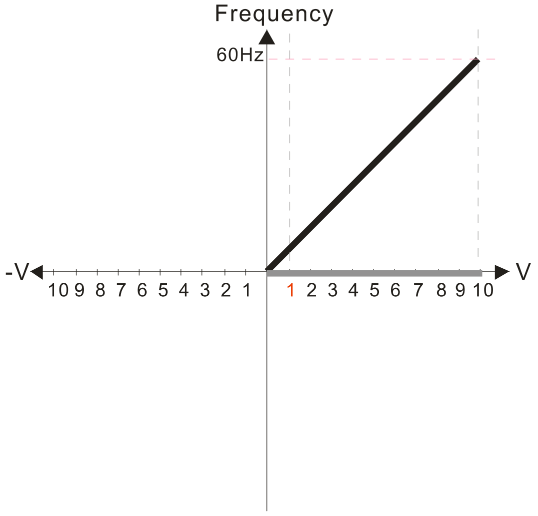
Pr.03-11 Analog Input Gain (AVI1)= 100%

Diagram 14



Pr.03-03=-10%

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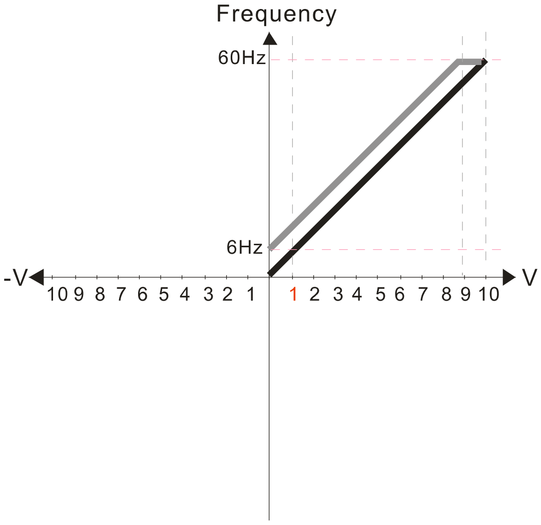
Pr.03-11 Analog Input Gain (AVI1)= 100%

Diagram 15



Pr.03-03=-10%

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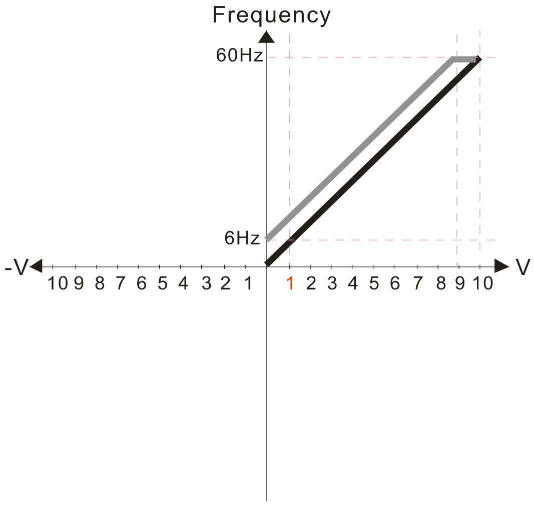
Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 16



Pr.03-03=-10%

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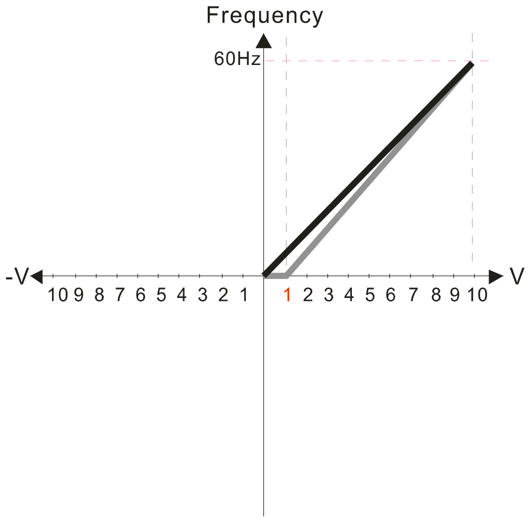
Pr.03-11 Analog Input Gain (AVI1) = 100%

Diagram 17



Pr.03-03=10%

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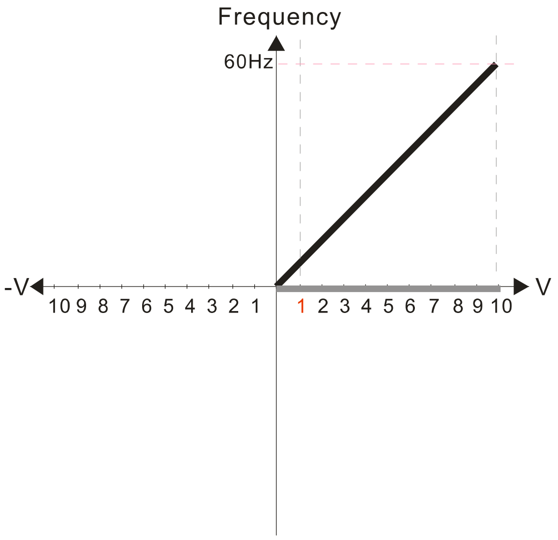
Pr.03-11 Analog Input Gain (AVI1)= 111.1%

10/9=111.1%

Diagram 18



Pr.03-03=10%

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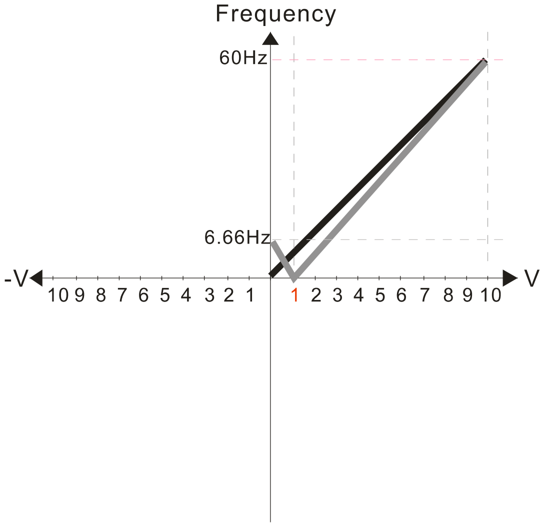
Pr.03-11 Analog Input Gain (AVI1)=111.1%
10/9 =111.1%

Diagram 19



Pr.03-03=10%

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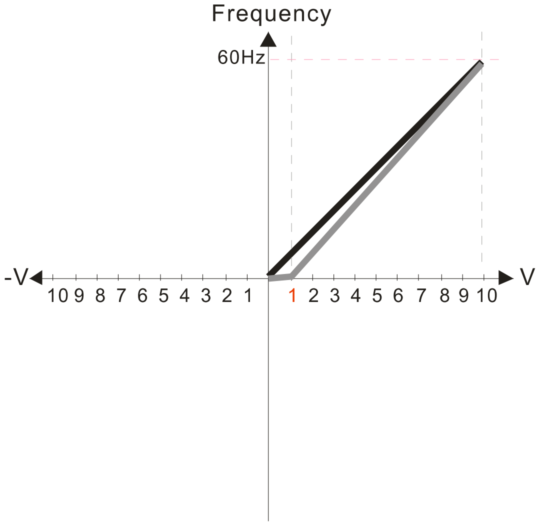
Pr.03-11 Analog Input Gain (AVI1) = 111.1%
10/9 = 111.1%

Diagram 20



Pr.03-03=10%

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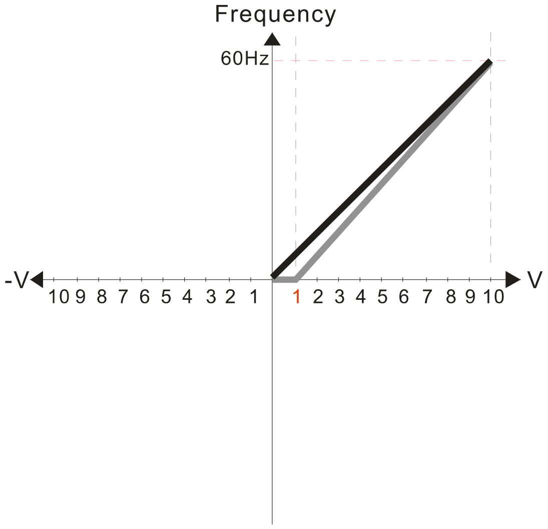
Pr.03-11 Analog Input Gain (AVI1) = 111.1%
10/9 = 111.1%

Diagram 21



Pr.03-03=10%

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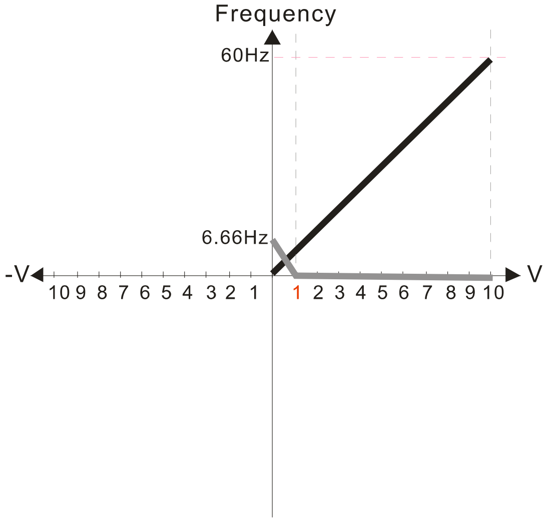
Pr.03-11 Analog Input Gain (AVI1) = 111.1%
10/9 = 111.1%

Diagram 22



Pr.03-03=10%

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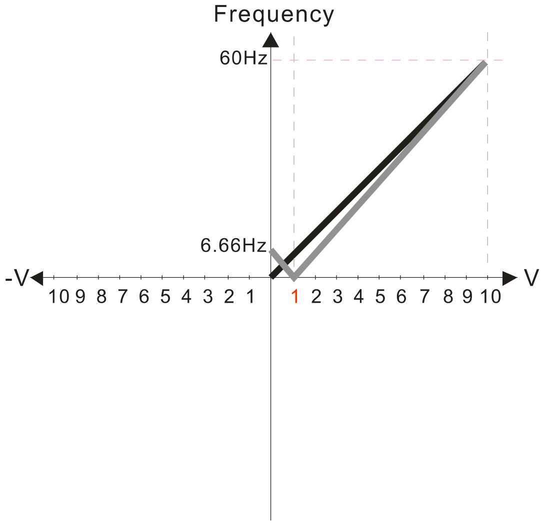
Diagram 23



Pr.03-03=10%

Pr.03-07–03-09 (Positive/Negative Bias Mode)
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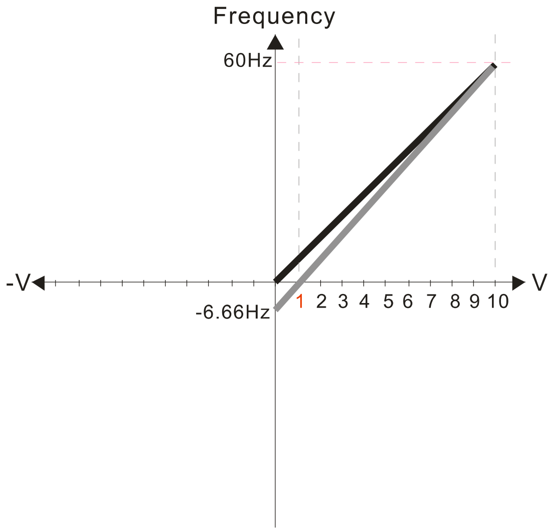
Pr.03-11 Analog Input Gain (AVI1) = 111.1%
10/9 = 111.1%

Diagram 24



Pr.03-03=10%

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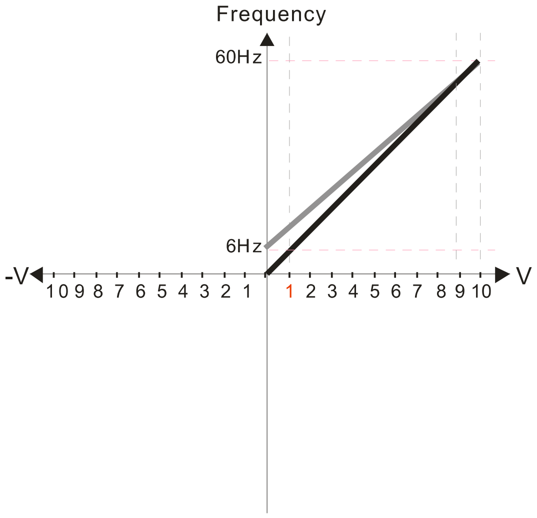
Pr.03-11 Analog Input Gain (AVI1) = 111.1%
10/9 = 111.1%

Diagram 25



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Calculate the bias:

$$\frac{60\text{-}6\text{Hz}}{10\text{V}} = \frac{6\text{-}0\text{Hz}}{(0\text{-}x\text{V})} \quad x\text{V}=\frac{10}{-9}=-1.11\text{V} \quad \therefore 03\text{-}03=\frac{-1.11}{10}\times100\,\% =-11.1\%$$

Calculate the gain: $03\text{-}11=\frac{10\text{V}}{11.1\text{V}}\times100\%=90.0\%$

Diagram 26

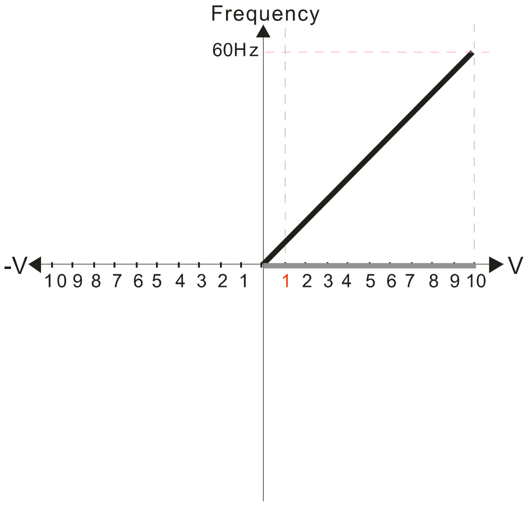

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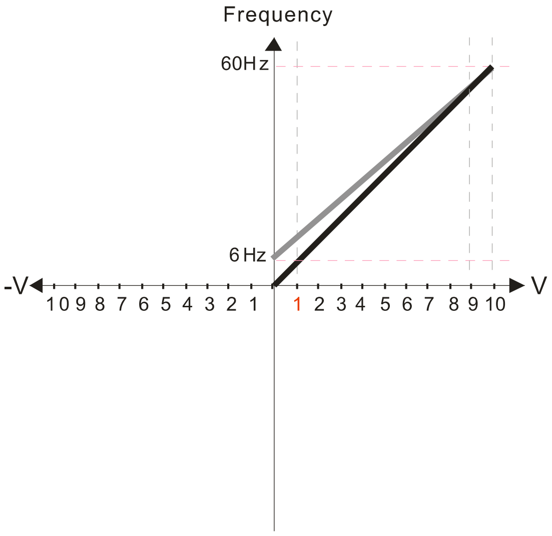
Diagram 27



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Calculate the gain: $03\text{-}11=\frac{10\text{V}}{11.1\text{V}}\times 100\%=90.0\%$

Diagram 28

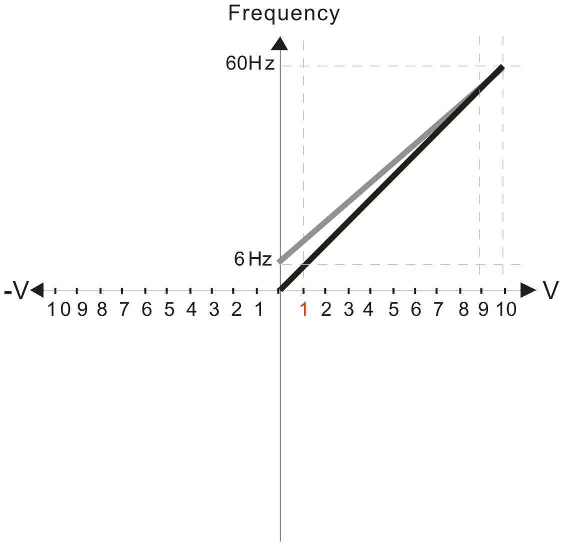

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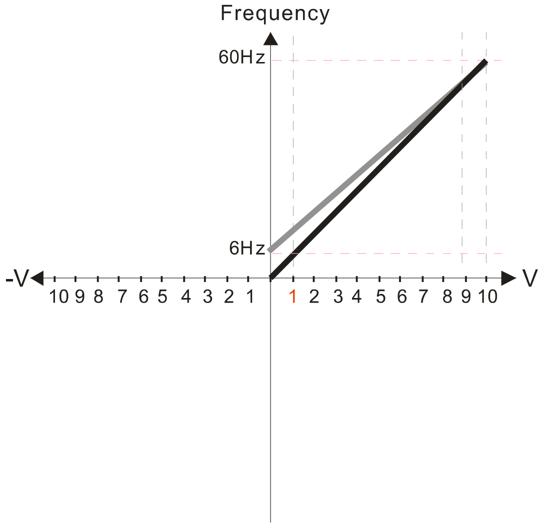
Diagram 29



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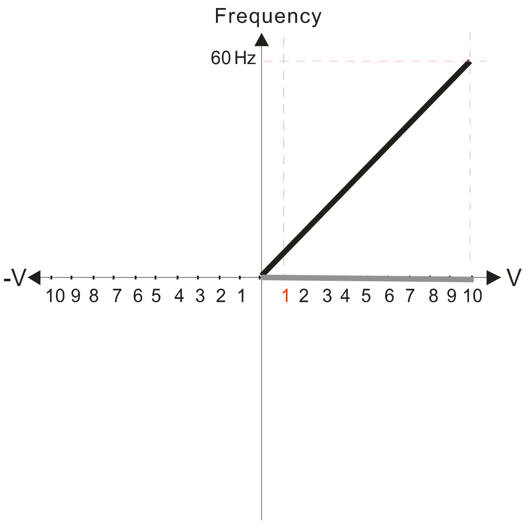
Calculate the gain: $03\text{-}11=\frac{10\text{V}}{11.1\text{V}}\times 100\%=90.0\%$

Diagram 30



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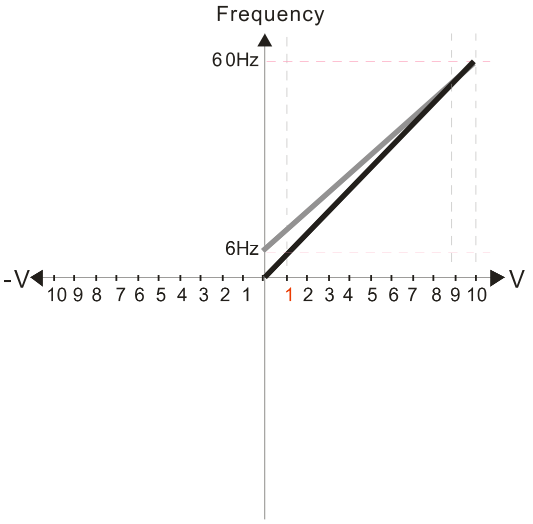
1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Calculate the bias:

$$\frac{60\text{-}6Hz}{10V} = \frac{6\text{-}0Hz}{(0\text{-}xV)} \quad xV=\frac{10}{-9}=-1.11V \quad \therefore 03\text{-}03=\frac{-1.11}{10}\times 100\% =-11.1\%$$

Calculate the gain: $03\text{-}11=\frac{10V}{11.1V}\times 100\%=90.0\%$

Diagram 31



Pr.03-07–03-09 (Positive/Negative Bias Mode)
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

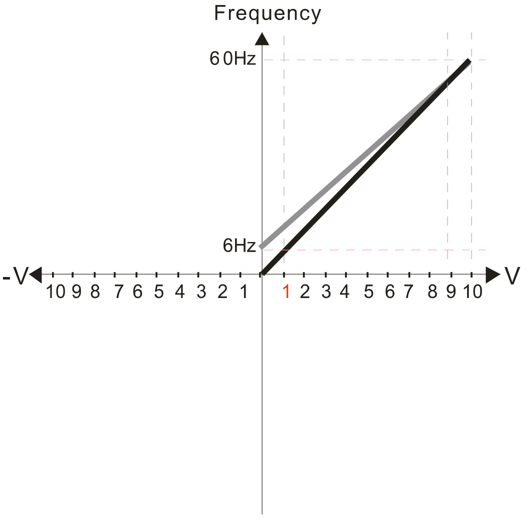
Pr.03-10 (Analog Frequency Command for Reverse Run)
0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.
1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Calculate the bias:

$$\frac{60\text{-}6Hz}{10V} = \frac{6\text{-}0Hz}{(0\text{-}xV)} \quad xV=\frac{10}{-9}=-1.11V \quad \therefore 03\text{-}03=\frac{-1.11}{10}\times 100\% =-11.1\%$$

Calculate the gain: $03\text{-}11=\frac{10V}{11.1V}\times 100\%=90.0\%$

Diagram 32



Pr.03-07–03-09 (Positive/Negative Bias Mode)
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

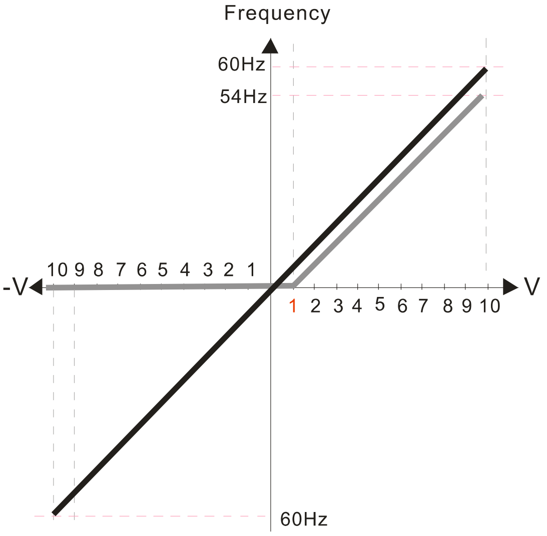
Pr.03-10 (Analog Frequency Command for Reverse Run)
0: Negative frequency is not valid. Forward and reverse run is controlled by digital keypad or external terminal.
1: Neagtive frequency is valid. Positive frequency = forward run; negative frequency = reverse run. Direction can not be switched by digital keypad or external teriminal control.

Calculate the bias:

$$\frac{60\text{-}6Hz}{10V} = \frac{6\text{-}0Hz}{(0\text{-}xV)} \quad xV=\frac{10}{-9}=-1.11V \quad \therefore 03\text{-}03=\frac{-1.11}{10}\times 100\% =-11.1\%$$

Calculate the gain: $03\text{-}11=\frac{10V}{11.1V}\times 100\%=90.0\%$

Diagram 33



Pr.00-21=0 (Digital keypad control and run in FWD direction)

Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%

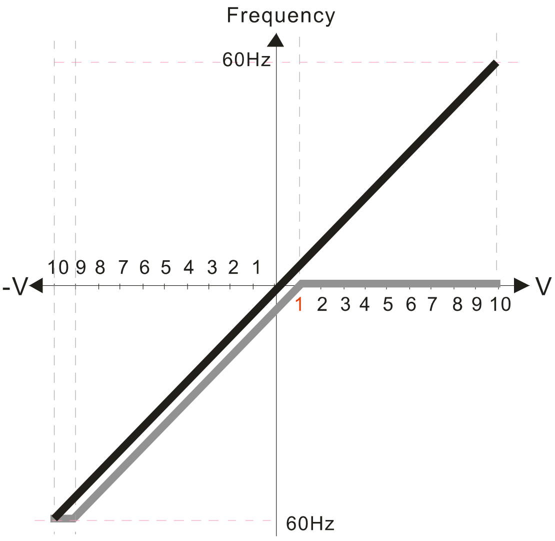
Pr.03-07–03-09 (Positive/Negative Bias Mode)

0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 100%

Pr.03-14 Analog Positive Input Gain (AVI2) = 100%

Diagram 34



Pr.00-21=0 (Digital keypad control and run in FWD direction)

Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%

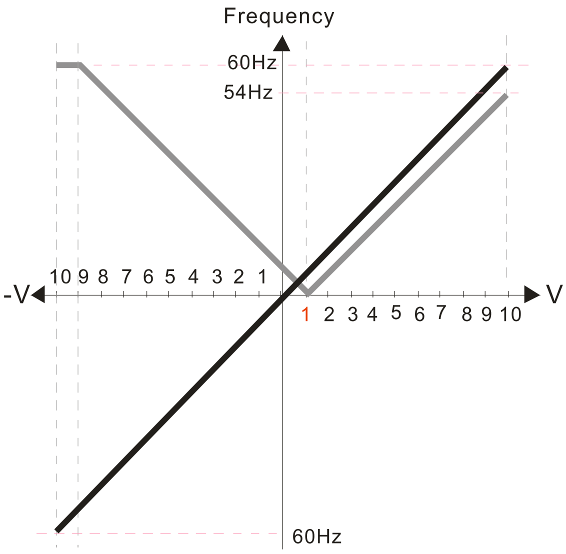
Pr.03-07–03-09 (Positive/Negative Bias Mode)

0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 100%

Pr.03-14 Analog Positive Input Gain (AVI2) = 100%

Diagram 35



Pr.00-21=0 (Digital keypad control and run in FWD direction)

Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%

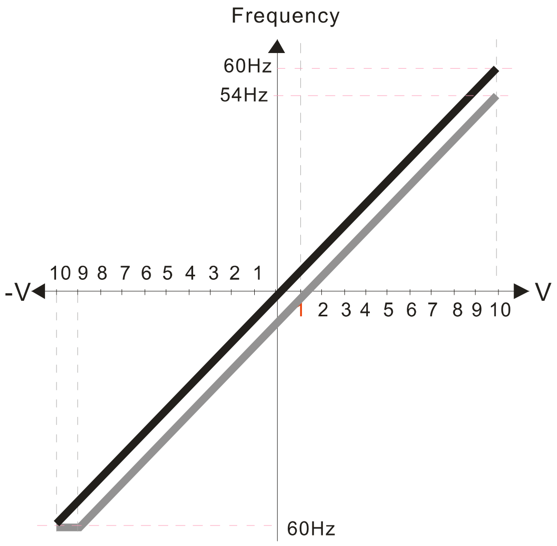
Pr.03-07–03-09 (Positive/Negative Bias Mode)

0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 100%

Pr.03-14 Analog Positive Input Gain (AVI2) = 100%

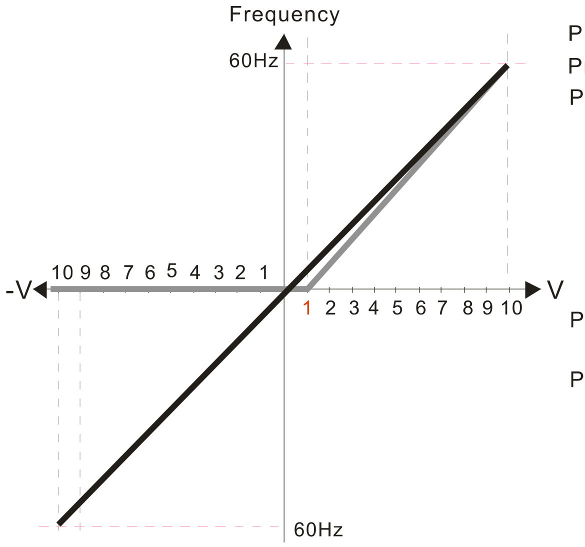
Diagram 36



Pr.00-21=0 (Digital keypad control and run in FWD direction)
Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%
Pr.03-07–03-09 (Positive/Negative Bias Mode)
- 0: No bias
- 1: Lower than or equal to bias
- 2: Greater than or equal to bias
- 3: The absolute value of the bias voltage while serving as the center
- 4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 100%
Pr.03-14 Analog Positive Input Gain (AVI2) = 100%

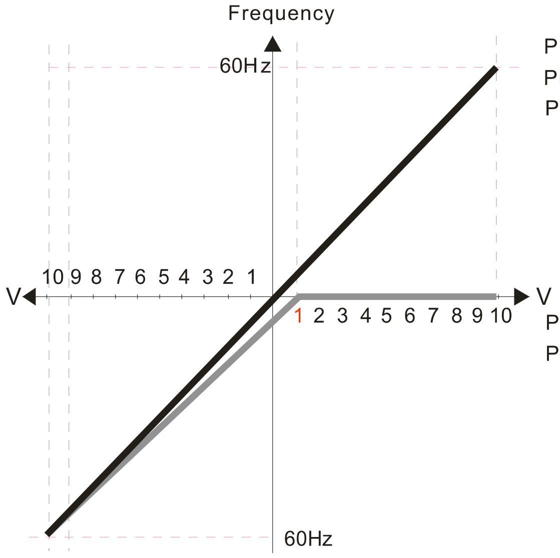
Diagram 37



Pr.00-21=0 (Digital keypad control and run in FWD direction)
Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%
Pr.03-07–03-09 (Positive/Negative Bias Mode)
- 0: No bias
- 1: Lower than or equal to bias
- 2: Greater than or equal to bias
- 3: The absolute value of the bias voltage while serving as the center
- 4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 111.1%
(10/9) × 100% = 111.1%
Pr.03-14 Analog Positive Input Gain (AVI2) = 100%

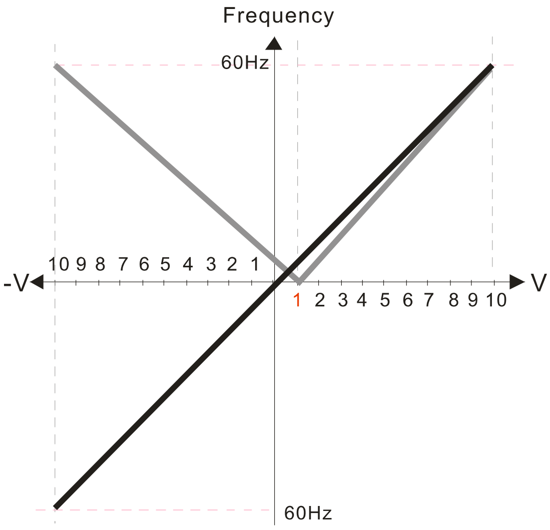
Diagram 38



Pr.00-21=0 (Digital keypad control and run in FWD direction)
Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%
Pr.03-07–03-09 (Positive/Negative Bias Mode)
- 0: No bias
- 1: Lower than or equal to bias
- 2: Greater than or equal to bias
- 3: The absolute value of the bias voltage while serving as the center
- 4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 100%
Pr.03-14 Analog Positive Input Gain (AVI2) = 90.0%
(10/11) × 100% = 90.9%

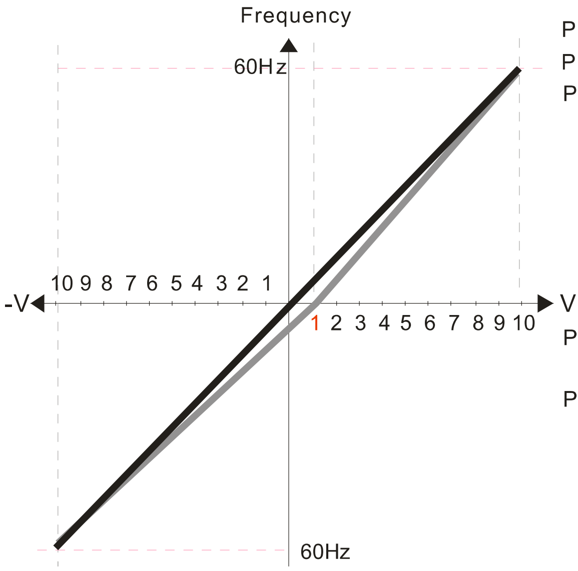
Diagram 39



Pr.00-21=0 (Digital keypad control and run in FWD direction)
Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%
Pr.03-07–03-09 (Positive/Negative Bias Mode)
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 111.1%
(10/9) × 100% = 111.1%
Pr.03-14 Analog Positive Input Gain (AVI2) = 90.9%
(10/11) × 100% = 90.9%

Diagram 40



Pr.00-21=0 (Digital keypad control and run in FWD direction)
Pr.03-05 Analog Positive Voltage Input Bias (AVI2) = 10%
Pr.03-07–03-09 (Positive/Negative Bias Mode)
0: No bias
1: Lower than or equal to bias
2: Greater than or equal to bias
3: The absolute value of the bias voltage while serving as the center
4: Serve bias as the center

Pr.03-13 Analog Positive Input Gain (AVI2) = 111.1%
(10/9) × 100% = 111.1%
Pr.03-14 Analog Positive Input Gain (AVI2) = 90.9%
(10/11) × 100% = 90.9%

03-10 Reverse Setting when Analog Signal Input is Negative Frequency

Default: 0

Settings 0: Negative frequency is not allowed. The digital keypad or external terminal controls the forward and reverse direction.

1: Negative frequency is allowed. Positive frequency = run in forward direction; negative frequency = run in reverse direction. The digital keypad or external terminal control cannot switch the running direction.

- Use this parameter only for AVI1 or ACI analog input.
- Requirements for negative frequency (reverse running):

1. Pr.03-10 = 1
2. Bias mode = Bias serve as the center
3. Corresponded analog input gain < 0 (negative); this makes the input frequency negative.

- In using the additional analog input function (Pr.03-18 = 1), when the analog signal is negative after the addition, you can set this parameter to allow or not allow the reverse running. The result after adding depends on the “Requirements for negative frequency (reverse running).”

03-11 AVI1 Analog Input Gain
03-12 ACI Analog Input Gain
03-13 AVI2 Analog Positive Input Gain
03-14 AVI2 Analog Negative Input Gain

Default: 100.0

Settings -500.0–500.0%

- Use Pr.03-03–Pr.03-14 are used when the Frequency command source is the analog voltage or current signal.

03-15 AVI1 Analog Input Filter Time
03-16 ACI Analog Input Filter Time
03-17 AVI2 Analog Input Filter Time

Default: 0.01

Settings 0.00–20.00 sec.

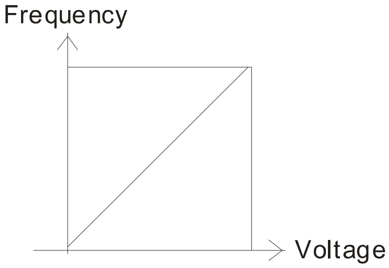
- Analog signals, such as those entering AVI1, ACI and AVI2, are commonly affected by interference that affects the stability of the analog control. Use the Input Noise Filter to create a more stable system.
- When the time constant setting is too large, the control is stable but the control response is slow. When the time constant setting is too small, the control response is be faster but the control may be unstable. For optimal setting, adjust the setting based on the control stability or the control response.

03-18 Analog Input Addition Function

Default: 0

Settings 0: Disable (AVI1, ACI, AVI2)
1: Enable

- When Pr.03-18 = 1:
  Example 1: Pr.03-00 = Pr.03-01 = 1, Frequency command = AVI1 + ACI
  Example 2: Pr.03-00 = Pr.03-01 = Pr.03-02 = 1, Frequency command = AVI1 + ACI + AVI2
  Example 3: Pr.03-00 = Pr.03-02 = 1, Frequency command = AVI1 + AVI2
  Example 4: Pr.03-01 = Pr.03-02 = 1, Frequency command = ACI + AVI2
- When Pr.03-18 = 0 and the analog input selection settings (Pr.03-00, Pr.03-01 and Pr.03-02) are the same, AVI1 has priority over ACI and AVI2 (AVI1 > ACI > AVI2).



$$\text{Fcmd}=[(\text{ay}\pm\text{bias})*\text{gain}]*\frac{\text{Fmax}(01\text{-}00)}{10\text{V or }16\text{mA or }20\text{mA}}$$

Fcmd: the corresponding frequency of 10V or 20mA

ay : 0~10V, 4~20mA, 0~20mA
bias : Pr.03-03, Pr. 03-04, Pr.03-05
gain : Pr.03-11, Pr.03-12, Pr.03-13, Pr.03-14

03-19 Signal Loss Selection for the Analog Input 4–20 mA

Default: 0

Settings 0: Disable
1: Continue operation at the last frequency
2: Decelerate to 0 Hz
3: Stop immediately and display “ACE”

🕮 Determines the treatment when the 4–20 mA signal is lost [AVIc (Pr.03-28 = 2) or ACIc (Pr.03-29 = 0)].

🕮 When Pr.03-28 ≠ 2, the voltage input to AVI1 terminal is 0–10 V or 0–20 mA, and Pr.03-19 is invalid.

🕮 When Pr.03-29 ≠ 0, the voltage input to ACI terminal is 0–10 V, and the Pr.03-19 is invalid.

🕮 When the setting is 1 or 2, the keypad displays the warning code “ANL”. It keeps blinking until the ACI signal is recovered.

🕮 When the setting is 3, and the ACI terminal is disconnected, the keypad displays “ACE” error. It keeps blinking until the connection is recovered and the error is reset.

🕮 When the drive stops, the condition that causes the warning does not exist, so the warning automatically disappears.

ϟ 03-20 AFM1 Analog Output Selection

ϟ 03-23 AFM2 Analog Output Selection

Default: 0

Settings 0–23

Function Chart

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>0</td><td>Output frequency (Hz)</td><td>Maximum frequency Pr.01-00 is processed as 100%.</td></tr>
<tr><td>1</td><td>Frequency command (Hz)</td><td>Maximum frequency Pr.01-00 is processed as 100%.</td></tr>
<tr><td>2</td><td>Motor speed (Hz)</td><td>Maximum frequency Pr.01-00 is processed as 100%</td></tr>
<tr><td>3</td><td>Output current (rms)</td><td>(2.5 × drive rated current) is processed as 100%</td></tr>
<tr><td>4</td><td>Output voltage</td><td>(2 × motor rated voltage) is processed as 100%</td></tr>
<tr><td>5</td><td>DC bus Voltage</td><td>450V (900V) = 100%</td></tr>
<tr><td>6</td><td>Power factor</td><td>-1.000–1.000 = 100%</td></tr>
<tr><td>7</td><td>Power</td><td>Drive rated power is processed as 100%</td></tr>
<tr><td>9</td><td>AVI1 percentage</td><td>0–10 V / 0–20 mA / 4–20 mA = 0–100%</td></tr>
<tr><td>10</td><td>ACI percentage</td><td>4–20 mA / 0–10 V / 0–20 mA = 0–100%</td></tr>
<tr><td>11</td><td>AVI2 percentage</td><td>0–10 V = 0–100%</td></tr>
<tr><td>20</td><td>CANopen analog output</td><td>For CANopen communication analog output
<table>
<tr><th>Terminal</th><th>Corresponding address</th></tr>
<tr><td>AFM1</td><td>2026-A1</td></tr>
<tr><td>AFM2</td><td>2026-A2</td></tr>
<tr><td>AO10</td><td>2026-AB</td></tr>
<tr><td>AO11</td><td>2026-AC</td></tr>
</table></td></tr>
</table>

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>21</td><td>RS-485 analog output</td><td>For RS-485 (InnerCOM / Modbus) control analog output
<table>
<tr><th>Terminal</th><th>Corresponding address</th></tr>
<tr><td>AFM1</td><td>26A0H</td></tr>
<tr><td>AFM2</td><td>26A1H</td></tr>
<tr><td>AO10</td><td>26AAH</td></tr>
<tr><td>AO11</td><td>26ABH</td></tr>
</table></td></tr>
<tr><td>22</td><td>Communication card analog output</td><td>For communication analog output (CMC-EIP01, CMC-PN01, CMC-DN01)
<table>
<tr><th>Terminal</th><th>Corresponding address</th></tr>
<tr><td>AFM1</td><td>26A0H</td></tr>
<tr><td>AFM2</td><td>26A1H</td></tr>
<tr><td>AO10</td><td>26AAH</td></tr>
<tr><td>AO11</td><td>26ABH</td></tr>
</table></td></tr>
<tr><td>23</td><td>Constant voltage output</td><td>Pr.03-32 and Pr.03-33 control the voltage output level
0–100% of Pr.03-32 corresponds to 0–10 V of AFM1.
0–100% of Pr.03-33 corresponds to 0–10 V of AFM2.</td></tr>
</table>

✎ **03-21** AFM1 Analog Output Gain

✎ **03-24** AFM2 Analog Output Gain

Default: 100.0

Settings 0.0–500.0%

Adjusts the voltage level outputted to the analog meter from the analog signal (Pr.03-20) output terminal AFM of the drive.

✎ **03-22** AFM1 Analog Output REV Direction

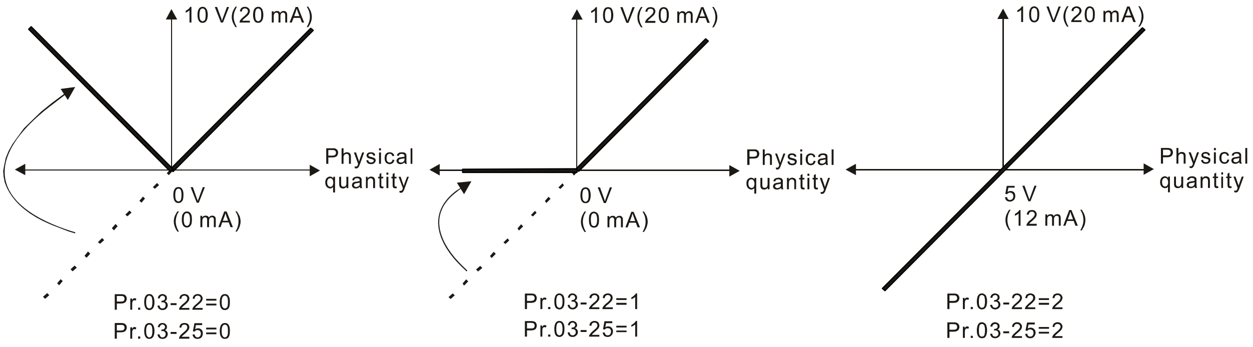
✎ **03-25** AFM2 Analog Output REV Direction

Default: 0

Settings 0: Absolute value in output voltage

1: Reverse output 0 V; forward output 0–10 V

2: Reverse output 5–0 V; forward output 5–10 V



Selections for the analog output direction

✎ **03-27** AFM2 Output Bias

Default: 0.00

Settings -100.00–100.00%

- Example 1, AFM2 0–10 V is set to the output frequency, the output equation is:
  10 V × (output frequency / Pr.01-00) × Pr.03-24 + 10 V × Pr.03-27
- Example 2, AFM2 0–20 mA is set to the output frequency, the output equation is:
  20 mA × (output frequency / Pr.01-00) × Pr.03-24 + 20 mA × Pr.03-27
- Example 3, AFM2 4–20 mA is set to the output frequency, the output equation is:
  4 mA + 16 mA × (output frequency / Pr.01-00) × Pr.03-24 + 16 mA × Pr.03-27
- This parameter sets the corresponding voltage of the analog output 0.

⌁ 03-28 AVI1 Terminal Input Selection

Default: 0

Settings 0: 0–10 V
1: 0–20 mA
2: 4–20 mA

⌁ 03-29 ACI Terminal Input Selection

Default: 0

Settings 0: 4–20 mA
1: 0–10 V
2: 0–20 mA

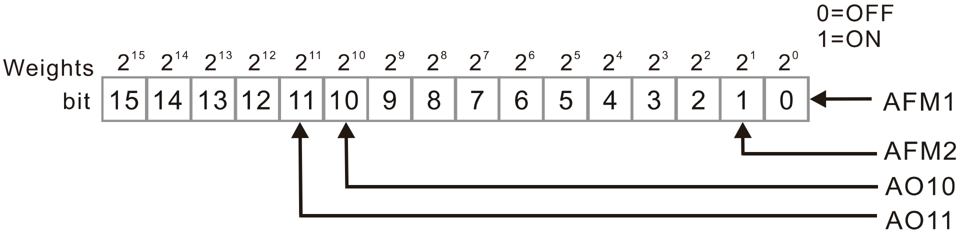
- When you change the input mode, verify that the external terminal switch (SW3, SW4) corresponds to the setting for Pr.03-28–Pr.03-29.
- When you change the setting, proportion to the corresponding ACI and ACI will change to default.

03-30 PLC Analog Output Terminal Status

Default: Read only

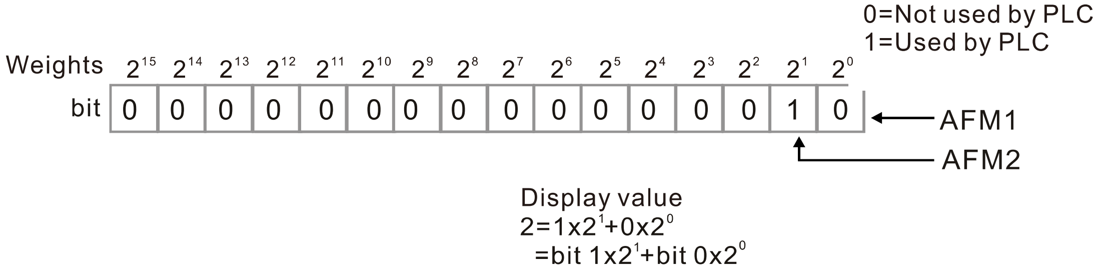
Settings Monitor the status of the PLC analog output terminals

- Pr.03-30 displays the external multi-function output terminal that used by PLC.



NOTE
2^7=128 2^6=64
2^5=32 2^4=16 2^3=8
2^2=4 2^1=2 2^0=1

- For Example:
  When Pr.03-30 displays 0002h (hex), it means that AFM2 is used by PLC.



✔ 03-31 AFM2 Output Selection

✔ 03-34 AFM1 Output Selection

Default: 0

Settings 0: 0–20 mA output
1: 4–20 mA output

✔ 03-32 AFM1 DC Output Setting Level

✔ 03-33 AFM2 DC Output Setting Level

Default: 0.00

Settings 0.00–100.00%

- 📖 Pair with multi-function output: 23, Pr.03-32 and Pr.03-33 outputs constant AFM voltage.
- 📖 Set Pr.03-32 between 0–100.00% to correspond to 0–10 V of AFM1.
- 📖 Set Pr.03-33 between 0–100.00% to correspond to 0–10 V of AFM2.

✔ 03-35 AFM1 Filter Output Time

✔ 03-36 AFM2 Filter Output Time

Default: 0.01

Settings 0.00–20.00 sec.

✔ 03-44 Multi-function MO Output by AI Level Source

Default: 0

Settings 0: AVI1
1: ACI
2: AVI2

✔ 03-45 AI Upper Level

Default: 50.00

Settings -100.00–100.00%

✔ 03-46 AI Lower Level

Default: 10.00

Settings -100.00–100.00%

- 📖 Use this function (Pr.03-44) with the multi-function output setting 67 (analog input level reached). The MO is active when the AI input level is higher than the Pr.03-45. The MO is disabled when the AI input is lower than the Pr.03-46.
- 📖 When setting levels, Pr.03-45 AI upper level must be higher than Pr.03-46 AI lower level.

✔ 03-50 Analog Input Curve Selection

Default: 7

Settings 0: Normal Curve
1: Three-point curve of AVI1
2: Three-point curve of ACI
3: Three-point curve of AVI 1& ACI
4: Three-point curve of AVI2

5: Three-point curve of AVI 1& AVI2
6: Three-point curve of ACI & AVI2
7: Three-point curve of AVI1 & ACI & AVI2

- Sets the calculation method for analog input.
- When Pr.03-50 = 0, all analog input signal is calculated by bias and gain.
- When Pr.03-50 = 1, AVI1 calculates by frequency and voltage / current (Pr.03-51–Pr.03-56), other analog input signal calculates by bias and gain.
- When Pr.03-50 = 2, ACI calculates by frequency and voltage / current (Pr.03-57–Pr.03-62), other analog input signal calculates by bias and gain.
- When Pr.03-50 = 3, AVI1 and ACI calculate by frequency and voltage / current (Pr.03-51–Pr.03-62), other analog input signal calculate by bias and gain.
- When Pr.03-50 = 4, AVI2 calculates by frequency and voltage (Pr.03-63–Pr.03-68), other analog input signal calculates by bias and gain.
- When Pr.03-50 = 5, AVI1 and AVI2 calculate by frequency and voltage / current (Pr.03-51–Pr.03-56 and Pr.03-63–Pr.03-68), other analog input signal calculate by bias and gain.
- When Pr.03-50 = 6, ACI and AVI2 calculate by frequency and voltage / current (Pr.03-57–Pr.03-68), other analog input signal calculates by bias and gain.
- When Pr.03-50 = 7, all analog input signal calculate by frequency and voltage / current (Pr.03-51–Pr.03-68).

✔ 03-51 AVI1 Lowest Point

Default:
0.00 / 0.00 / 4.00

Settings Pr.03-28 = 0, 0.00–10.00 V
Pr.03-28 = 1, 0.00–20.00 mA
Pr.03-28 = 2, 0.00–20.00 mA

✔ 03-52 AVI1 Proportional Lowest Point

Default: 0.00

Settings -100.00–100.00%

✔ 03-53 AVI1 Mid-Point

Default:
5.00 / 10.00 / 12.00

Settings Pr.03-28 = 0, 0.00–10.00 V
Pr.03-28 = 1, 0.00–20.00 mA
Pr.03-28 = 2, 0.00–20.00 mA

✔ 03-54 AVI1 Proportional Mid-Point

Default: 50.00

Settings -100.00–100.00%

03-55 AVI1 Highest Point

Default:
10.00 / 20.00 / 20.00

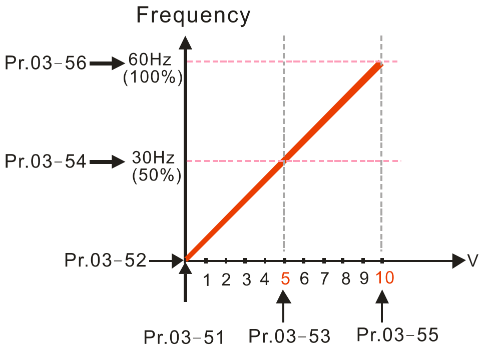
Settings Pr.03-28 = 0, 0.00–10.00 V
Pr.03-28 = 1, 0.00–20.00 mA
Pr.03-28 = 2, 0.00–20.00 mA

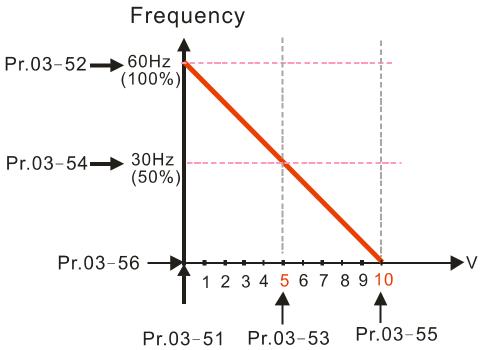
03-56 AVI1 Proportional Highest Point

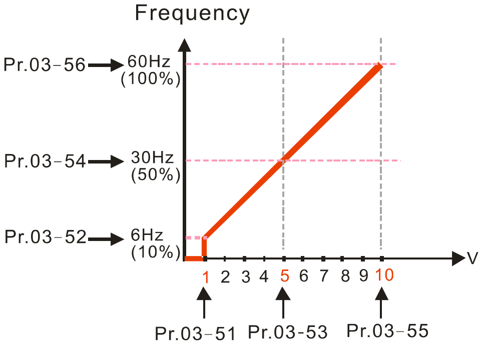
Default: 100.00

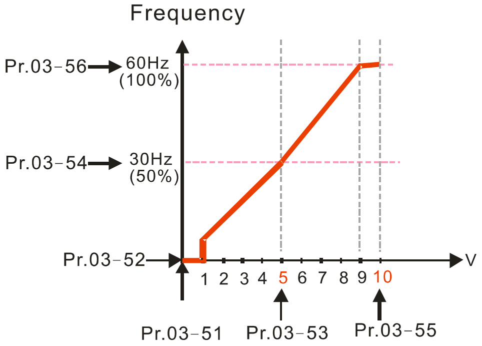
Settings -100.00–100.00%

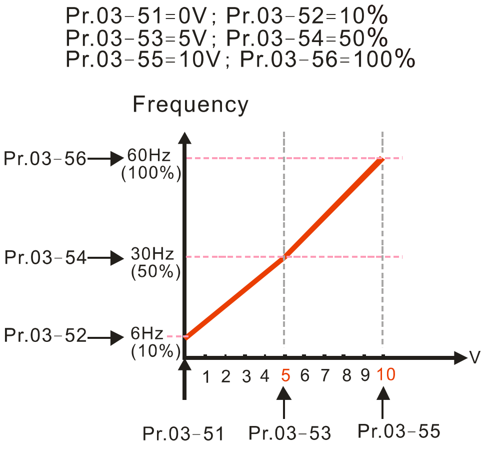
- When Pr.03-28 = 0, the AVI1 setting is 0–10 V and the unit is in voltage (V).
  When Pr.03-28 ≠ 0, the AVI1 setting is 0–20 mA or 4–20 mA and the unit is in current (mA).
- When you set the analog input AVI1 to frequency command, 100% corresponds to Fmax (Pr.01-00 Maximum Operation Frequency).
- The requirement for these there parameters (Pr.03-51, Pr.03-53 and Pr.03-55) is Pr.03-51 < Pr.03-53 < Pr.03-55. The values for three proportional points (Pr.03-52, Pr.03-54 and Pr.03-56) have no limits. Values between two points are calculated by a linear equation. The ACI and AVI2 are the same as AVI1.
- The output percentage is 0% when the AVI1 input value is lower than the lowest point setting.
  Example: Pr.03-51 = 1 V, Pr.03-52 = 10%. The output is 0% when AVI1 input is lower than 1 V. If the AVI1 input varies between 1 V and 1.1 V, the drive's output frequency is between 0% and 10%.


Pr.03-51=0V; Pr.03-52=0%
Pr.03-53=5V; Pr.03-54=50%
Pr.03-55=10V; Pr.03-56=100%

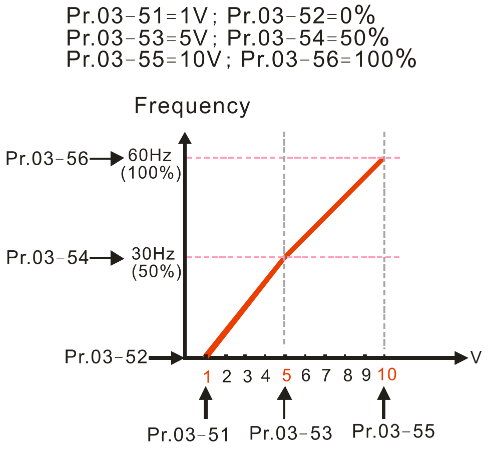

Pr.03-51=0V; Pr.03-52=100%
Pr.03-53=5V; Pr.03-54=50%
Pr.03-55=10V; Pr.03-56=0%


Pr.03-51=1V; Pr.03-52=10%
Pr.03-53=5V; Pr.03-54=50%
Pr.03-55=10V; Pr.03-56=100%


Pr.03-51=1V; Pr.03-52=10%
Pr.03-53=5V; Pr.03-54=50%
Pr.03-55=9V; Pr.03-56=100%



Pr.03-51=0V ; Pr.03-52=10%
Pr.03-53=5V ; Pr.03-54=50%
Pr.03-55=10V ; Pr.03-56=100%



Pr.03-51=1V ; Pr.03-52=0%
Pr.03-53=5V ; Pr.03-54=50%
Pr.03-55=10V ; Pr.03-56=100%

03-57 ACI Lowest Point

Default:
4.00 / 0.00 / 0.00

Settings Pr.03-29 = 0, 0.00–20.0 mA
Pr.03-29 = 1, 0.00–10.00 V
Pr.03-29 = 2, 0.00–20.00 mA

03-58 ACI Proportional Low Point

Default: 0.00

Settings -100.00–100.00%

03-59 ACI Mid-Point

Default:
12.00 / 5.00 / 10.00

Settings Pr.03-29 = 0, 0.00–20.00 mA
Pr.03-29 = 1, 0.00–10.00 V
Pr.03-29 = 2, 0.00–20.00 mA

03-60 ACI Proportional Mid-Point

Default: 50.00

Settings -100.00–100.00%

03-61 ACI Highest Point

Default:
20.00 / 10.00 / 20.00

Settings Pr.03-29 = 0, 0.00–20.00 mA
Pr.03-29 = 1, 0.00–10.00 V
Pr.03-29 = 2, 0.00–20.00 mA

03-62 ACI Proportional Highest Point

Default: 100.00

Settings -100.00–100.00%

📖 When Pr.03-29 = 1, the ACI setting is 0–10 V and the unit is in voltage (V).
When Pr.03-29 ≠ 1, the ACI setting is 0–20 mA or 4–20 mA and the unit is in current (mA).

📖 When you set the analog input ACI to the Frequency command, 100% corresponds to Fmax (Pr.01-00 Maximum Operation Frequency).

📖 The requirement for these three parameters (Pr.03-57, Pr.03-59 and Pr.03-61) is Pr.03-57 < Pr.03-59 < Pr.03-61. The values for three proportional points (Pr.03-58, Pr.03-60 and Pr.03-62) have no limits. There is a linear calculation between two points.

📖 The output percentage becomes 0% when the ACI input value is lower than the lowest point setting.

Example:

Pr.03-57 = 2 mA; Pr.03-58 = 10%, then the output becomes 0% when the AVI1 input is ≤ 2 mA. If the ACI input swings between 2 mA and 2.1 mA, the drive’s output frequency oscillates between 0% and 10%.

✎ **03-63** Positive AVI2 Voltage Lowest Point

Default: 0.00

Settings 0.00–10.00 V

✎ **03-64** Positive AVI2 Voltage Proportional Lowest Point

Default: 0.00

Settings -100.00–100.00%

✎ **03-65** Positive AVI2 Voltage Mid-Point

Default: 5.00

Settings 0.00–10.00 V

✎ **03-66** Positive AVI2 Voltage Proportional Mid-Point

Default: 50.00

Settings -100.00–100.00%

✎ **03-67** Positive AVI2 Voltage Highest Point

Default: 10.00

Settings 0.00–10.00 V

✎ **03-68** Positive AVI2 Voltage Proportional Highest Point

Default: 100.00

Settings -100.00–100.00%

📖 When you set the positive voltage AVI2 to the Frequency command, 100% corresponds to Fmax (Pr.01-00 Maximum Operation Frequency) and the motor runs in the forward direction.

📖 The requirement for these three parameters (Pr.03-63, Pr.03-65 and Pr.03-67) is Pr.03-63 < Pr.03-65 < Pr.03-67. The values for three proportional points (Pr.03-64, Pr.03-66 and Pr.03-68) have no limits. There is a linear calculation between two points.

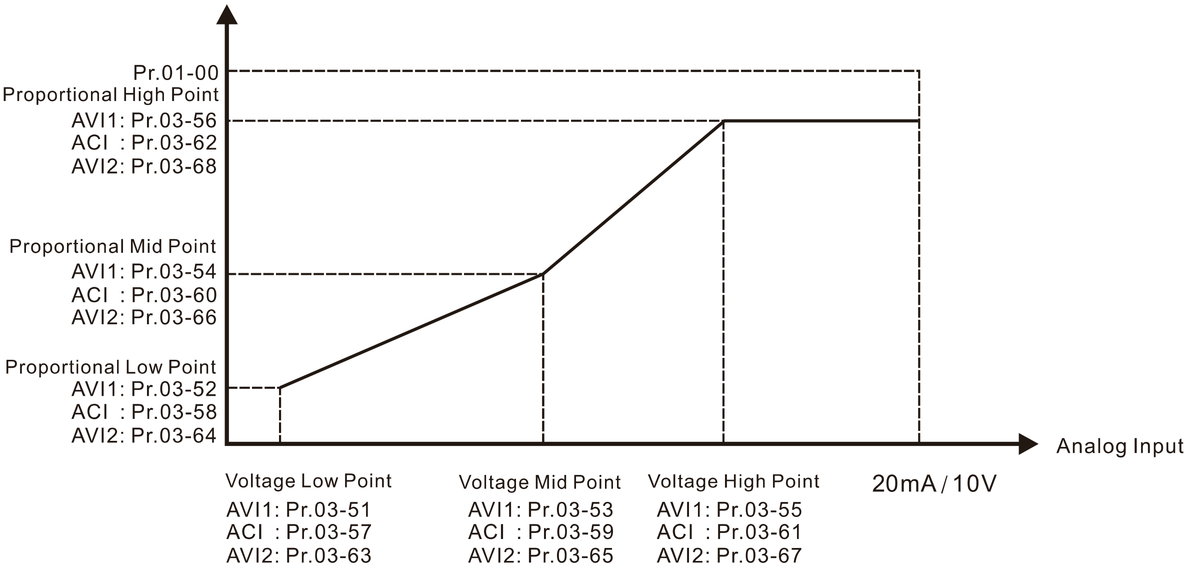
📖 The output percentage becomes 0% when the positive voltage AVI2 input value is lower than the lowest point setting.

For example:

If Pr.03-63 = 1 V; Pr.03-64 = 10%, then the output becomes 0% when the input is lower than 1 V. If the AVI input swings between 1 V and 1.1 V, the drive’s output frequency oscillates between 0% and 10%.

📖 When AVI1 Selection (Pr.03-28) is 0–10 V, the setting ranges for Pr.03-51, Pr.03-53, and Pr.03-55 must be 0.00–10.00 or 0.00–20.00.

- When ACI Selection (Pr.03-29) is 0–10 V, the setting ranges for Pr.03-57, Pr.03-59 and Pr.03-61 must be 0.00–10.00 or 0.00–20.00.
- Use Pr.03-51–Pr.03-68 to set the open circuit corresponding function of analog input value and maximum operation frequency (Pr.01-00), as shown in the figure below:



04 Multi-Step Speed Parameters

⚡ This parameter can be set during operation.

⚡ 04-00 1st Step Speed Frequency

⚡ 04-01 2nd Step Speed Frequency

⚡ 04-02 3rd Step Speed Frequency

⚡ 04-03 4th Step Speed Frequency

⚡ 04-04 5th Step Speed Frequency

⚡ 04-05 6th Step Speed Frequency

⚡ 04-06 7th Step Speed Frequency

⚡ 04-07 8th Step Speed Frequency

⚡ 04-08 9th Step Speed Frequency

⚡ 04-09 10th Step Speed Frequency

⚡ 04-10 11th Step Speed Frequency

⚡ 04-11 12th Step Speed Frequency

⚡ 04-12 13th Step Speed Frequency

⚡ 04-13 14th Step Speed Frequency

⚡ 04-14 15th Step Speed Frequency

Default: 0.00

Settings 0.00–599.00 Hz

📖 Use the multi-function input terminals (refer to setting 1–4 of Pr.02-01–Pr.02-08 and Pr.02-26–Pr.02-31 Multi-function Input Command) to select the multi-step speed command (the maximum is 15th step speed). Pr.04-00 to Pr.04-14 set the multi-step speed frequency as shown in the following diagram.

📖 The external terminal/digital keypad/communication controls the RUN and STOP commands with Pr.00-21.

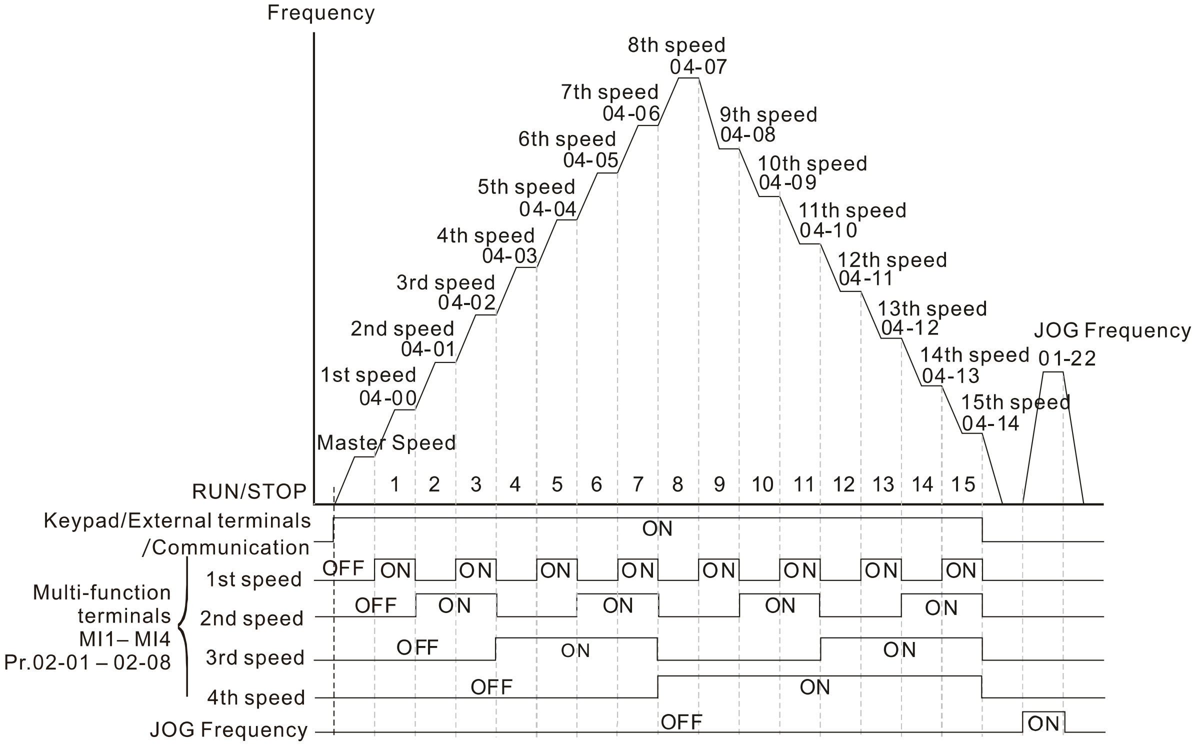
📖 You can set each multi-step speed between 0.00–599.00 Hz during operation.

📖 Explanation for the timing diagram of the multi-step speed and external terminals.

The related parameter settings are:

1. Pr.04-00–04-14: sets the 1st to 15th multi-step speed (to set the frequency of each step speed)
2. Pr.02-01–02-08 and Pr.02-26–02-31: sets the multi-function input terminals (multi-step speed command 1–4)

- Related parameters:
  Pr.01-22 JOG Frequency
  Pr.02-01 Multi-function Input Command 1 (MI1)
  Pr.02-02 Multi-function Input Command 2 (MI2)
  Pr.02-03 Multi-function Input Command 3 (MI3)
  Pr.02-04 Multi-function Input Command 4 (MI4)



Multi-speed via External Terminals

✎	04-50	PLC Buffer 0
✎	04-51	PLC Buffer 1
✎	04-52	PLC Buffer 2
✎	04-53	PLC Buffer 3
✎	04-54	PLC Buffer 4
✎	04-55	PLC Buffer 5
✎	04-56	PLC Buffer 6
✎	04-57	PLC Buffer 7
✎	04-58	PLC Buffer 8
✎	04-59	PLC Buffer 9
✎	04-60	PLC Buffer 10
✎	04-61	PLC Buffer 11
✎	04-62	PLC Buffer 12
✎	04-63	PLC Buffer 13
✎	04-64	PLC Buffer 14
✎	04-65	PLC Buffer 15
✎	04-66	PLC Buffer 16
✎	04-67	PLC Buffer 17
✎	04-68	PLC Buffer 18
✎	04-69	PLC Buffer 19

Default: 0

Settings 0–65535

📖 You can combine the PLC buffer with the built-in PLC function for a variety of applications.

✓ 04-70 PLC Application Parameter 0

✓ 04-71 PLC Application Parameter 1

✓ 04-72 PLC Application Parameter 2

✓ 04-73 PLC Application Parameter 3

✓ 04-74 PLC Application Parameter 4

✓ 04-75 PLC Application Parameter 5

✓ 04-76 PLC Application Parameter 6

✓ 04-77 PLC Application Parameter 7

✓ 04-78 PLC Application Parameter 8

✓ 04-79 PLC Application Parameter 9

✓ 04-80 PLC Application Parameter 10

✓ 04-81 PLC Application Parameter 11

✓ 04-82 PLC Application Parameter 12

✓ 04-83 PLC Application Parameter 13

✓ 04-84 PLC Application Parameter 14

04-85 PLC Application Parameter 15

04-86 PLC Application Parameter 16

04-87 PLC Application Parameter 17

04-88 PLC Application Parameter 18

04-89 PLC Application Parameter 19

04-90 PLC Application Parameter 20

04-91 PLC Application Parameter 21

04-92 PLC Application Parameter 22

04-93 PLC Application Parameter 23

04-94 PLC Application Parameter 24

04-95 PLC Application Parameter 25

04-96 PLC Application Parameter 26

04-97 PLC Application Parameter 27

04-98 PLC Application Parameter 28

04-99 PLC Application Parameter 29

Default: 0

Settings 0–65535

📖 Pr.04-70–Pr.04-99 are user-defined parameters. You can combine these 30 PLC Application Parameters with the PLC programming for a variety of applications.

05 Motor Parameters

✓ You can set this parameter during operation.

The following are abbreviations for different types of motors:

- IM: Induction motor
- PM: Permanent magnet synchronous AC motor
- IPM: Interior permanent magnet synchronous AC motor
- SPM: Surface permanent magnet synchronous AC motor
- SynRM: Synchronous reluctance motor

05-00 Motor Parameter Auto-Tuning

Default: 0

Settings 0: No function
1: Simple rolling auto-tuning for induction motor(IM)
2: Static auto-tuning for induction motor
5: Rolling auto-tuning for PM (IPM / SPM)
11: SynRM parameter auto-tuning (applied to 230V / 460V models)
13: Static auto-tuning for PM (IPM / SPM)

📖 Refer to Section 12-2 “Adjustment and Application” for more details of motor adjustment process.

05-01 Full-load Current for Induction Motor 1 (A)

Default: Depending on the model power

Settings Depending on the model power

📖 Sets this value according to the rated current of the motor as indicated on the motor nameplate.

📖 The default is 90% of the drive’s rated current.
Example: The rated current for a 7.5 HP (5.5 kW) is 25 A. The default is 22.5 A.
The setting range is between 2.5–30 A. (25 × 10% = 2.5 A and 25 × 120% = 30 A)

✓ 05-02 Rated Power for Induction Motor 1(kW)

Default: Depending on the model power

Settings 0.00–655.35 kW

📖 Sets the rated power for motor 1. The default is the drive’s power value.

✓ 05-03 Rated Speed for Induction Motor 1 (rpm)

Default: Depending on the motor’s number of poles

Settings 0–xxxx rpm (Depending on the motor’s number of poles)
1710 (60 Hz 4 poles); 1410 (50 Hz 4 poles)

📖 Sets the rated speed for the motor as indicated on the motor nameplate.

📖 Pr.01-01 and Pr.05-04 determine the maximum rotor speed for IM.
For example: Pr.01-01 = 20 Hz, Pr.05-04 = 2, according to the equation 120 x 20 Hz / 2 = 1200

rpm and take integers. Due to the slip of the IM, the maximum setting value for Pr.05-03 is 1199 rpm (1200 rpm – 1).

05-04 Number of Poles for Induction Motor 1

Default: 4

Settings 2–64

- Sets the number poles for the motor (must be an even number).
- Set up Pr.01-01 and Pr.05-03 before setting up Pr.05-04 to make sure the motor operates normally. Pr.01-01 and Pr.05-03 determine the maximum set up number poles for the IM.
  For example: Pr.01-01 = 20 Hz and Pr.05-03 = 39 rpm, according to the equation 120 x 20 Hz / 39 rpm = 61.5 and take even number, the number of poles is 60. Therefore, Pr.05-04 can be set to the maximum of 60 poles.

05-05 No-load Current for Induction Motor 1 (A)

Default: Depending on the model power

Settings 0.0–Pr.05-01 default

- The default is 10–40% of motor rated current.
- For model with 110 kW and above, default setting is 20% of motor rated current.

05-06 Stator Resistance (Rs) for Induction Motor 1

Default: Depending on the model power

Settings 0.000–65.535 Ω

05-07 Rotor Resistance (Rr) for Induction Motor 1

Default: 0.000

Settings 0.000–65.535 Ω

05-08 Magnetizing Inductance (Lm) for Induction Motor 1

05-09 Stator Inductance (Lx) for Induction Motor 1

Default: 0.0

Settings 0.0–6553.5 mH

05-13 Full-load Current for Induction Motor 2 (A)

Default: Depending on the model power

Settings Depending on the model power

- Set this value according to the rated current of the motor as indicated on the motor nameplate. The default is 90% of the drive’s rated current.
  Example: The rated current for a 7.5 HP (5.5 kW) motor is 25 A. The default is 22.5 A.
  The setting range is between 2.5–30 A. (25 × 10% = 2.5 A and 25 × 120% = 30 A)

✎ **05-14** Rated Power for Induction Motor 2 (kW)

Default: Depending on the model power

Settings 0.00–655.35 kW

🕮 Set the rated power for motor 2. The default is the drive's power value.

✎ **05-15** Rated Speed for Induction Motor 2 (rpm)

Default: Depending on the motor's number of poles

Settings 0–xxxx rpm (Depending on the motor's number of poles)
1710 (60 Hz 4 poles); 1410 (50 Hz 4 poles)

🕮 Sets the rated speed for the motor as indicated on the motor nameplate.

05-16 Number of Poles for Induction Motor 2

Default: 4

Settings 2–64

🕮 Sets the number of poles for the motor (must be an even number).

🕮 Set up Pr.01-35 and Pr.05-15 before setting up Pr.05-16 to make sure the motor operates normally. Pr.01-35 and Pr.05-15 determine the maximum set up number of poles.
For example: Pr.01-35 = 20 Hz and Pr.05-15 = 39 rpm, according to the equation 120 x 20 Hz / 39 rpm = 61.5 and take even number, the number of poles is 60. Therefore, Pr.05-16 can be set to the maximum of 60 poles.

05-17 No-load Current for Induction Motor 2 (A)

Default: Depending on the model power

Settings 0.00–Pr.05-13 default

🕮 The default is 10–40% of motor rated current.

🕮 For model with 110 kW and above, default setting is 20% of motor rated current.

05-18 Stator Resistance (Rs) for Induction Motor 2

Default: Depending on the model power

Settings 0.000–65.535 Ω

05-19 Rotor Resistance (Rr) for Induction Motor 2

Default: 0.000

Settings 0.000–65.535 Ω

05-20 Magnetizing Inductance (Lm) for Induction Motor 2

05-21 Stator Inductance (Lx) for Induction Motor 2

Default: 0.0

Settings 0.0–6553.5 mH

05-22 Induction Motor 1 / 2 Selection

Default: 1

Settings 1: Motor 1

2: Motor 2

- Sets the motor currently operated by the AC motor drive.

✓ 05-23 Frequency for Y-connection / Δ-connection Switch for an Induction Motor

Default: 60.00

Settings 0.00–599.00 Hz

05-24 Y-connection / Δ-connection Switch for Induction Motor

Default: 0

Settings 0: Disable

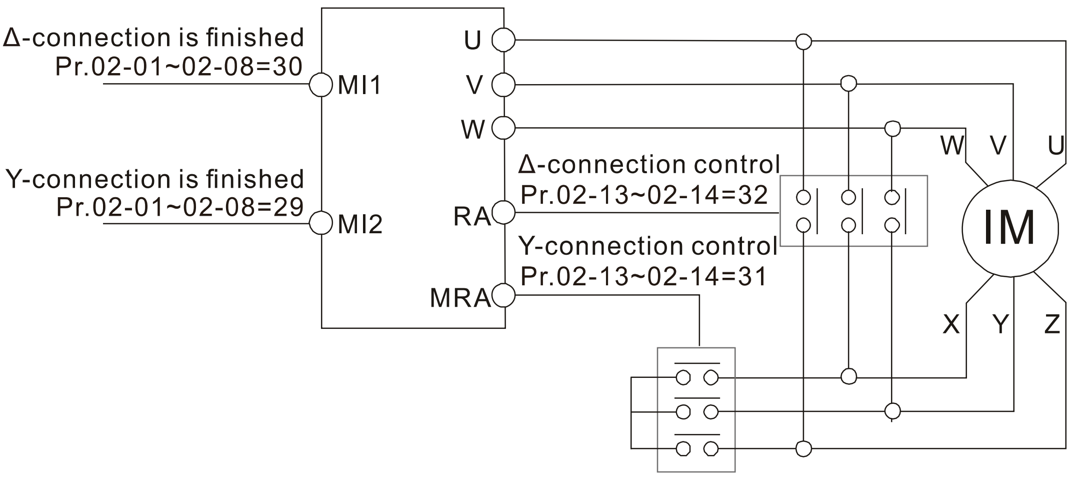
1: Enable

✓ 05-25 Delay Time for Y-connection / Δ-connection Switch for an Induction Motor

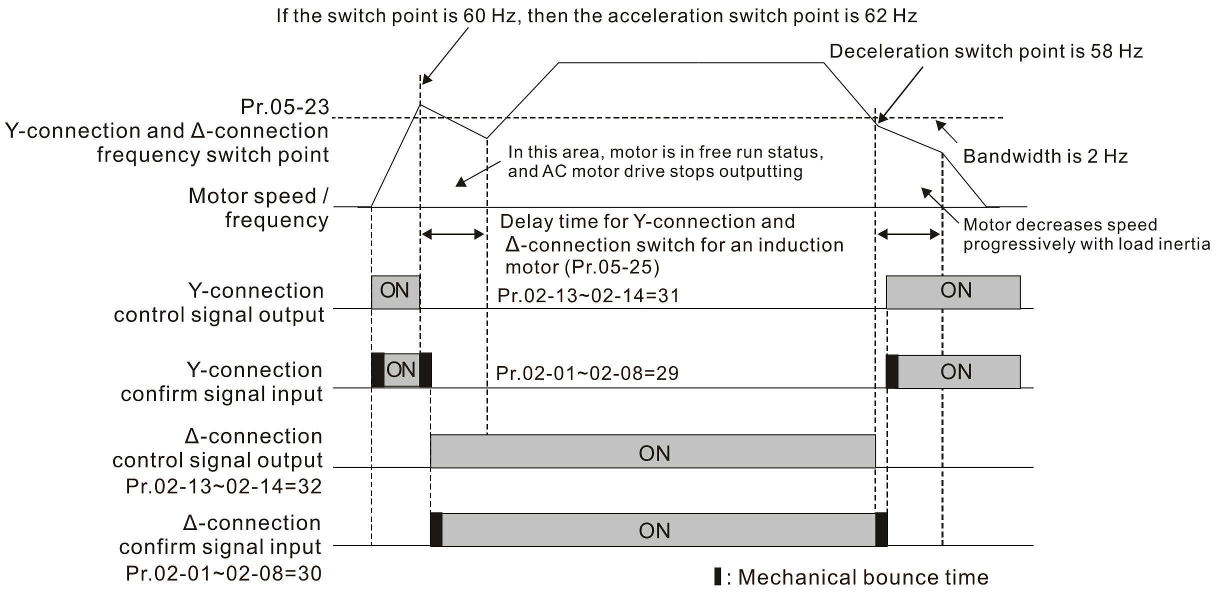
Default: 0.200

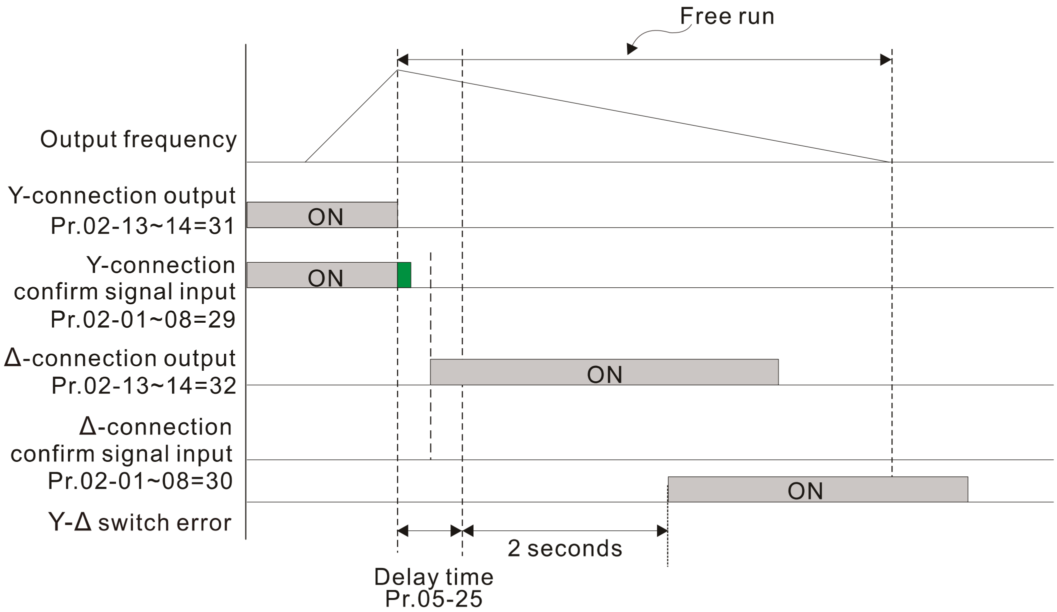
Settings 0.000–60.000 sec.

- You can apply Pr.05-23–Pr.05-25 in a wide range of motors, and the motor coil executes the Y-connection / Δ-connection switch as required. The wide range motors are related to the motor design. In general, the motor has higher torque with low speed Y-connection, and has higher speed with high speed Δ-connection).
- Pr.05-24 enables and disables the switch of Y-connection / Δ-connection.
- When you set Pr.05-24 as 1, the drive uses the Pr.05-23 setting and current motor frequency, and switches the current motor to Y-connection or Δ-connection. You can switch the relevant motor parameter settings simultaneously.
- Pr.05-25 sets the switch delay time of Y-connection / Δ-connection.
- When the output frequency reaches Y-connection / Δ-connection switch frequency, the drive delays according to Pr.05-25 before activating the multi-function output terminals.



Y-Δ connection switch: can be used for wide range motor
Y-connection for low speed: higher torque can be used for rigid tapping
Δ-connection for high speed: higher torque can be used for high-speed drilling


If the switch point is 60 Hz, then the acceleration switch point is 62 Hz
Deceleration switch point is 58 Hz
Pr.05-23
Y-connection and Δ-connection frequency switch point
Bandwidth is 2 Hz
In this area, motor is in free run status, and AC motor drive stops outputting
Motor speed / frequency
Delay time for Y-connection and Δ-connection switch for an induction motor (Pr.05-25)
Motor decreases speed progressively with load inertia
Y-connection control signal output
ON
Pr.02-13~02-14=31
ON
Y-connection confirm signal input
ON
Pr.02-01~02-08=29
ON
Δ-connection control signal output Pr.02-13~02-14=32
ON
Δ-connection confirm signal input Pr.02-01~02-08=30
ON
▮: Mechanical bounce time


Free run
Output frequency
Y-connection output Pr.02-13~14=31
ON
Y-connection confirm signal input Pr.02-01~08=29
ON
Δ-connection output Pr.02-13~14=32
ON
Δ-connection confirm signal input Pr.02-01~08=30
ON
Y-Δ switch error
2 seconds
Delay time Pr.05-25

05-28 Accumulated Watt-hour for a Motor (W-hour)

Default: Read only

Settings 0.0–6553.5

05-29 Accumulated Watt-hour for a Motor in Low Word (kW-hour)

Default: Read only

Settings 0.0–6553.5

05-30 Accumulated Watt-hour for a Motor in High Word (MW-hour)

Default: Read only

Settings 0–65535

- Pr.05-28–05-30 record the amount of power consumed by the motors. The accumulation begins when the drive is activated and the record is saved when the drive stops or turns OFF. The amount of consumed watts continues to accumulate when the drive is activated again. To clear the accumulation, set Pr.00-02 as 5 to return the accumulation record to 0.
- The accumulated total watts of the motor per hour = Pr.05-30 x 1000000 + Pr.05-29 x 1000 + Pr.05-28 Wh

Example: When Pr.05-30 = 76 MWh and Pr.05-29 = 150 kWh, Pr.05-28 = 400 Wh (or 0.4 kWh), the accumulated total kilowatts of the motor per hour = 76 x 1000000 + 150 x 1000 + 40 = 76150400Wh = 76150.4 kWh

05-31 Accumulated Motor Operation Time (Minutes)

Default: 0

Settings 0–1439

05-32 Accumulated Motor Operation Time (Days)

Default: 0

Settings 0–65535

📖 Use Pr.05-31 and Pr.05-32 to record the motor operation time. To clear the operation time, set Pr.05-31 and Pr.05-32 as 00. An operation time shorter than 60 seconds is not recorded.

05-33 Induction Motor (IM) or Permanent Magnet Synchronous AC Motor Selection

Default: 0

Settings 0: IM
1: SPM
2: IPM
3: SynRM (applied to 230V / 460V models)

05-34 Full-load Current for a Permanent Magnet Synchronous AC Motor / Reluctance Motor

Default: Depending on the model power

Settings Depending on the model power

📖 Sets the full-load current for the motor according to motor's nameplate. The default is 90% of the drive's rated current.

For example: The rated current of a 7.5 HP (5.5 kW) is 25 A. The default is 22.5 A.

The setting range is between 2.5–30 A. (25 × 10% = 2.5 A and 25 × 120% = 30 A)

✎ 05-35 Rated Power for a Permanent Magnet Synchronous AC Motor / Reluctance Motor

Default: Depending on the motor power

Settings 0.00–655.35 kW

📖 Sets the rated power for the permanent magnet synchronous motor. The default is the drive's power value.

✎ 05-36 Rated Speed for a Permanent Magnet Synchronous AC Motor / Reluctance Motor

Default: 2000

Settings 0–65535 rpm

05-37 Pole Number for a Permanent Magnet Synchronous AC Motor / Reluctance Motor

Default: 10

Settings 0–65535

05-38 System Inertia for a Permanent Magnet Synchronous AC Motor / Reluctance Motor

Default: Depending on the motor power

Settings 0.0–6553.5 kg-cm^2

🕮 Default values are as below:

Rated Power [kW]	0.4	0.75	1.5	2.2	3.7	5.5	7.5	9.3	11
Rotor Inertia [kg-cm^2]	1.2	3.0	6.6	15.8	25.7	49.6	82.0	121.6	177.0

Rated Power [kW]	14.1	18.2	27	33	40	46	54	54 and above
Rotor Inertia [kg-cm^2]	211.0	265.0	308.0	527.0	866.0	1082.0	1267.6	1515.0

05-39 Stator Resistance for a Permanent Magnet Synchronous AC Motor / Reluctance Motor

Default: 0.000

Settings 0.000–65.535 Ω

05-40 Permanent Magnet Synchronous AC Motor / Reluctance Motor Ld

Default: 0.00

Settings 0.00–655.35 mH

05-41 Permanent Magnet Synchronous AC Motor / Reluctance Motor Lq

Default: 0.00

Settings 0.00–655.35 mH

⚡ 05-43 Ke parameter for a Permanent Magnet Synchronous AC Motor

Default: 0

Settings 0–65535 V/krpm

🕮 Permanent magnet motor parameter Ke ($V_{phase, rms}$ / krpm).

🕮 When Pr.05-00 = 5, parameter Ke is calculated according to the motor's actual operation.

🕮 When Pr.05-00 = 13, parameter Ke is automatically calculated according to the motor power, current and rotor speed.

06 Protection Parameters

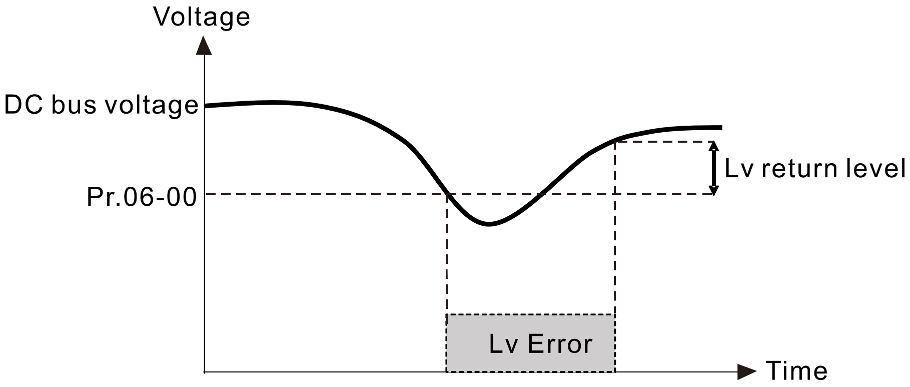
✎ You can set this parameter during operation.

✎ 06-00 Low Voltage Level

Settings		Default:
	230V models:	
	Frame A–D: 150.0–220.0 V_{DC}	180.0
	Frame E and above: 190.0–220.0 V_{DC}	200.0
	460V models:	
	Frame A–D: 300.0–440.0 V_{DC}	360.0
	Frame E and above: 380.0–440.0 V_{DC}	400.0
	575V models: 420.0–520.0 V_{DC}	470.0
	690V models: 450.0–660.0 V_{DC}	480.0

- Sets the Low Voltage (Lv) level. When the DC bus voltage is lower than Pr.06-00, a Lv fault is triggered, and the drive stops output and the motor coasts to stop.
- If the Lv fault is triggered during operation, the drive stops output and the motor coasts to stop. There are three Lv faults: LvA (Lv during acceleration), Lvd (Lv during deceleration), and Lvn (Lv in constant speed) that are triggered according to the status of acceleration or deceleration. You must press RESET to clear the Lv fault. The drive automatically restarts if you set to restart after momentary power loss (refer to Pr.07-06 Restart after Momentary Power Loss and Pr.07-07 Allowed Power Loss Duration for details).
- If the Lv fault is triggered when the drive is in STOP status, the drive displays LvS (Lv during stop), which is not recorded, and the drive restarts automatically when the input voltage is higher than Pr.06-00 + Lv return level (as listed below).

Lv Return Level	230V	460V	575V	690V
Frame A–D	30 V_{DC}	60 V_{DC}	100 V_{DC}	100 V_{DC}
Frame E–H	40 V_{DC}	80 V_{DC}	N/A	120 V_{DC}



✎ 06-01 Over-voltage Stall Prevention

Settings		Default:
	0: Disabled	
	230V models: 0.0–450.0 V_{DC}	380.0
	460V models: 0.0–900.0 V_{DC}	760.0
	575V models: 0.0–1116.0 V_{DC}	920.0
	690V models: 0.0–1318.0 V_{DC}	1087.0

- Setting Pr.06-01 to 0.0 disables the over-voltage stall prevention function (connected with braking unit or brake resistor). Use this setting when braking units or brake resistors are connected to the drive.
- Setting Pr.06-01 to a value > 0.0 enables the over-voltage stall prevention. This setting refers to the power supply system and loading. If the setting is too low, then over-voltage stall prevention is easily activated, which may increase the deceleration time.
- Related parameters:
  - Pr.01-13, Pr.01-15, Pr.01-17, Pr.01-19 Deceleration Time 1–4
  - Pr.02-13–Pr.02-15 Multiple-function Output (Relay1–3)
  - Pr.06-02 Selection for Over-voltage Stall Prevention.

✓ 06-02 Selection for Stall Prevention

Default: 0

Settings 0: Traditional over-voltage and traditional over-current stall prevention
1: Smart over-voltage and traditional over-current stall prevention
2: Traditional over-voltage and smart over-current stall prevention
3: Smart over-voltage and smart over-current stall prevention

---

- A comparison between traditional stall prevention and smart stall prevention:

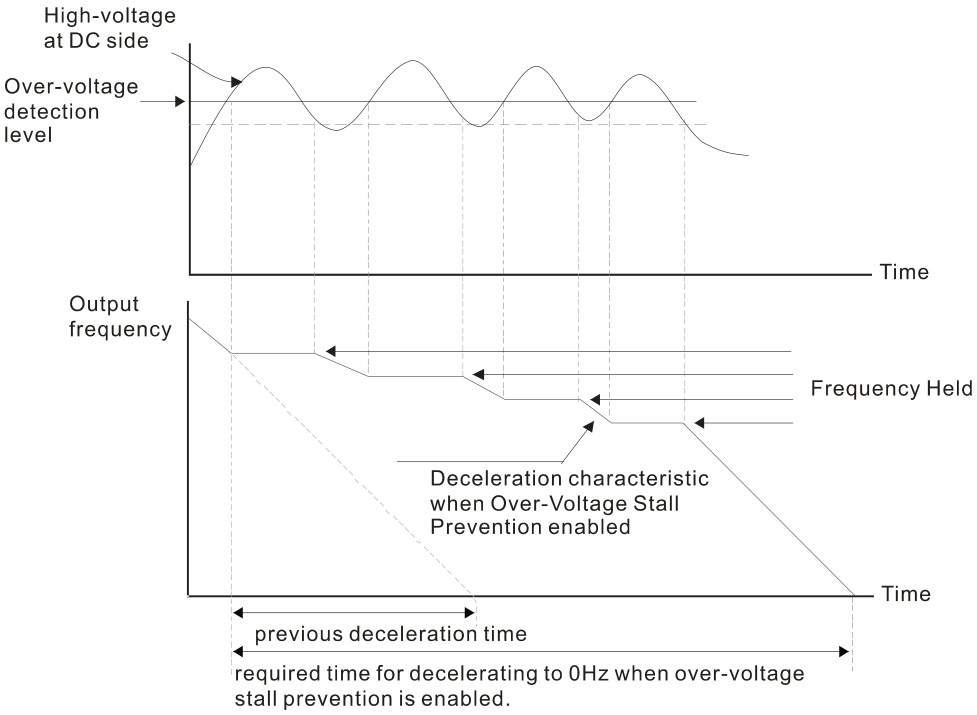
Type	Over-voltage			Over-current		
	Description	Action	Parameter	Description	Action	Parameter
Traditional	Frequency maintains during deceleration	Deceleration stops	Pr.06-01	Frequency maintains during acceleration	Acceleration stops	Pr.06-03
				Frequency decreases at constant speed	Frequency gradually decreases	Pr.06-04
Smart	Frequency increases during acceleration / deceleration / constant speed	Frequency gradually increases	Pr.06-01	Frequency decreases during acceleration / deceleration	Frequency gradually decreases	Pr.06-03
				Frequency decreases at constant speed	Frequency gradually decreases	Pr.06-04

- Pr.06-02 (Selection for stall prevention) can be used with Pr.01-49 (Regenerative energy restriction control method), but Pr.06-02 cannot work with Pr.01-44 (Auto-acceleration and auto-deceleration setting).
- When Pr.06-02 or Pr.01-49 is enabled (setting value > 0), Pr.01-44 (Auto-acceleration and auto-deceleration setting) automatically disables (setting value = 0) and cannot be set; when Pr.01-44 is enabled (setting value > 0), Pr.06-02 and Pr.01-49 automatically disable and cannot be set.
- If you use smart over-voltage or smart over-current stall prevention for industries that require fast response, you can decrease the deceleration time when needed.
- When using smart over-voltage stall prevention, the drive decelerates to stop with the fastest deceleration time according to different working condition, rather than the first to fourth deceleration time (Pr.01-13–01-19).

- For 220V / 440V 160 kW models and above, the default for Pr.06-02 is automatically set to 1 (Smart over-voltage and traditional over-current stall prevention). If you need to set the deceleration time with Pr.01-13–01-19, set Pr.06-02 = 0.
- Related parameters:
  Pr.06-01 Over-voltage stall prevention, Pr.06-03 Over-current stall prevention during acceleration, Pr.06-04 Over-current stall prevention during operation, Pr.06-05 Acceleration / deceleration time selection for stall prevention at constant speed, Pr.01-12–01-19 Acceleration / Deceleration time 1–4, and Pr.02-13–02-15 Multi-function output (Relay 1–3).

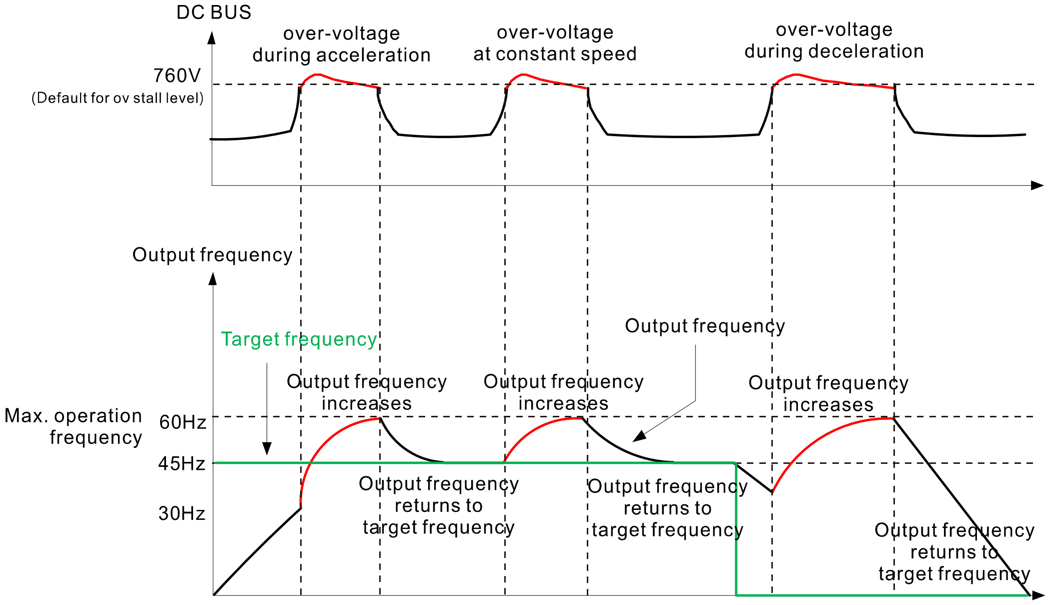
Traditional over-voltage stall prevention

- Used for uncertain load inertia. When it stops under normal load, the over-voltage does not occur during deceleration and fulfills the deceleration time setting. However, load regenerative inertia may occasionally increase and does not trip due to over-voltage when decelerating to stop. In this case, the drive automatically increases the deceleration time until it stops.
- Because of the motor load inertia, the motor may exceed the synchronous speed when the drive decelerates; in this case, the motor becomes generator. If the motor load inertia is larger, or the setting for drive's decelerating time is too small, the motor regenerates energy to the drive, and makes the DC bus voltage increase to the maximum allowable value. Thus, when traditional over-voltage stall prevention is enabled, the drive does not decelerate further and maintains the output frequency until the voltage drops below the setting value again.
- When the over-voltage stall prevention is enabled, the drive deceleration time is larger than the setting time.
- When there is a problem with the deceleration time, this function is disabled. See below for solution:
  1. Increase the deceleration time properly.
  2. Install a brake resistor (refer to Section 7-1 Brake Resistors and Brake Units Selection Chart for details) to dissipate the heat, that is, the electrical energy regenerating from the motor.


High-voltage at DC side
Over-voltage detection level
Time
Output frequency
Frequency Held
Deceleration characteristic when Over-Voltage Stall Prevention enabled
Time
previous deceleration time
required time for decelerating to 0Hz when over-voltage stall prevention is enabled.

Smart over-voltage stall prevention

- Adopts closed-loop control and takes the setting for Pr.06-01 over-voltage stall prevention as target command during acceleration, deceleration and constant speed. When the DC bus voltage is higher than the stall prevention level, the controller increases the output frequency gradually according to closed-loop response until the DC bus voltage drops below the stall prevention level, and returns to target frequency based on the previous setting for deceleration time when the DC bus voltage is lower than the stall prevention level. If the DC bus voltage is still higher than the stall prevention level during the adjustment, the output frequency increases to the maximum operation frequency (Pr.01-00).

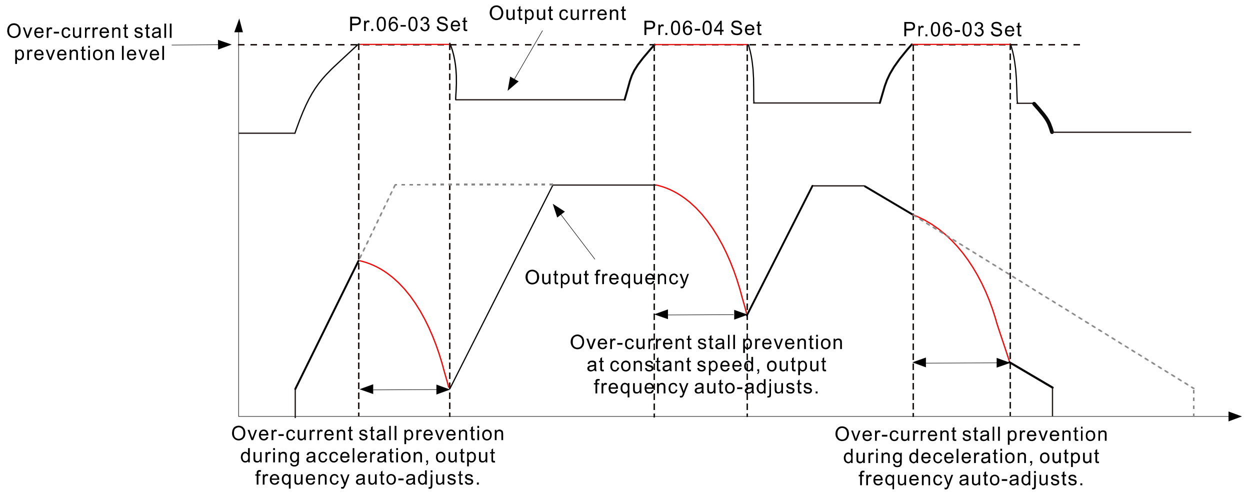

DC BUS
over-voltage during acceleration
over-voltage at constant speed
over-voltage during deceleration
760V
(Default for ov stall level)
Output frequency
Target frequency
Output frequency
Output frequency increases
Output frequency increases
Output frequency increases
Max. operation frequency
60Hz
45Hz
30Hz
Output frequency returns to target frequency
Output frequency returns to target frequency
Output frequency returns to target frequency

Traditional over-current stall prevention

- When the output current exceeds the over-current stall prevention level (Pr.06-03) during acceleration, the output frequency stops accelerating. The output frequency continues to accelerate when the output current drops below the stall prevention level to protect the drive.
- When the output current exceeds the over-current stall prevention during operation (Pr.06-04), the output frequency decreases according to the setting for acceleration / deceleration time selection for over-current stall prevention at constant speed (Pr.06-05). When the output current drops below the stall prevention level, the output frequency accelerates to the target frequency according to its previous set acceleration time.

Smart over-current stall prevention

- Adopts closed-loop control. It takes the setting for Pr.06-03 over-current stall prevention during acceleration as target command during acceleration and deceleration, and takes Pr.06-04 over-current stall prevention during operation as target command at constant speed. When the output current exceeds the stall prevention level, the controller decreases the output frequency gradually according to the closed-loop response until the current drops below the stall prevention level, and returns to target frequency based on the previous setting when the current is lower than the stall prevention level. If the output current is still higher than the stall prevention level during the adjustment, the output frequency decreases to the minimum output frequency at 0.5 Hz.


Over-current stall prevention level
Pr.06-03 Set
Output current
Pr.06-04 Set
Pr.06-03 Set
Output frequency
Over-current stall prevention at constant speed, output frequency auto-adjusts.
Over-current stall prevention during acceleration, output frequency auto-adjusts.
Over-current stall prevention during deceleration, output frequency auto-adjusts.

06-03 Over-current Stall Prevention during Acceleration

Default: 120

Settings 230V / 460V models

Light duty: 0–130% (100%: drive's rated current)

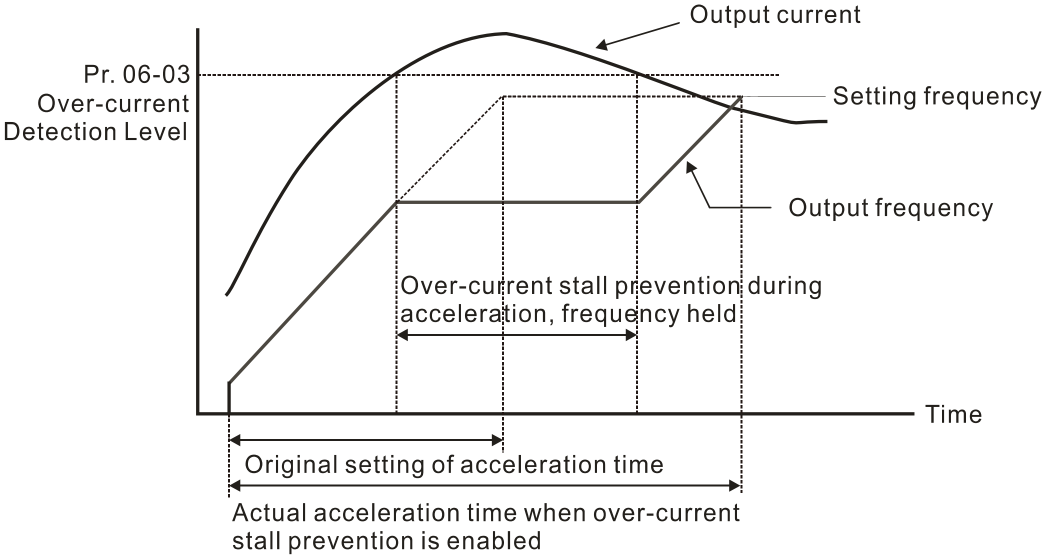
Normal duty: 0–160% (100%: drive's rated current)

575V / 690V models

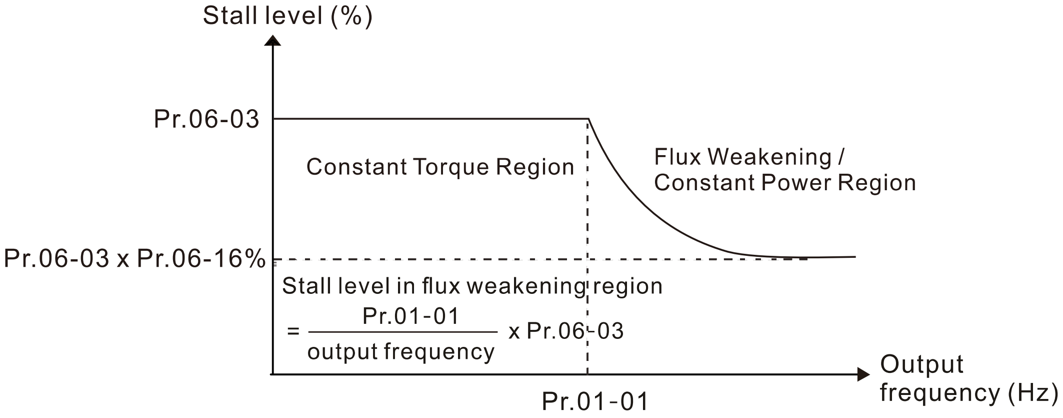
Light duty: 0–125% (100%: drive's rated current)

Normal duty: 0–150% (100%: drive's rated current)

- This parameter only works in VF and SVC control modes.
- If the motor load is too large or the drive's acceleration time is too short, the output current of the drive may be too high during acceleration, and it may cause motor damage or trigger the drive's protection functions (oL or oc). Use this parameter to prevent these situations.
- During acceleration, the output current of the drive may increase abruptly and exceed the setting value of Pr.06-03. In this case, the drive stops accelerating and keeps the output frequency constant, and then continues to accelerate until the output current decreases.


Output current
Pr. 06-03 Over-current Detection Level
Setting frequency
Output frequency
Over-current stall prevention during acceleration, frequency held
Time
Original setting of acceleration time
Actual acceleration time when over-current stall prevention is enabled

- Refer to Pr.06-16 for more details of stall level in flux weakening region. The protection curve is as following:



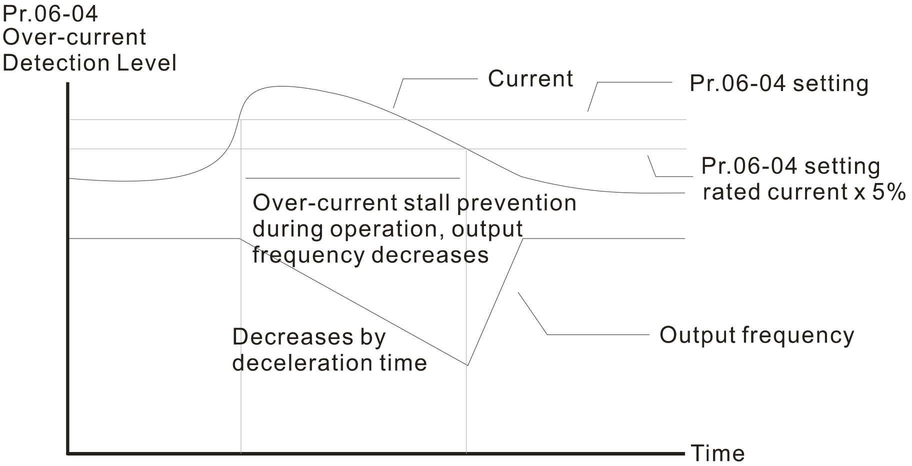
- 🕮 When you enable the over-current stall prevention, the drive's acceleration time is longer than the setting.
- 🕮 When the over-current stall prevention occurs because the motor capacity is too small or operates in the default, decrease the Pr.06-03 setting value.
- 🕮 If you encounter any problem with the acceleration time, refer to the following guides for troubleshooting:
  1. Increase the acceleration time to a proper value.
  2. Setting Pr.01-44 Auto-Acceleration and Auto-Deceleration Setting to 1, 3 or 4 (auto-acceleration).
- 🕮 Related parameters:
  - Pr.01-12, Pr.01-14, Pr.01-16, Pr.01-18 Acceleration Time 1–4
  - Pr.01-44 Auto-Acceleration and Auto-Deceleration Setting
  - Pr.02-13–02-15 Multi-function Output Relay1–3.

✓ 06-04 Over-current Stall Prevention during Operation

Default: 120

Settings 230V / 460V models
Light duty: 0–130% (100%: drive's rated current)
Normal duty: 0–160% (100%: drive's rated current)
575V / 690V models
Light duty: 0–125% (100%: drive's rated current)
Normal duty: 0–150% (100%: drive's rated current)

- 🕮 This parameter only works in VF and SVC control modes.
- 🕮 This is a protection for the drive to decrease output frequency automatically when the motor over-loads abruptly during constant motor operation.
- 🕮 If the output current exceeds the setting value for Pr.06-04 when the drive is operating, the drive decelerates according to the Pr.06-05 setting to prevent the motor from stalling. The lower limit for the over-current stall prevention is determined by the maximum value among 0.5 Hz, Pr.01-07 and Pr.01-11.
- 🕮 If the output current is lower than the setting value for Pr.06-04, the drive accelerates (according to Pr.06-05) again to the setting frequency.



Over-current stall prevention during operation

✓ 06-05 Acceleration / Deceleration Time Selection for Stall Prevention at Constant Speed

Default: 0

Settings
0: By current acceleration / deceleration time
1: By the first acceleration / deceleration time
2: By the second acceleration / deceleration time
3: By the third acceleration / deceleration time
4: By the fourth acceleration / deceleration time
5: By auto-acceleration / auto-deceleration

🕮 Sets the acceleration / deceleration time selection when stall prevention occurs at constant speed.

✓ 06-06 Over-torque Detection Selection (OT1)

Default: 0

Settings
0: No function
1: Continue operation after over-torque detection during constant speed operation
2: Stop after over-torque detection during constant speed operation
3: Continue operation after over-torque detection during RUN
4: Stop after over-torque detection during RUN

✓ 06-09 Over-torque Detection Selection (OT2)

Default: 0

Settings
0: No function
1: Continue operation after over-torque detection during constant speed operation
2: Stop after over-torque detection during constant speed operation
3: Continue operation after over-torque detection during RUN
4: Stop after over-torque detection during RUN

🕮 When you set Pr.06-06 and Pr.06-09 to 1 or 3, a warning message displays, but there is no error record.

🕮 When you set Pr.06-06 and Pr.06-09 to 2 or 4, an error message displays and there is an error record.

06-07 Over-torque Detection Level (OT1)

Default: 120

Settings 10–200% (100% corresponds to the light-duty rated current of the drive)

06-08 Over-torque Detection Level (OT1)

Default: 0.1

Settings 0.0–60.0 sec.

06-10 Over-torque Detection Level (OT2)

Default: 120

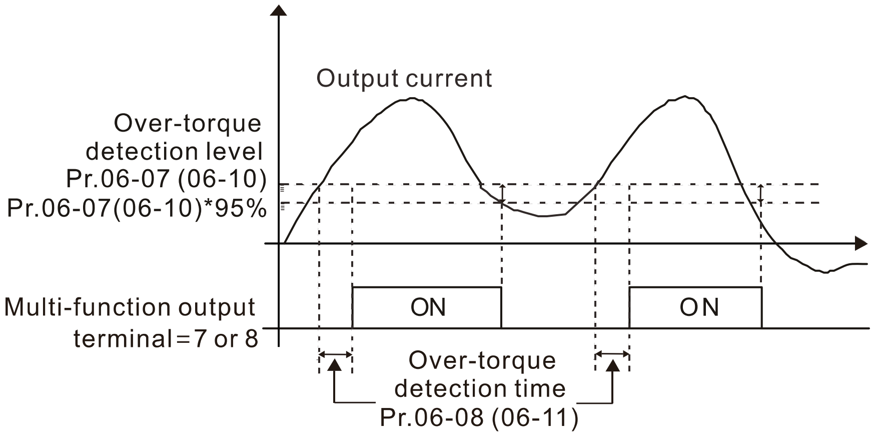
Settings 10–200% (100% corresponds to the light-duty rated current of the drive)

06-11 Over-torque Detection Time (OT2)

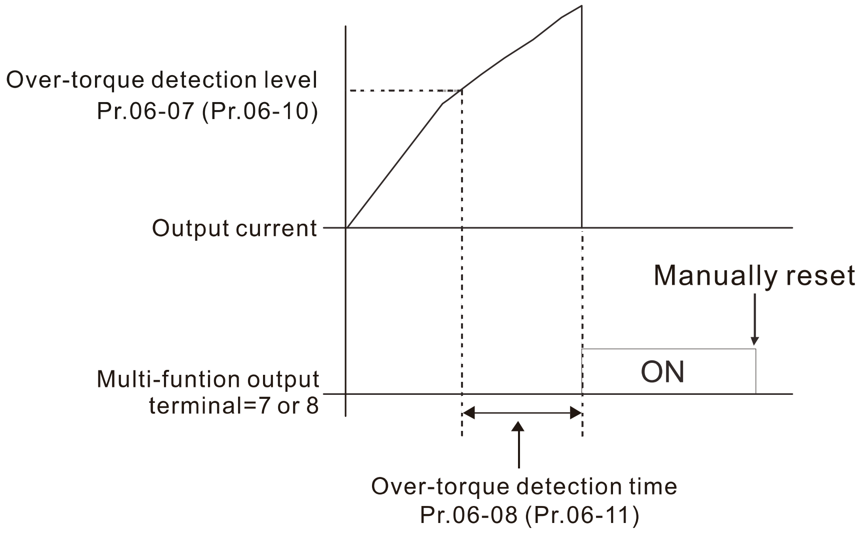
Default: 0.1

Settings 0.0–60.0 sec.

- When the output current exceeds the over-torque detection level (Pr.06-07 or Pr.06-10) and exceeds the over-torque detection time (Pr.06-08 or Pr.06-11), the over-torque detection follows the setting of Pr.06-06 and Pr.06-09.
- When you set Pr.06-06 or Pr.06-09 to 1 or 3, an ot1 / ot2 warning displays while the drive keeps running after over-torque detection. The warning remains on until the output current is smaller than 5% of the over-torque detection level.


Output current
Over-torque detection level
Pr.06-07 (06-10)
Pr.06-07(06-10)*95%
Multi-function output terminal=7 or 8
ON
ON
Over-torque detection time
Pr.06-08 (06-11)

- When you set Pr.06-06 or Pr.06-09 to 2 or 4, an ot1 / ot2 warning displays and the drive stops running after over-torque detection. The drive does not run until you manually reset it.


Over-torque detection level
Pr.06-07 (Pr.06-10)
Output current
Manually reset
ON
Multi-funtion output terminal=7 or 8
Over-torque detection time
Pr.06-08 (Pr.06-11)

✎ 06-12 Current Limit

Default: 150

Settings 0–200% (100% corresponds to the rated current of the drive)

- 🕮 Sets the maximum output current of the drive. Use Pr.11-17–Pr.11-20 to set the drive's output current limit. When setting the control mode to PMFOC and SynRM FOC, if the output frequency of the drive reaches this current limit, the output frequency decreases automatically. It works like the current stall prevention.
- 🕮 This parameter is invalid in VF and SVC control mode.

✎ 06-13 Electronic Thermal Relay Selection (Motor 1)

✎ 06-27 Electronic Thermal Relay Selection (Motor 2)

Default: 2

Settings 0: Inverter motor (with external forced cooling)
1: Standard motor (motor with fan on the shaft)
2: Disable

- 🕮 Prevents self-cooled motor from overheating under low speed. Use an electronic thermal relay to limit the drive's output power.
- 🕮 Setting the parameter to 0 is suitable for an inverter motor (motor fan using an independent power supply). For this kind of motor, there is no significant correlation between cooling capacity and motor speed. Therefore, the action of electronic thermal relays remains stable in low speed to ensure the load capability of the motor in low speed.
- 🕮 Setting the parameter to 1 is suitable for standard motor (motor fan is fixed on the rotor shaft). For this kind of motor, the cooling capacity is lower in low speed; therefore, the action of electronic thermal relay reduces the action time to ensure the life of motor.
- 🕮 When the power is cycled frequently, if the power is switched OFF, the electronic thermal relay protection is reset; therefore, even setting the parameter to 0 or 1 may not protect the motor well. If there are several motors connected to one drive, install an electronic thermal relay in each motor.

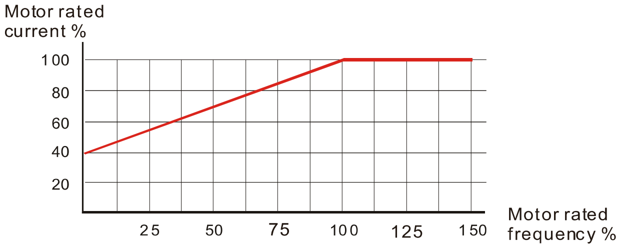
✎ 06-14 Electronic Thermal Relay Action Time 1 (Motor 1)

✎ 06-28 Electronic Thermal Relay Action Time 2 (Motor 2)

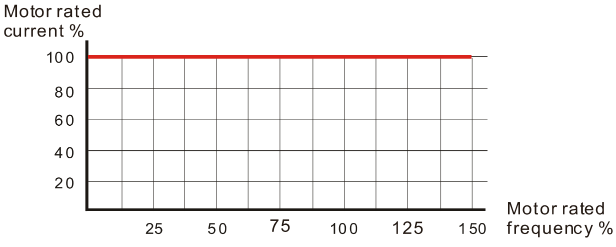
Default: 60.0

Settings 30.0–600.0 sec.

- 🕮 Set the parameter to 150% of motor rated current and use with the setting of Pr.06-14 and Pr.06-28 to prevent motor damage due to overheating. When it reaches the setting, the drive displays "EoL1 / EoL2", and the motor coasts to stop.
- 🕮 Use this parameter to set the action time of electronic thermal relay. It works based on the I^2t characteristic curve of electronic thermal relay, the output frequency and current of the drive, and the operation time to prevent motor from overheating.



Motor cooling curve with shaft-fixed fan



Motor cooling curve with independent fan

📖 The action of electronic thermal relay depends on the setting for Pr.06-13 and Pr.06-27.

1. Pr.06-13 or Pr.06-27 is set to 0 (using inverter motor)：

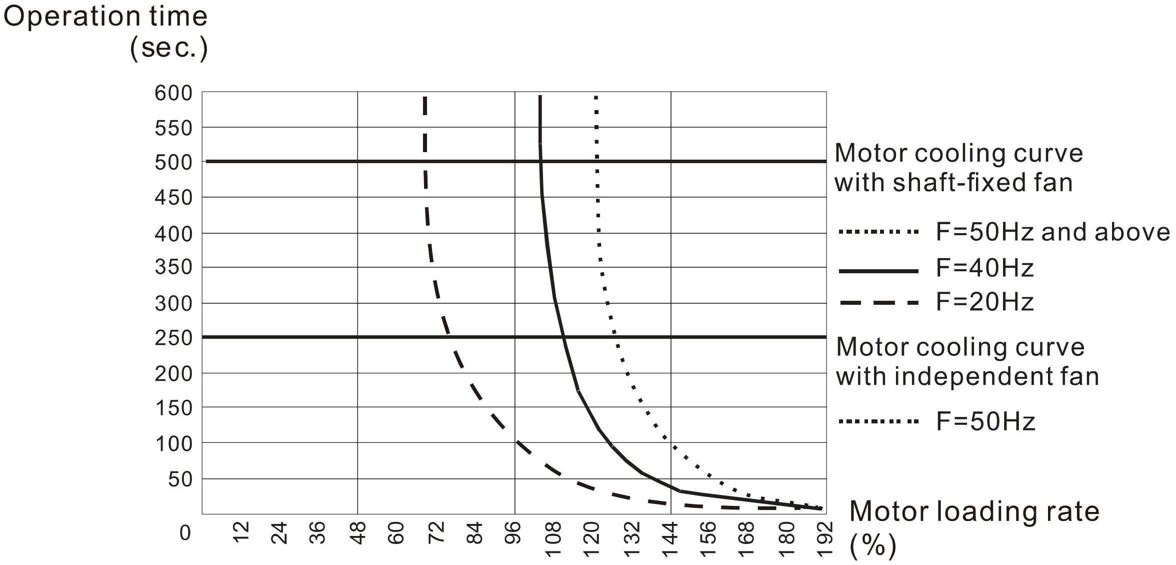
   When the output current of motor drive is higher than 150% of the motor rated current (refer to the motor rated current % corresponded to the motor rated frequency in the motor cooling curve with independent fan), motor drive starts to count the time. The electronic thermal relay acts when the accumulated time exceeds Pr.06-14 or 06-28.

2. Pr.06-13 or Pr.06-27 is set to 1 (using standard motor)：

   When the output current of the drive is higher than 150% of the motor rated current (refer to the motor rated current % corresponded to the motor rated frequency in the motor cooling curve with shaft-fixed fan), the drive starts to count the time. The electronic thermal relay acts when the accumulated time exceeds Pr.06-14 or 06-28

3. If the motor's rated current (Pr.05-01) is not set, set 90% of the drive's rated current (Pr.00-01) as the default for this parameter.

📖 The actual electronic thermal relay action time adjusts according to the drive output current (shown as the motor loading rate %). The action time is short when the current is high, and the action time is long when the current is low. Refer to following diagram: (The motor cooling curve with shaft-fixed fan and motor cooling curve with independent fan F = 50 Hz are the same one.)



06-15 Temperature Level Overheat (oH) Warning

Default: 105.0

Settings 0.0–110.0°C

📖 If Pr.06-15 is set to 110°C, when the temperature reaches 110°C, the drive stops with an IGBT overheat fault.

- For Frame C and above, when IGBT temperature is above Pr.06-15 minus 15°C, the cooling fan enhances performance to 100%; however, when IGBT temperature is below 35°C of Pr.06-15 and the temperature of capacitance is below 10°C of oH2 over-heat warning (Pr.06-51), the cooling fan resets. The temperature 35°C is the criterion if Pr.06-15 is set below to 35°C.

⚡ 06-16 Stall Prevention Limit Level (Weak Magnetic Area Current Stall Prevention Level)

Default: 50

Settings 0–100% (Refer to Pr.06-03)

- Sets the over-current stall prevention level when the motor's operation frequency is larger than Pr.01-01 (base frequency). This parameter only works during acceleration.
- Example: Pr.06-03 = 150%, Pr.06-04 = 100% and Pr.06-16 = 80%, when the operation frequency is larger than Pr.01-01, the lowest over-current stall prevention level during acceleration is: Pr.06-03 × Pr.06-16 = 150 × 80% = 120%. (Refer to Pr.06-03 diagram for the protection curve)
- Pr.06-16 is invalid when the over-current stall prevention activates according to Pr.06-04 at constant speed.

06-17 Fault Record 1
06-18 Fault Record 2
06-19 Fault Record 3
06-20 Fault Record 4
06-21 Fault Record 5
06-22 Fault Record 6

Settings

0: No fault record
1: Over-current during acceleration (ocA)
2: Over-current during deceleration (ocd)
3: Over-current during steady speed (ocn)
4: Ground fault (GFF)
5: IGBT short-circuit between upper bridge and lower bridge (occ)
6: Over-current at stop (ocS)
7: Over-voltage during acceleration (ovA)
8: Over-voltage during deceleration (ovd)
9: Over-voltage at constant speed (ovn)
10: Over-voltage at stop (ovS)
11: Low-voltage during acceleration (LvA)
12: Low-voltage during deceleration (Lvd)
13: Low-voltage at constant speed (Lvn)
14: Low-voltage at stop (LvS)
15: Phase loss protection (OrP)
16: IGBT overheating (oH1)
17: Heatsink overheating (oH2)
18: IGBT temperature detection failure (tH1o)

19: Capacitor hardware error (tH2o)
21: Over load (oL)
22: Electronic thermal relay 1 protection (EoL1)
23: Electronic thermal relay 2 protection (EoL2)
24: Motor overheating (oH3) (PTC / PT100)
26: Over torque 1 (ot1)
27: Over torque 2 (ot2)
28: Under current (uC)
30: EEPROM write error (cF1)
31: EEPROM read error (cF2)
33: U-phase error (cd1)
34: V-phase error (cd2)
35: W-phase error (cd3)
36: cc (current clamp) hardware error (Hd0)
37: oc (over-current) hardware error (Hd1)
38: ov (over-voltage) hardware error (Hd2)
39: occ hardware error (Hd3)
40: Auto-tuning error (AUE)
41: PID loss ACI (AFE)
48: ACI loss (ACE)
49: External fault (EF)
50: Emergency stop (EF1)
51: External base block (bb)
52: Enter wrong password three times and locked (Pcod)
53: Firmware version error (ccod)
54: Illegal command (CE1)
55: Illegal data address (CE2)
56: Illegal data value (CE3)
57: Data is written to read-only address (CE4)
58: Modbus transmission time-out (CE10)
60: Brake transistor error (bF)
61: Y-connection / ∆-connection switch error (ydc)
62: Deceleration energy backup error (dEb)
63: Over slip error (oSL)
64: Electric valve switch error (ryF)
68: Reverse direction of the speed feedback (SdRv)
69: Over speed rotation feedback (SdOr)
70: Large deviation of speed feedback (SdDe)
71: Watchdog (WDTT)
72: STO loss 1 (STL1)
73: Emergency stop for external safety (S1)
74: FIRE mode output (Fire)

76: Safety Torque Off (STO)
77: STO loss 2 (STL2)
78: STO loss 3 (STL3)
82: Output phase loss U phase (OPHL)
83: Output phase loss V phase (OPHL)
84: Output phase loss W phase (OPHL)
89: Rotor position detection error (RoPd)
90: Forced to stop (FStp)
101: CANopen guarding error (CGdE)
102: CANopen heartbeat error (CHbE)
104: CANopen bus off error (CbFE)
105: CANopen index error (CidE)
106: CANopen station address error (CAdE)
107: CANopen memory error (CFrE)
111: InrCOM time-out error (ictE)
142: Auto-tuning error 1 (no feedback current error) (AUE1)
143: Auto-tuning error 2 (motor phase loss error) (AUE2)
144: Auto-tuning error 3 (no-load current I_0 measuring error) (AUE3)
148: Auto-tuning error (leakage inductance Lsigma measuring error) (AUE4)

🕮 The parameters record when the fault occurs and forces a stop.

🕮 When low-voltage at stop fault (LvS) occurs, the fault is not recorded. When low-voltage during operation faults (LvA, Lvd, Lvn) occur, the faults are recorded.

🕮 When dEb function is valid and enabled, the drive executes dEb and records fault code 62 to Pr.06-17–Pr.06-22 simultaneously.

06-23 Fault Output Option 1
06-24 Fault Output Option 2
06-25 Fault Output Option 3
06-26 Fault Output Option 4

Default: 0

Settings 0–65535 (Refer to bit table for fault code)

🕮 Use these parameters with multi-function output terminal (set Pr.06-23–Pr.06-26 to 35–38) for the specific requirement. When the fault occurs, the corresponding terminals are activated. Convert the binary value to decimal value before you enter the value for Pr.06-23–Pr.06-26).

Fault Code	bit0	bit1	bit2	bit3	bit4	bit5	bit6
	current	Volt.	OL	SYS	FBK	EXI	CE
0: No fault							
1: Over-current during acceleration (ocA)	●						
2: Over-current during deceleration (ocd)	●						
3: Over-current during steady speed (ocn)	●						
4: Ground fault (GFF)	●						

Fault Code	bit0	bit1	bit2	bit3	bit4	bit5	bit6
	current	Volt.	OL	SYS	FBK	EXI	CE
5: IGBT short-circuit between upper bridge and lower bridge (occ)	●						
6: Over-current at stop (ocS)	●						
7: Over-voltage during acceleration (ovA)		●					
8: Over-voltage during deceleration (ovd)		●					
9: Over-voltage at constant speed (ovn)		●					
10: Over-voltage at stop (ovS)		●					
11: Low-voltage during acceleration (LvA)		●					
12: Low-voltage during deceleration (Lvd)		●					
13: Low-voltage at constant speed (Lvn)		●					
14: Low-voltage at stop (LvS)		●					
15: Phase loss protection (OrP)		●					
16: IGBT overheating (oH1)			●				
17: Heatsink overheating (oH2)			●				
18: IGBT temperature detection failure (tH1o)			●				
19: Capacitor hardware error (tH2o)			●				
21: Over load (oL)			●				
22: Electronic thermal relay 1 protection (EoL1)			●				
23: Electronic thermal relay 2 protection (EoL2)			●				
24: Motor overheating (oH3) (PTC / PT100)			●				
26: Over torque 1 (ot1)			●				
27: Over torque 2 (ot2)			●				
28: Under current (uC)	●						
30: EEPROM write error (cF1)				●			
31: EEPROM read error (cF2)				●			
33: U-phase error (cd1)				●			
34: V-phase error (cd2)				●			
35: W-phase error (cd3)				●			
36: cc (current clamp) hardware error (Hd0)				●			
37: oc (over-current) hardware error (Hd1)				●			
38: ov (over-voltage) hardware error (Hd2)				●			
39: occ hardware error (Hd3)				●			
40: Auto-tuning error (AUE)				●			
41: PID loss ACI (AFE)					●		
48: ACI loss (ACE)					●		
49: External fault (EF)						●	
50: Emergency stop (EF1)						●	
51: External base block (bb)						●	
52: Enter wrong password three times and locked (Pcod)				●			
53: Firmware version error (ccod)				●			

Fault Code	bit0	bit1	bit2	bit3	bit4	bit5	bit6
	current	Volt.	OL	SYS	FBK	EXI	CE
54: Illegal command (CE1)							●
55: Illegal data address (CE2)							●
56: Illegal data value (CE3)							●
57: Data is written to read-only address (CE4)							●
58: Modbus transmission time-out (CE10)							●
60: Brake transistor error (bF)						●	
61: Y-connection/Δ-connection switch error (ydc)						●	
62: Deceleration energy backup error (dEb)		●					
63: Over slip error (oSL)						●	
64: Electric valve switch error (ryF)						●	
68: Reverse direction of the speed feedback (SdRv)					●		
69: Over speed rotation feedback (SdOr)					●		
70: Large deviation of speed feedback (SdDe)					●		
71: Watchdog (WDTT)				●			
72: STO loss 1 (STL1)				●			
73: Emergency stop for external safety (S1)				●			
74: FIRE mode output (Fire)						●	
76: Safety Torque Off (STO)				●			
77: STO loss 2 (STL2)				●			
78: STO loss 3 (STL3)				●			
82: Output phase loss U phase (OPHL)	●						
83: Output phase loss V phase (OPHL)	●						
84: Output phase loss W phase (OPHL)	●						
89: Rotor position detection error (RoPd)				●			
90: Forced to stop (FStp)				●			
101: CANopen guarding error (CGdE)							●
102: CANopen heartbeat error (CHbE)							●
104: CANopen bus off error (CbFE)							●
105: CANopen index error (CIdE)							●
106: CANopen station address error (CAdE)							●
107: CANopen memory error (CFrE)							●
111: InrCOM time-out error (ictE)							●
142: Auto-tuning error 1 (no feedback current error) (AUE1)	●						
143: Auto-tuning error 2 (motor phase loss error) (AUE2)				●			
144: Auto-tuning error 3 (no-load current I_0 measuring error) (AUE3)	●						
148: Auto-tuning error 4 (leakage inductance Lsigma measuring error) (AUE4)	●						

ϟ 06-29 PTC Detection Selection / PT100 Motion

Default: 0

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop
3: No warning

🕮 Sets the operation mode of a drive after detecting PTC / PT100 / KTY84 detection.

ϟ 06-30 PTC Level

Default: 50.0

Settings 0.0–100.0%

🕮 Sets AVI1 / ACI / AVI2 analog input function Pr.03-00–03-02 to 6 [Thermistor (PTC) input value].

🕮 Use this to set the PTC level, the corresponding value for 100% is the analog input maximum value.

06-31 Frequency Command at Malfunction

Default: Read only

Settings 0.00–599.00 Hz

🕮 When a malfunction occurs, check the current frequency command. If it happens again, it overwrites the previous record.

06-32 Output Frequency at Malfunction

Default: Read only

Settings 0.00–599.00 Hz

🕮 When a malfunction occurs, check the current output frequency. If it happens again, it overwrites the previous record.

06-33 Output Voltage at Malfunction

Default: Read only

Settings 0.0–6553.5 V

🕮 When a malfunction occurs, check the current output voltage. If it happens again, it overwrites the previous record.

06-34 DC bus Voltage at Malfunction

Default: Read only

Settings 0.0–6553.5 V

🕮 When a malfunction occurs, check the current DC bus voltage. If it happens again, it overwrites the previous record.

06-35 Output Current at Malfunction

Default: Read only

Settings 0.0–6553.5 Amp

🕮 When a malfunction occurs, check the current output current. If it happens again, it overwrites the previous record.

06-36 IGBT Temperature at Malfunction

Default: Read only

Settings -3276.7–3276.7°C

🕮 When a malfunction occurs, check the current IGBT temperature. If it happens again, it overwrites the previous record.

06-37 Capacitance Temperature at Malfunction

Default: Read only

Settings -3276.7–3276.7°C

🕮 When a malfunction occurs, check the current capacitance temperature. If it happens again, it overwrites the previous record.

06-38 Motor Speed in rpm at Malfunction

Default: Read only

Settings -32767–32767 rpm

🕮 When a malfunction occurs, check the current motor speed in rpm. If it happens again, it overwrites the previous record.

06-40 Status of Multi-function Input Terminal at Malfunction

Default: Read only

Settings 0000h–FFFFh

06-41 Status of Multi-function Output Terminal at Malfunction

Default: Read only

Settings 0000h–FFFFh

🕮 When a malfunction occurs, check the current status of multi-function input / output terminals. If it happens again, it overwrites the previous record.

06-42 Drive Status at Malfunction

Default: Read only

Settings 0000h–FFFFh

🕮 When a malfunction occurs, check the current drive status (communication address 2101H). If it happens again, it overwrites the previous record.

✓ 06-44 STO Latch Selection

Default: 0

Settings 0: STO Latch
1: STO No latch

🕮 Pr.06-44 = 0: STO Alarm Latch. After you clear the cause of the STO Alarm, use a Reset command to clear the STO Alarm.

🕮 Pr.06-44 = 1: STO Alarm no Latch. After you clear the cause of the STO Alarm, the STO Alarm clears automatically.

🕮 All of STL1–STL3 errors are “Alarm Latch” mode (in STL1–STL3 mode, the Pr.06-44 function is not available).

06-45 Output Phase Loss Detection Action (OPHL)

Default: 3

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop
3: No warning

🕮 The OPHL protection is enabled when Pr.06-45 is not set to 3.

06-46 Detection Time of Output Phase Loss

Default: 0.500

Settings 0.000–65.535 sec.

06-47 Current Detection Level for Output Phase Loss

Default: 1.00

Settings 0.00–100.00%

06-48 DC Brake Time of Output Phase Loss

Default: 0.000

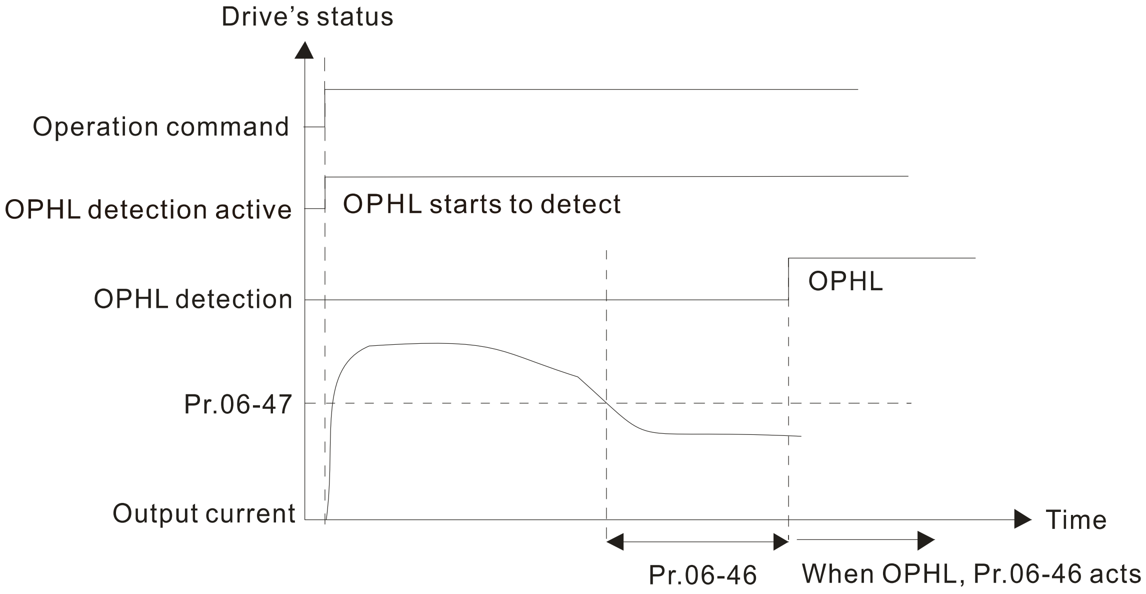
Settings 0.000–65.535 sec.

🕮 There are two situations for the output phase loss detection: “detect when the drive is in operation” and “detect before operation”. Setting Pr.06-48 to 0 disables the OPHL detection function before operation.

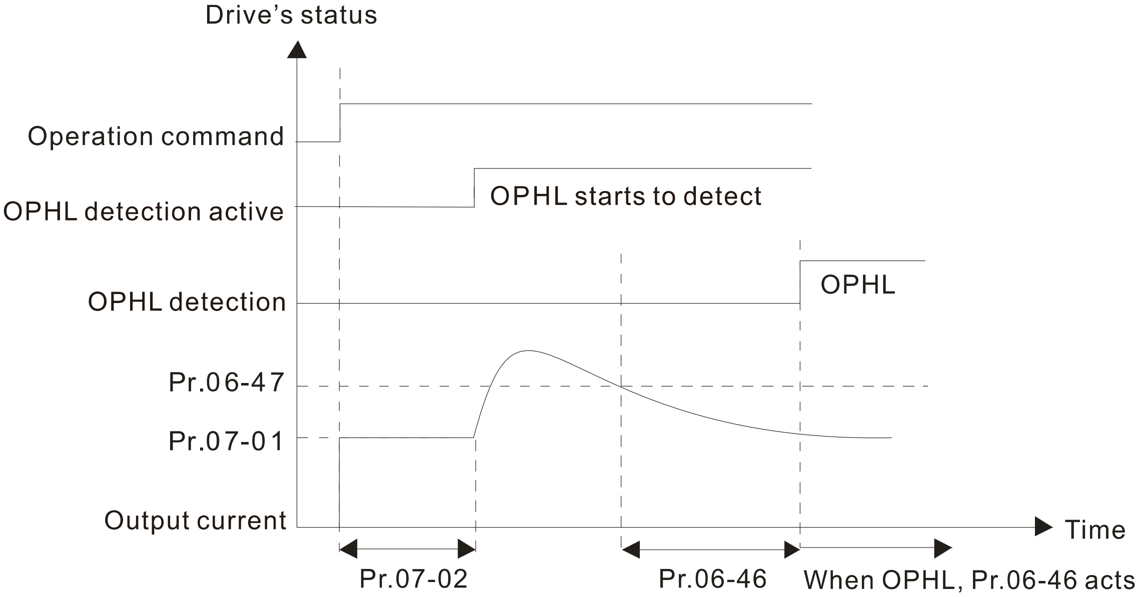
🕮 The status of output phase loss detection are as following:

- ● Status 1: The drive is in operation

  When any phase is less than the Pr.06-47 setting, and exceeds Pr.06-46 setting time, the drive executes according to the Pr.06-45 setting.

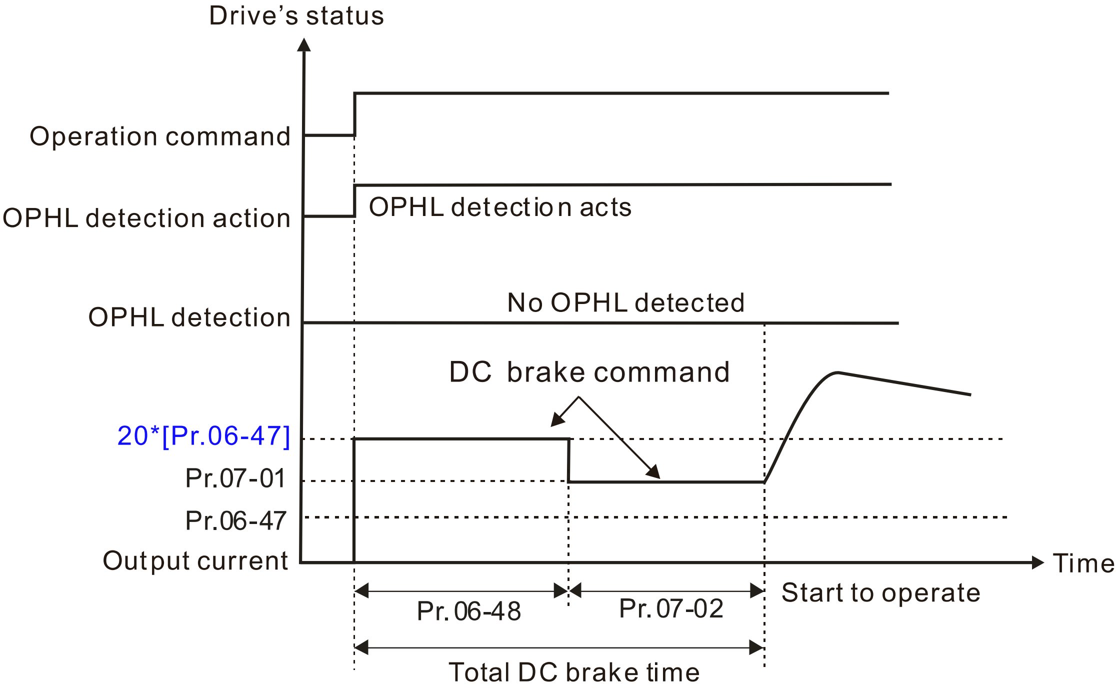


- Status 2: The drive is in STOP; Pr.06-48 = 0 ; Pr.07-02 ≠ 0
  After the drive starts, the DC brake operates according to Pr.07-01 and Pr.07-02. During this period, OPHL detection is not active. After the DC brake action is completed, the drive starts to run, and enables the OPHL protection as mentioned above for status 1.



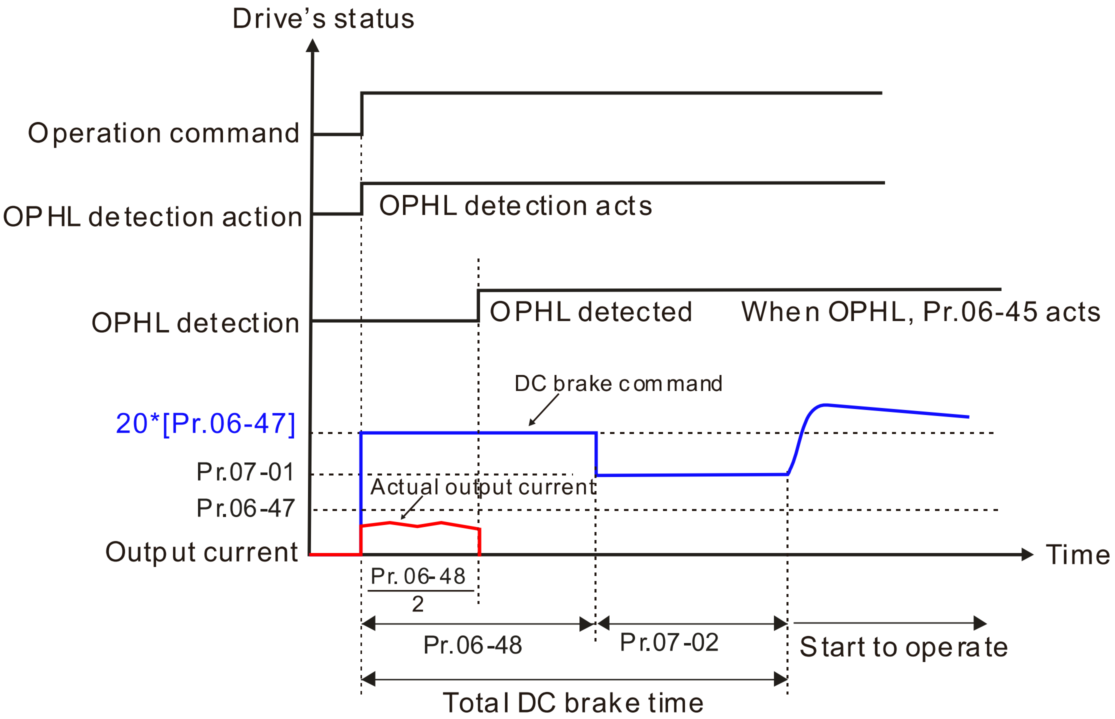
- Status 3: The drive is in STOP; Pr.06-48≠0 ; Pr.07-02≠0
  When the drive starts, it executes Pr.06-48 first, and then executes Pr.07-02 (DC brake). The DC brake current level in this state includes two parts: one is 20 times the Pr.06-47 setting value in Pr.06-48 setting time; the other is the Pr.07-02 setting value in Pr.07-01 setting time. The total DC brake time is T = Pr.06-48 + Pr.07-02.

Status 3-1: Pr.06-48 ≠ 0, Pr.07-02 ≠ 0 (No OPHL detected before operation)



Status 3-2: Pr.06-48 ≠ 0, Pr.07-20 ≠ 0 (OPHL detected before operation)

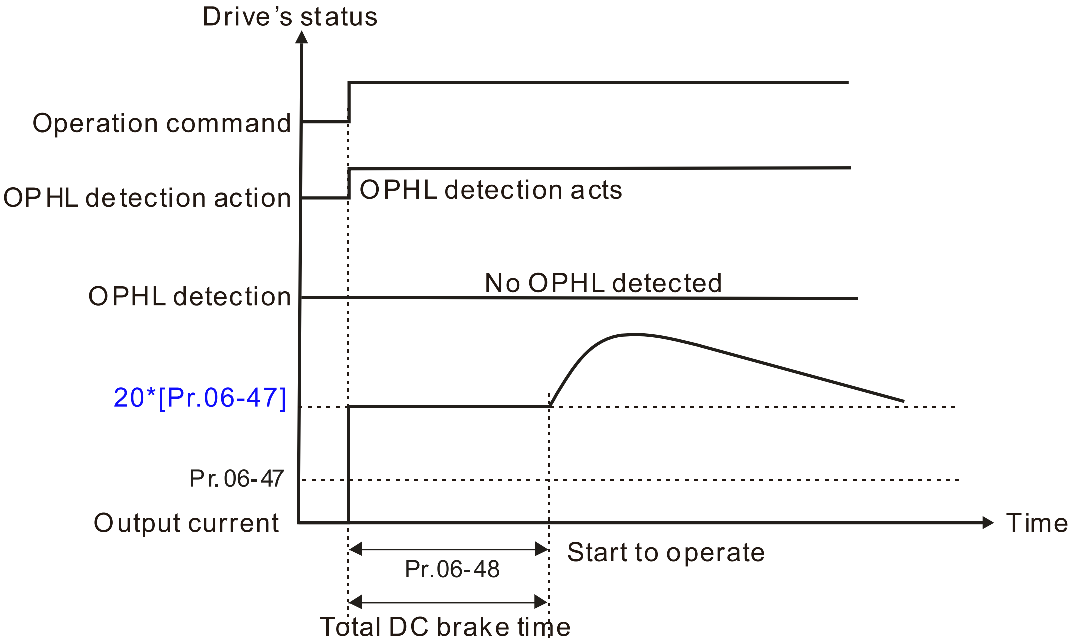
In this period, if an OPHL occurs within the time for Pr.06-48, the drive executes the Pr.06-45 setting after the drive starts counting for half the time of Pr.06-48.



- Status 4: The drive is in STOP; Pr.06-48 ≠ 0 ; Pr.07-02 = 0

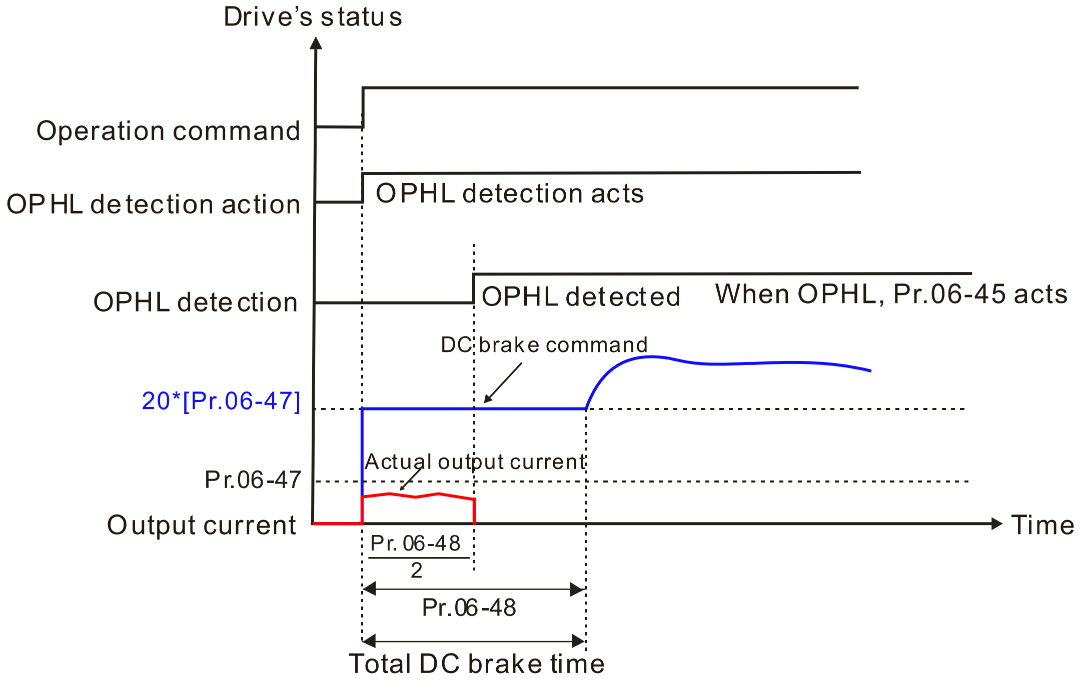
When the drive starts, it executes Pr.06-48 as the DC brake. The DC brake current level is 20 times the Pr.06-47 setting value.

Status 4-1: Pr.06-48 ≠ 0, Pr.07-02 = 0 (No OPHL detected before operation)



Status 4-2: Pr.06-48 ≠ 0, Pr.07-02 = 0 (OPHL detected before operation)

In this period, if an OPHL occurs within the time for Pr.06-48, the drive executes the Pr.06-45 setting after the drive starts counting for half the time of Pr.06-48.



06-49 LvX Auto-Reset

Default: 0

Settings 0: Disable

1: Enable

06-50 Time for Input Phase Loss Detection

Default: 0.20

Settings 0.00–600.00 sec.

Sets the time for input phase loss detection; setting 0.20 seconds means to check every 0.20 sec.

06-52 Ripple of Input Phase Loss

Default:

30.0/ 60.0/ 75.0/ 90.0

Settings 230V models: 0.0–100.0 V_{DC}

460V models: 0.0–200.0 V_{DC}

575V models: 0.0–400.0 V_{DC}

690V models: 0.0–480.0 V_{DC}

When the drive detects the DC bus ripple is higher than the setting for Pr.06-52, and lasts for the time of Pr.06-50 plus 30 seconds, the drive executes the input phase loss protection according to Pr.06-53.

In the period of Pr.06-50 setting plus 30 seconds, if the DC bus ripple is lower than the setting for Pr.06-52, the OrP protection recalculates.

✎ 06-53 Input Phase Loss Detection Action (OrP)

Default: 0

Settings 0: Fault and ramp to stop

1: Fault and coast to stop

📖 When the DC bus ripple voltage lasts for Pr.06-50 ripple time, the drive activates the Input Phase Loss protection according to the Pr.06-53 settings:

- DC bus ripple frequency ≤ 166 Hz
- The amplitude is higher than Pr.06-52 setting [default 30 V (230V models), 60 V (460V models)]. It starts to count time after 20 consecutive times.
- When the counting lasts for the following time conditions, an ORP occurs.

(I)% is rated current percentage

(I)%	Actual seconds
50	432
75	225
120	60

📖 When any of the above conditions is not met, the ORP protection recalculates.

✎ 06-55 Derating Protection

Default: 0

Settings 0: Auto-decrease carrier frequency and limit output current

1: Constant carrier frequency and limit output current

2:Auto-decrease carrier frequency

📖 Refer to Pr.00-01 (Maximum Operation Frequency) for allowable maximum output frequency in each control mode.

📖 The corresponded carrier frequency lower limit under each control mode:

- VF, SVC: 599 Hz, 6K
- FOC sensorless (IM): 300 Hz, 6K
- FOC sensorless (PM): 500 Hz, 10K

📖 Refer to the Section 9-7 Derating for Ambient Temperature, Altitude and Carrier Frequency for the derating ratio.

📖 Setting 0:

- Actual over-current stall prevention level = derating ratio × over-current stall prevention level (Pr.06-03 and Pr.06-04).
- Rated current derating level: derating ratio × rated current (Pr.00-01).
- When the operating point is greater than the derating curve, the carrier frequency (Fc) output by the drive decreases automatically according to the ambient temperature, overload output current and time.
- Applicable conditions: If overloads are not frequent, and the concern is only about the carrier frequency operating with the rated current for a long time, and changes to the carrier wave due to short overload are acceptable, set to 0.
- Take VFD007CP43A Normal Duty for example: ambient temperature 50°C, UL Open Type, and independent installation. When the carrier frequency is set to 15 kHz, it corresponds to

72% of the derating ratio. When the output current is higher than the value, it automatically decreases the carrier frequency according to the ambient temperature, output current and overload time (for example: set Pr.06-03 to 200%). At this time, the over-current stall prevention level is 144% (= 72% × 200%) of the rated current (Pr.00-01).

📖 Setting 1:

- When the operating point is greater than the derating curve 1, the carrier frequency (Fc) output by the drive is fixed to the default value.
- Applicable conditions: Select this mode if the change of carrier frequency and motor noise caused by ambient temperature and frequent overload are not acceptable. Refer to Pr.00-17.
- Take VFD007CP43A Normal Duty for example: ambient temperature 50°C, UL Open Type, and independent installation. When the carrier frequency maintains at 15 kHz, it corresponds to 72% of the derating ratio. The oL protection executes when the current is 120% × 72% = 86% for one minute; therefore, it must operate by the curve to keep the carrier frequency.

📖 Setting 2:

- The protection method and action are set to 0, but this disables the current limit when output current is the derating ratio x 160% of output current in normal load, and derating ratio x 130% of output current in light load.
- The advantage is that it can provide a higher starting output current (Pr.06-55 = 0) when the carrier frequency (Pr.00-17) setting is higher than the default value. The disadvantage is that the carrier frequency derates easily when it overloads.
  For example: when Pr.06-55 = 0 or 1, the over-current stall prevention level = Ratio × Pr.06-03. When Pr.06-55 = 2, the over-current stall prevention level = Pr.06-03.

📖 Use with the settings for Pr.00-16 and Pr.00-17.

✎ **06-56** PT100 Voltage Level 1

Default: 5.000

Settings 0.000–10.000 V

✎ **06-57** PT100 Voltage Level 2

Default: 7.000

Settings 0.000–10.000 V

📖 Condition settings: PT100 voltage level Pr.06-57 > Pr.06-56.

✎ **06-58** PT100 Level 1 Frequency Protection

Default: 0.00

Settings 0.00–599.00 Hz

✎ **06-59** PT100 Activation Level 1 Protection Frequency Delay Time

Default: 60

Settings 0–6000 sec.

📖 PT100 operation instructions:

(1) Use voltage type analog input (AVI1, AVI2 and ACI voltage 0–10 V) and select PT100 mode.

(2) Select one of the voltage type analog inputs below:

(a) AVI1 (Pr.03-00 = 11)

(b) AVI2 (Pr.03-02 = 11)

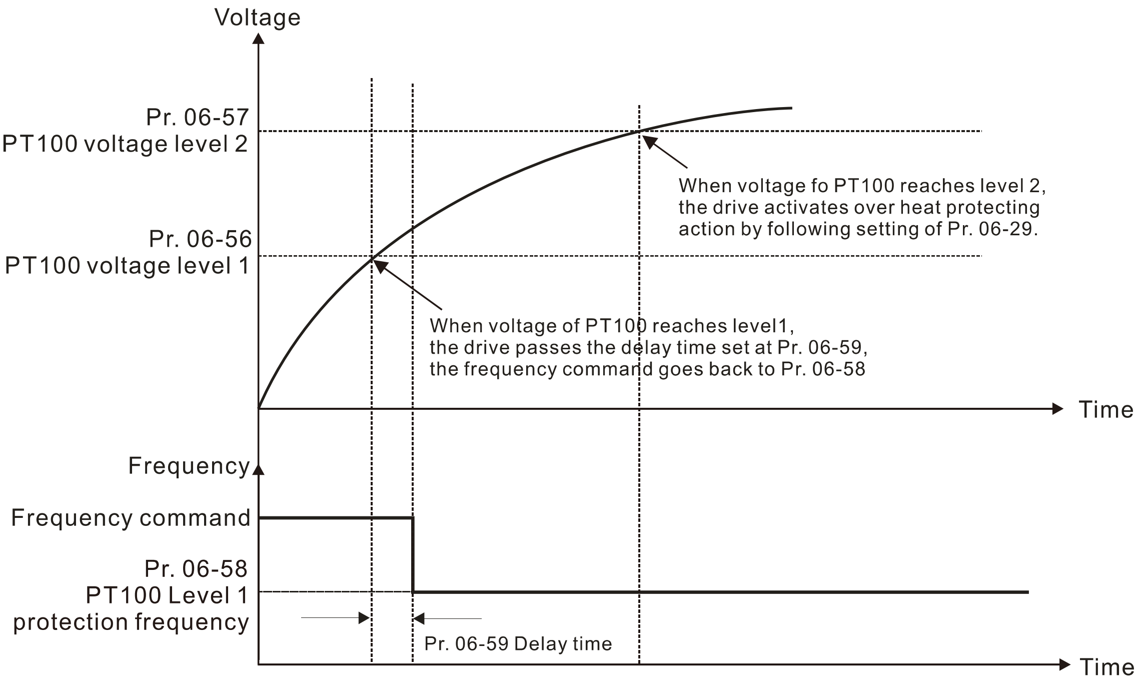
(c) ACI (Pr.03-01 = 11 and Pr.03-29 = 1).

(3) When selecting Pr.03-01 = 11 and Pr.03-29 = 1, you must switch SW4 to 0–10 V for the external I/O board.

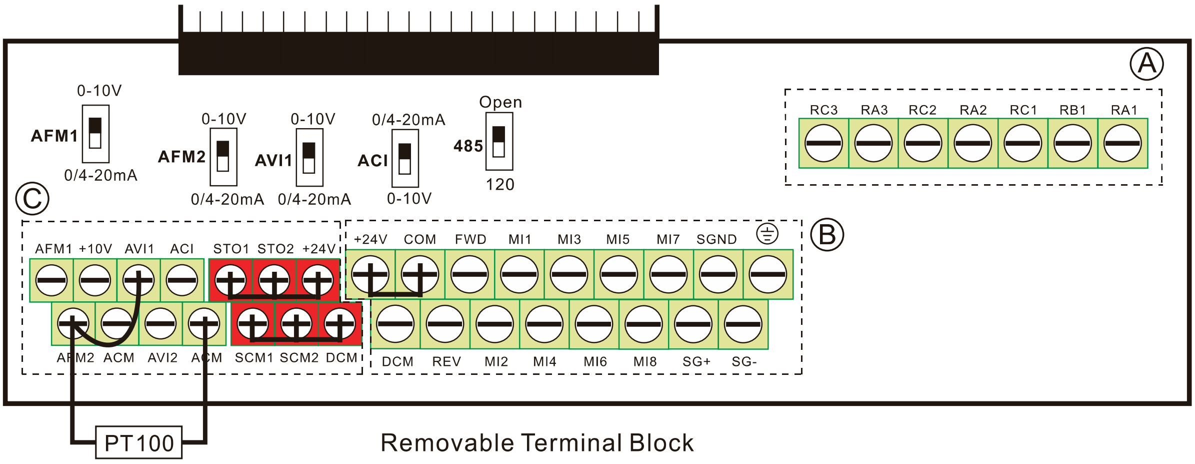
(4) The AFM2 outputs constant voltage or current, then Pr.03-23 = 23. You must switch AFM2 SW2 to 0–20 mA for the external I/O board, and set AFM2 output level to 45% (Pr.03-33 = 45%) of 20 mA = 9 mA.

(5) Use Pr.03-33 to adjust the constant voltage or constant current of the AFM2 output; the setting range is 0–100.00%.

(6) There are two types of action levels for PT100. The diagram below shows the PT100 protecting action:



(7) PT100 wiring diagram:


A
B
C
0-10V
AFM1
0/4-20mA
AFM2
AVI1
ACI
485
Open
120
RC3 RA3 RC2 RA2 RC1 RB1 RA1
AFM1 +10V AVI1 ACI STO1 STO2 +24V
+24V COM FWD MI1 MI3 MI5 MI7 SGND
AFM2 ACM AVI2 ACM SCM1 SCM2 DCM
DCM REV MI2 MI4 MI6 MI8 SG+ SG-
PT100

Removable Terminal Block

Figure 1

📖 When Pr.06-58 = 0.00 Hz, PT100 function is disabled.

Case:

When using PT100, if the motor temperature is higher than 135°C (275°F), the drive starts to count the delay time for auto-deceleration (Pr.06-59). The drive decreases the motor frequency to the setting for Pr.06-58 when it reaches the delay time count value. The drive operates at the frequency set for Pr.06-58 until the motor temperature is lower than 135°C (275°F). If the motor temperature is higher than 150°C (302°F), the drive automatically decelerates to STOP and displays the warning “oH3”.

Set up process:

1. Switch AFM2 to 0–20 mA on the I/O control terminal block. (Refer to Figure 1, PT100 wiring diagram)
2. Wiring (Refer to Figure 1, PT100 wiring diagram):
   Connect external terminal AFM2 to “+”
   Connect external terminal ACM to “-“
   Connect external terminals AFM2 and AVI1 to “short circuit”
3. Set Pr.03-00 = 11 or Pr.03-23 = 23 or Pr.03-33 = 45% (9 mA).
4. Refer to the RTD temperature and resistance comparison table
   Temperature = 135°C, resistance = 151.71 Ω; input current: 9 mA, voltage: about 1.37 V_{DC}
   Temperature = 150°C, resistance = 157.33 Ω; input current: 9 mA, voltage: about 1.42 V_{DC}
5. When the RTD temperature > 135°C, the drive decelerates to the specified operation frequency automatically. Then, Pr.06-56 = 1.37 V and Pr.06-58 = 10 Hz. (When Pr.06-58 = 0, it disables the specified operation frequency.)
6. When the RTD temperature > 150°C, the drive outputs a fault, decelerates to STOP, and displays the warning ”oH3”. Then, Pr.06-57 = 1.42 V and Pr.06-29 = 1 (fault and ramp to stop).

✎ **06-60** Software Detection GFF Current Level

Default: 60.0

Settings 0.0–6553.5% (100% corresponds to the light-load rated current of the drive)

✎ **06-61** Software Detection GFF Filter Time

Default: 0.10

Settings 0.00–655.35 sec.

📖 When the drive detects that the unbalanced three-phase output current is higher than the setting for Pr.06-60, GFF protection activates. The drive then stops output.

06-63 Operation Time of Fault Record 1 (Day)

06-65 Operation Time of Fault Record 2 (Day)

06-67 Operation Time of Fault Record 3 (Day)

06-69 Operation Time of Fault Record 4 (Day)

Default: Read only

Settings 0–65535 days

06-64 Operation Time of Fault Record 1 (Min)
06-66 Operation Time of Fault Record 2 (Min)
06-68 Operation Time of Fault Record 3 (Min)
06-70 Operation Time of Fault Record 4 (Min)

Default: Read only

Settings 0–1439 min.

📖 If there is any malfunctions when the drive operates, Pr.06-17–Pr.06-22 record the malfunctions, and Pr.06-63–Pr.06-70 record the operation time for four sequential malfunctions. Check if there is any problem with the drive according to the interval of the recorded fault.

Example:

The first error: ocA occurs after motor drive operates for 1000 minutes.

The second error: ocd occurs after another 1000 minutes.

The third error: ocn occurs after another 1000 minutes.

The fourth error: ocA occurs after another 1000 minutes.

The fifth error: ocd occurs after another 1000 minutes.

The sixth error: ocn occurs after 1000 minutes.

Then Pr.06-17–Pr.06-22 and Pr.06-63–Pr.06-70 are recorded as follows:

	1st fault	2nd fault	3rd fault	4th fault	5th fault	6th fault
Pr.06-17	ocA	ocd	ocn	ocA	ocd	ocn
Pr.06-18	0	ocA	ocd	ocn	ocA	ocd
Pr.06-19	0	0	ocA	ocd	ocn	ocA
Pr.06-20	0	0	0	ocA	ocd	ocn
Pr.06-21	0	0	0	0	ocA	ocd
Pr.06-22	0	0	0	0	0	ocA
Pr.06-63	0	1	2	2	3	4
Pr.06-64	1000	560	120	1120	680	240
Pr.06-65	0	0	1	2	2	3
Pr.06-66	0	1000	560	120	1120	680
Pr.06-67	0	0	0	1	2	2
Pr.06-68	0	0	1000	560	120	1120
Pr.06-69	0	0	0	0	1	2
Pr.06-70	0	0	0	1000	560	120

※ By examining the time record, you can see that the last fault (Pr.06-17) happened after the drive ran for 4 days and 240 minutes.

✎ **06-71** Low Current Setting Level

Default: 0.0

Settings 0.0–100.0% (100% corresponds to the light-load rated current of the drive)

✎ **06-72** Low Current Detection Time

Default: 0.00

Settings 0.00–360.00 sec.

✓ 06-73 Low Current Action

Default: 0

Settings 0: No function
1: Fault and coast to stop
2: Fault and ramp to stop by the 2nd deceleration time
3: Warn and operation continue

📖 The drive operates according to the setting for Pr.06-73 when the output current is lower than the setting for Pr.06-71, and when the time of the low current exceeds the detection time for Pr.06-72. Use this parameter with the multi-function output terminal = 44 (low current output).

📖 The low current detection function does not execute when the drive is in sleep or standby status.

📖 Sets Pr.06-71 low current level according to the drive's rated current, the equation is Pr.00-01 (drive's rated current) × Pr.06-71 (low current setting level)% = low current detection level (A). The drive changes the setting for Pr.00-01 (rated current) according to the setting for Pr.00-16 (load selection).

✓ 06-76 dEb Motion Offset

Default:
20.0/ 40.0/ 50.0/ 60.0

Settings 230V models: 0.0–200.0 V_{DC}
460V models: 0.0–200.0 V_{DC}
575V models: 0.0–200.0 V_{DC}
690V models: 0.0–200.0 V_{DC}

06-80 Fire Mode

Default: 0.00

Settings 0: Disable
1: Forward (counter clockwise) operation
2: Reverse (clockwise) operation

📖 Use this parameter with multi-function input terminal setting 58 or 59, and multi-function output terminal setting 53 or 54.
0: Fire detection is invalid.
1: The motor operates in a counterclockwise direction (U, V, W).
2: The motor operates in a clockwise direction (U, W, V).

✓ 06-81 Operating Frequency in Fire Mode

Default: 60.00

Settings 0.00–599.00 Hz

📖 Enables fire mode (Pr.06-80 = 1 or 2) and sets the operation frequency in fire mode (Pr.06-81). The drive operates with operation frequency in fire mode when the fire mode is enabled. Refer to Pr.06-86 Fire mode operating sequence for details.

06-82 Enable Bypass on Fire Mode

Default: 0

Settings 0: Disable Bypass

1: Enable Bypass

The Bypass function only enables in Fire mode.

When the Bypass function enables and the fault listed in Table 1 occurs, the drive automatically switches to mains power for the motor's operation.

06-83 Bypass Delay Time on Fire Mode

Default: 0.0

Settings 0.0–6550.0 sec.

Conditions to enable the Bypass function (Pr.06-82 = 1):

(1) When a fault that can enable the Bypass function (as shown in Table 1) occurs in Fire mode, and the fire alarm lasts for Pr.06-83 setting time, the Bypass function enables and the Bypass fire mode indication (MOx = 54) is ON.

(2) When a fault that can be reset (as shown in Table 1) occurs in Fire mode, the automatic reset time is zero, and the fire alarm lasts for Pr.06-83 setting time, then the Bypass function enables and the Bypass fire mode indication (MOx = 54) is ON. If the fault is successfully reset (no fault) before the Bypass function enabled, the counter of bypass delay time returns to zero and waits for the next trigger.

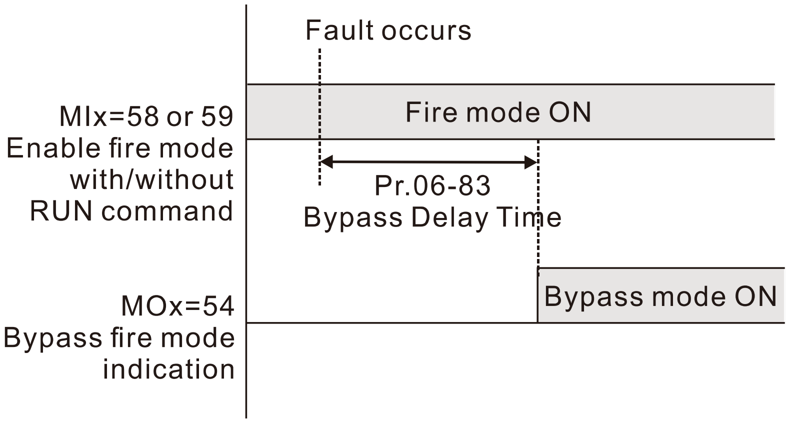


Table 1: Fault detection under Normal mode, Fire mode and Bypass function in Fire mode. (V means detectable)

Code	Fault name	Normal mode	Fire Mode	Enable bypass function
1	Over-current during acceleration (ocA)	V(RS)	V(able to auto-reset)	V
2	Over-current during deceleration (ocd)	V(RS)	V(able to auto-reset)	V
3	Over-current during steady speed (ocn)	V(RS)	V(able to auto-reset)	V
4	Ground Fault (GFF)	V	V(able to auto-reset)	V
5	IGBT short-circuit between upper bridge and lower bridge (occ)	V(RS)	V(able to auto-reset)	V
6	Over-current at stop (ocS)	V(RS)	V(able to auto-reset)	V
7	Over-voltage during acceleration (ovA)	V(RS)	V(able to auto-reset)	V
8	Over-voltage during deceleration (ovd)	V(RS)	V(able to auto-reset)	V
9	Over-voltage at constant speed (ovn)	V(RS)	V(able to auto-reset)	V

Code	Fault name	Normal mode	Fire Mode	Enable bypass function
10	Over-voltage at stop (ovS)	V(RS)	V(able to auto-reset)	V
11	Low-voltage during acceleration (LvA)	V	Not-detectable	Not-detectable
12	Low-voltage during deceleration (Lvd)	V	Not-detectable	Not-detectable
13	Low-voltage at constant speed (Lvn)	V	Not-detectable	Not-detectable
14	Low-voltage at Stop (LvS)	V	Not-detectable	Not-detectable
15	Phase loss protection (OrP)	V	V(able to auto-reset)	V
16	IGBT overheating (oH1)	V	V(able to auto-reset)	V
17	Heatsink overheating (oH2)	V	V(able to auto-reset)	V
18	IGBT temperature detection failure (tH1o)	V	V(able to auto-reset)	V
19	Capacitor hardware error (tH2o)	V	V(able to auto-reset)	V
21	Over load (oL) (150% 1Min, Inverter)	V	Not-detectable	Not-detectable
22	Electronic thermal relay 1 protection (EoL1)	V	Not-detectable	Not-detectable
23	Electronic thermal relay 2 protection (EoL2)	V	Not-detectable	Not-detectable
24	Motor overheating (oH3) (PTC / PT100)	V	V(able to auto-reset)	V
26	Over torque 1 (ot1)	V	Not-detectable	Not-detectable
27	Over torque 2 (ot2)	V	Not-detectable	Not-detectable
28	Under current (uC)	V	Not-detectable	Not-detectable
30	EEPROM write error (cF1)	V	Not-detectable	Not-detectable
31	EEPROM read error (cF2)	V	V	Not-detectable
33	U-phase error (cd1)	V	V	Not-detectable
34	V-phase error (cd2)	V	V	Not-detectable
35	W-phase error (cd3)	V	V	Not-detectable
36	cc (current clamp) hardware error (Hd0)	V	V	Not-detectable
37	oc (over-current) hardware error (Hd1)	V	V	Not-detectable
38	ov (over-voltage) hardware error (Hd2)	V	V	Not-detectable
39	occ hardware error (Hd3)	V	V	Not-detectable
40	Auto-tuning error (AUE)	V	Not-detectable	Not-detectable
41	PID loss ACI (AFE)	V	Not-detectable	Not-detectable
48	ACI loss (ACE)	V	Not-detectable	Not-detectable
49	External fault (EF)	V	Not-detectable	Not-detectable
50	Emergency stop (EF1)	V	Not-detectable	Not-detectable
51	External base block (bb)	V	Not-detectable	Not-detectable
52	Enter wrong password three times and locked (Pcod)	V	Not-detectable	Not-detectable
53	Firmware version error (ccod)	V	V	Not-detectable
54	Illegal command (CE1)	V	Not-detectable	Not-detectable
55	Illegal data address (CE2)	V	Not-detectable	Not-detectable
56	Illegal data value (CE3)	V	Not-detectable	Not-detectable
57	Data is written to read-only address (CE4)	V	Not-detectable	Not-detectable
58	Modbus transmission time-out (CE10)	V	Not-detectable	Not-detectable
60	Braking transistor error (bF)	V	Not-detectable	Not-detectable
61	Y-connection / Δ-connection switch error (ydc)	V	Not-detectable	Not-detectable
62	Deceleration energy backup error (dEb)	V	Not-detectable	Not-detectable
63	Over slip error (oSL)	V	Not-detectable	Not-detectable

Code	Fault name	Normal mode	Fire Mode	Enable bypass function
64	Electric valve switch error (ryF)	V	Not-detectable	Not-detectable
68	Reverse direction of the speed feedback (SdRv)	V	Not-detectable	Not-detectable
69	Over speed rotation feedback (SdOr)	V	Not-detectable	Not-detectable
70	Large deviation of speed feedback (SdDe)	V	Not-detectable	Not-detectable
71	Watchdog (WDTT)	Not detectable	Not-detectable	Not-detectable
72	STO loss 1 (STL1)	V	V	Not-detectable
73	Emergency stop for external safety (S1)	V	V	Not-detectable
74	Fire mode output (Fire)	V	V (keeps operating)	V (keeps operating)
76	Safety Torque Off (STO)	V	V	Not-detectable
77	STO loss 2 (STL2)	V	V	Not-detectable
78	STO loss 3 (STL3)	V	V	Not-detectable
82	Output phase loss U-phase (OPHL)	V	V(able to auto-reset)	V
83	Output phase loss V-phase (OPHL)	V	V(able to auto-reset)	V
84	Output phase loss W-phase (OPHL)	V	V(able to auto-reset)	V
89	Rotor position detection error (RoPd)	V	V	V
90	Forced to stop (FStp)	V	Not-detectable	Not-detectable
101	CANopen guarding error (CGdE)	V	Not-detectable	Not-detectable
102	CANopen heartbeat error (CHbE)	V	Not-detectable	Not-detectable
104	CANopen bus off error (CbFE)	V	Not-detectable	Not-detectable
105	CANopen index error (CidE)	V	Not-detectable	Not-detectable
106	CANopen station address error (CAdE)	V	Not-detectable	Not-detectable
107	CANopen memory error (CFrE)	V	Not-detectable	Not-detectable
111	InrCOM time-out error (ictE)	V	Not-detectable	Not-detectable
142	Auto-tuning error 1 (no feedback current error) (AUE1)	Not detectable	Not-detectable	Not-detectable
143	Auto-tuning error 2 (motor phase loss error) (AUE2)	Not detectable	Not-detectable	Not-detectable
144	Auto-tuning error 3 (no-load current I_0 measuring error) (AUE3)	Not detectable	Not-detectable	Not-detectable
148	Auto-tuning error 4 (leakage inductance Lsigma measuring error) (AUE4)	Not detectable	Not-detectable	Not-detectable

✎ 06-84 Number of Times of Reset in Fire Mode

Default: 0

Settings 0–10

🕮 When a fault occurs in fire mode, the drive attempts resetting the fault to prevent entering bypass mode. Use Pr.06-84 and Pr.06-85 to set this function.

🕮 When this function is disabled (Pr.06-84 = 0) and a fault that listed in Table 1 occurs, the drive enters bypass mode (Pr.06-82 = 1, bypass function is enabled).

Example: If Pr.06-83 = 3, the drive attempts to reset the fault for three times at most. When the fourth fault occurs in the setting time for Pr.06-85, the drive will no longer attempt to reset the fault, and directly goes into Bypass mode after the setting delay time for Pr.06-83.

06-85 Length of Time of Reset in Fire Mode

Default: 60.0

Settings 0.0–6000.0 sec.

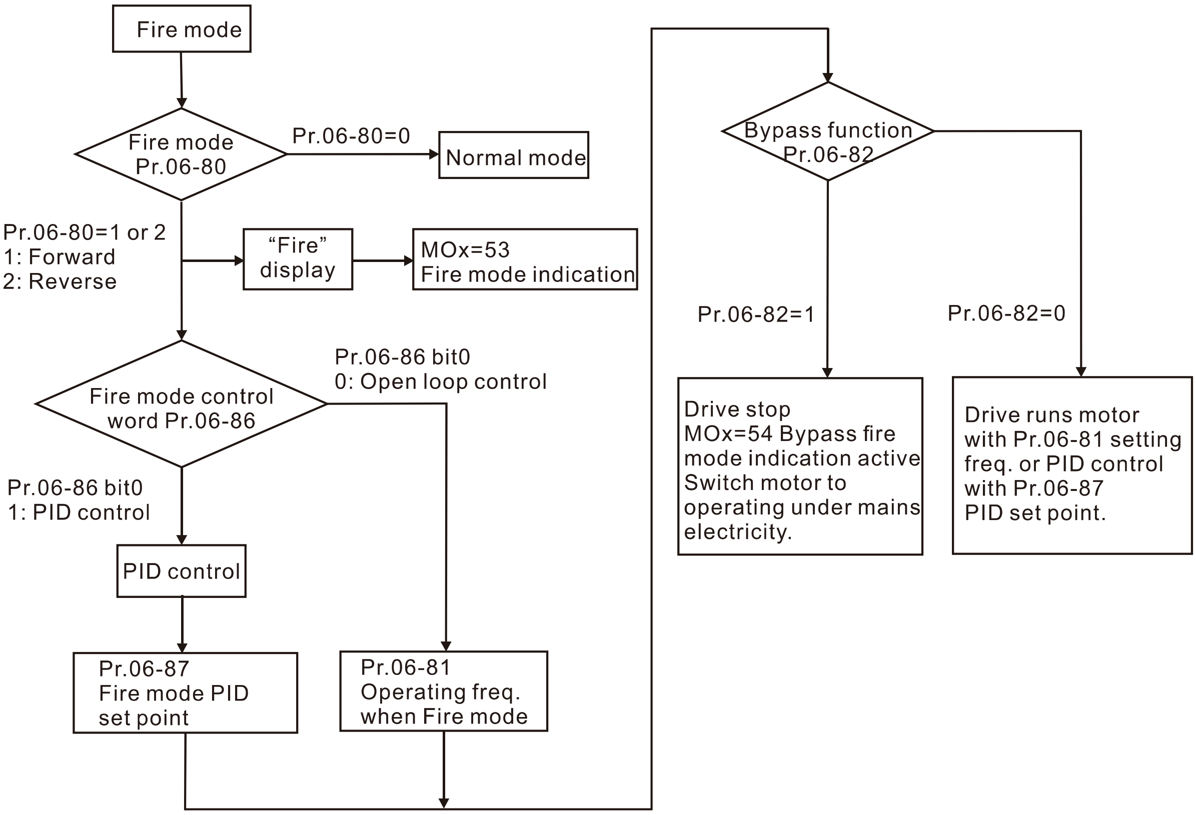
The settings for Pr.06-82 to Pr.06-85 determine whether to switch the motor operation to mains power in fire mode.

06-86 Fire Mode Motion

Default: 0

Settings bit0: 0 = Open Loop; 1 = Close Loop (PID control)
bit1: 0 = Manual reset fire mode; 1 = Auto reset fire mode
0: Open loop control and manual reset fire mode
1: Close loop control and manual reset fire mode
2: Open loop control and auto reset fire mode
3: Close loop control and auto reset fire mode

The sequence of Fire mode operation is as the diagram below. Choose the operation mode [open-loop control or close-loop control (PID control)] according to the setting for Pr.06-86.


Fire mode
Fire mode Pr.06-80
Pr.06-80=0
Normal mode
Pr.06-80=1 or 2
1: Forward
2: Reverse
"Fire" display
MOx=53 Fire mode indication
Fire mode control word Pr.06-86
Pr.06-86 bit0 0: Open loop control
Pr.06-86 bit0 1: PID control
PID control
Pr.06-87 Fire mode PID set point
Pr.06-81 Operating freq. when Fire mode
Bypass function Pr.06-82
Pr.06-82=1
Pr.06-82=0
Drive stop MOx=54 Bypass fire mode indication active Switch motor to operating under mains electricity.
Drive runs motor with Pr.06-81 setting freq. or PID control with Pr.06-87 PID set point.

The Fire mode operating procedure:

- Pr.06-86 bit0 = 0:

  When setting Pr.06-80 = 1 or 2, and the multi-functional input terminals MIx = 58 is ON, the drive enables the fire mode operation. The drive accelerates to the setting frequency for Pr.06-81, and the keypad KPC-CC01 displays a "Fire" warning. The drive outputs a RUN command for the fire mode when the multi-function output terminal MOx is set to 53. If you set Pr.06-82 = 1 to enable the Bypass function and the condition is established, the MOx = 54 Bypass fire mode indicates action and switches the motor power to the mains power, then the drive stops.

- Pr.06-86 bit0 = 1:
  When setting the Pr.06-80 = 1 or 2, and the multi-functional input terminals MIx = 58 is ON, the drive enables the fire mode operation. The drive runs PID control with Pr.06-87 as PID set point, and the keypad KPC-CC01 displays a “Fire” warning. The drive outputs a RUN command for the fire mode when the multi-function output terminal MOx is set to 53. If you set Pr.06-82 = 1 to enable the Bypass function and the condition is established, the MOx = 54 Bypass fire mode indicates action and switches the motor power to the mains power, then the drive stops.
- If an error occurs to the PID feedback signal, the drive switches to the open-loop control and runs according to the setting frequency for Pr.06-81.

06-87 Fire Mode PID Set Point

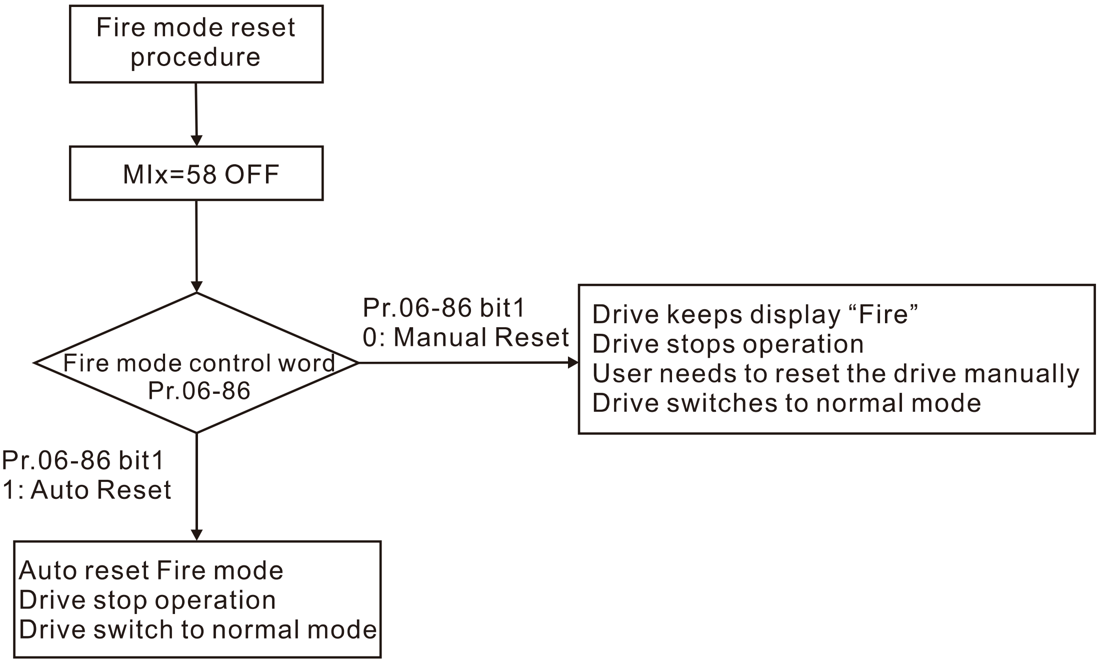
Default: 0.00

Settings 0.00–100.00%

🕮 Sets the PID target value in Fire mode.

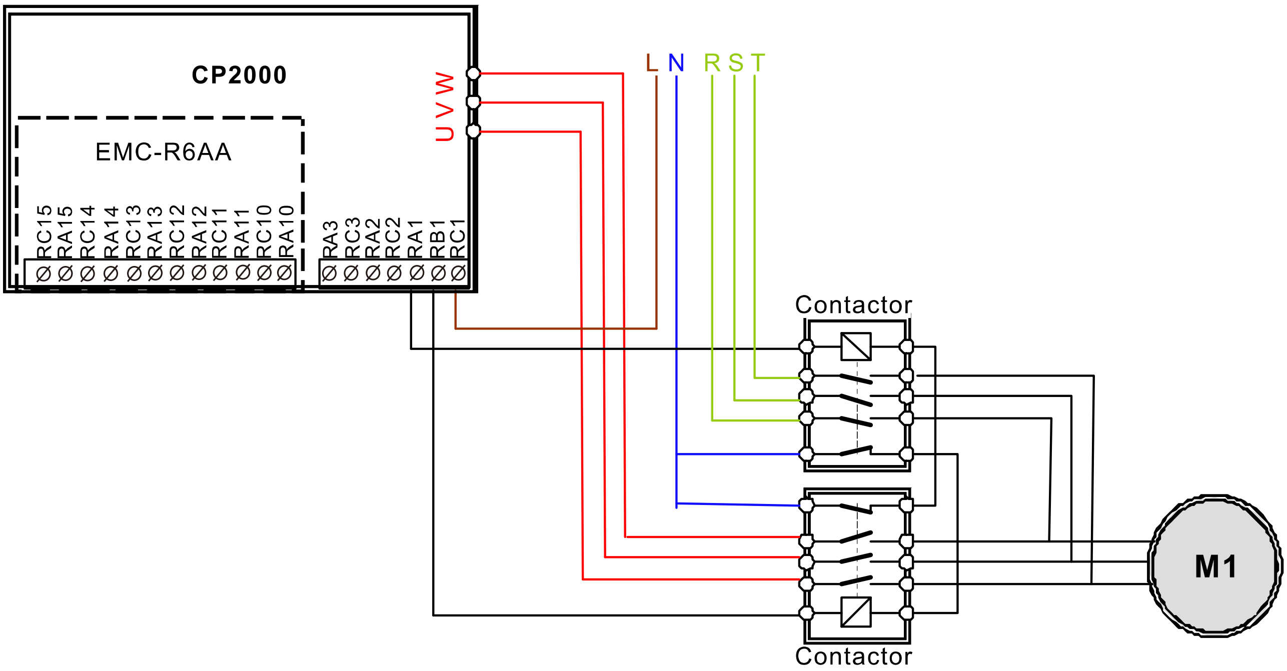
The Fire mode reset procedure:

When the terminal MIx = 58 changes from ON to OFF, the drive starts to run “fire mode reset procedure”, and determines whether to “Manual reset” or “Auto reset” fire mode according to the selection of Pr.06-86 bit1.


Fire mode reset procedure
MIx=58 OFF
Fire mode control word Pr.06-86
Pr.06-86 bit1 0: Manual Reset
Drive keeps display “Fire”
Drive stops operation
User needs to reset the drive manually
Drive switches to normal mode
Pr.06-86 bit1 1: Auto Reset
Auto reset Fire mode
Drive stop operation
Drive switch to normal mode

Wiring Diagram:

1. When AC power is ON, RB1 and RC1 are ON, and RA1 and RC1 are OFF.
2. When operating in fire mode and bypass indication function is disabled, RB1 and RC1 are ON, and the motor is driven by the drive.
3. When operating in fire mode and bypass indication function is enabled, RA1 and RC1 are ON, and the motor runs under mains electricity.



🕮 When in fire mode, the running direction of the drive is based on Pr.06-80 = 1 (Forward / Counter clockwise operation) or Pr.06-80 = 2 (Reverse / Clockwise operation). Other running direction commands are invalid and Pr.00-23 Motor Operating Direction is not available when in fire mode.

🕮 When in fire mode, all keypad command are ignored, including RUN, STOP, JOG and direction commands.

🕮 When in fire mode, all RS-485 communication commands are ignored, including RUN, STOP, JOG and direction commands.

🕮 When in fire mode, B.B. and EF are not activated, including external terminal B.B, communication B.B, external terminal EF, communication EF and external terminal EF1). Any activated B.B. is automatically invalid, including external terminal B.B. and communication B.B., and the drive executes speed tracking.

🕮 When in fire mode, activated EF and EF1 are automatically invalid, including external terminals EF & EF1 and communication EF).

🕮 When in fire mode, the JOG command is not available (JOG command source: keypad, external terminals and communications). Any operating JOG command is automatically invalid.

🕮 When in fire mode, the Acceleration / Deceleration Speed Inhibit function is not available. Any activated acceleration / deceleration speed inhibition is automatically invalid.

🕮 When in fire mode, If you set Pr.06-86 to bit0 = 0 (open-loop control), the drive does not execute parameter group 08 PID function. Any operating PID function is automatically invalid.

🕮 When in fire mode, the Hand-Off-Auto function is not available, including multi-function output terminals.

- When in fire mode, the drive does not execute the circulative control function, and all circulating control function parameters are cleared. The circulative control function is automatically invalid when in fire mode.
- When in fire mode, the drive does not execute the sleep function.
- When in fire mode, the drive does not execute the DC brake function. Any operating DC brake is automatically invalid when in fire mode.
- When in fire mode, the drive does not execute over-current stall prevention function. Any operating over-current stall prevention is automatically invalid when in fire mode.
- When in fire mode, over-torque detection function is not available.
- When in fire mode, oL1/oL2 detection function is not available.
- When in fire mode, abnormal communication (CE10, CE1, CE2, CE3 and CE4) detection is not available.
- The cd1, cd2, cd3 and Hd0, Hd1, Hd2, Hd3 are boot check and cannot be cleared. The above errors cannot be cleared when in fire mode. The drive does not operate when in fire mode.
- Lv protection is not activated when in fire mode, so the drive keeps running or runs until the power is lost. If the Lv error occurs before the fire mode warning, clear the Lv error to operate the drive.
- If bypass fire mode indication (MOx = 54) is activated, reboot the drive and deactivate the fire mode to turn off this terminal output.
- When in fire mode, the output stop function is not available.
- When in fire mode, the skip frequency function is not available.
- When in fire mode, the operating frequency for Pr.06-81 cannot be larger than Pr.01-00 Maximum Output Frequency. If Pr.06-81 > Pr.01-00, the maximum frequency is automatically set to Pr.01-00.

07 Special Parameters

✎ You can set this parameter during operation.

The following are abbreviations for different types of motors:

- IM: Induction motor
- PM: Permanent magnet synchronous AC motor
- IPM: Interior permanent magnet synchronous AC motor
- SPM: Surface permanent magnet synchronous AC motor
- SynRM: Synchronous reluctance motor

✎ 07-00 Software Brake Chopper Action Level

Default: 380.0/740.0/895.0/1057.0

Settings 230V models: 350.0–450.0 V_{DC}

460V models: 700.0–900.0 V_{DC}

575V models: 850.0–1116.0 V_{DC}

690V models: 939.0–1318.0 V_{DC}

🕮 Sets the DC bus voltage at which the brake chopper is activated. Choose a suitable brake resistor to achieve the best deceleration. Refer to Chapter 7 Optional Accessories for information about brake resistors.

🕮 This parameter is only valid for the models below 22 kW of 230V models and 30 kW of 460V models.

✎ 07-01 DC Brake Current Level

Default: 0

Settings 0–100%

🕮 100% corresponds to the rated current of the drive (Pr.00-01).

🕮 Sets the level of the DC brake current output to the motor at start-up and stop. It is recommended that you start with a low DC brake current level and then increase until you reach the proper holding torque. However, the DC brake current cannot exceed the motor's rated current to prevent the motor from burnout. Do NOT use the DC brake for mechanical retention, otherwise, injury or accident may occur.

🕮 The PM has the magnetic field itself, using the DC brake may possibly cause the motor run in a reverse direction, therefore, it is not recommended to use DC brake for PM.

✎ 07-02 DC Brake Time at Start-up

Default: 0.0

Settings 0.0–60.0 sec.

🕮 The motor may continue rotating after the drive stops output due to external forces or the inertia of the motor itself. If you use the drive with the motor rotating, it may cause motor damage or trigger drive protection due to over-current. This parameter outputs DC current, generating torque to force the motor to stop to get a stable start before more operation. This parameter determines the duration of the DC brake current output to the motor when the drive starts up. Setting this parameter to 0.0 disables the DC brake at start-up.

- The PM has the magnetic field itself, using the DC brake may possibly cause the motor run in a reverse direction, therefore, it is not recommended to use DC brake for PM. Use Pr.10-49 zero voltage command to force the motor decelerate or to stop.

07-03 DC Brake Time at STOP

Default: 0.0

Settings 0.0–60.0 sec.

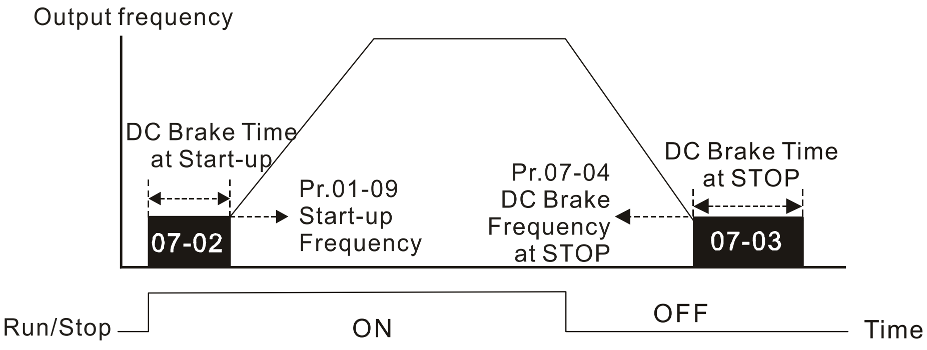
- The motor may continue rotating after the drive stops output due to external forces or the inertia of the motor itself. This parameter outputs DC current, generating torque to force the drive stop after the drive stops output to make sure that the motor stops.
- This parameter determines the duration of the DC brake current output to the motor when braking. To enable the DC brake at STOP, you must set Pr.00-22 (Stop Method) to 0 (ramp to stop). Set this parameter to 0.0 to disable the DC brake at stop.
- Related parameters: Pr.00-22 Stop Method, Pr.07-04 DC Brake Frequency at STOP.

07-04 DC Brake Frequency at STOP

Default: 0.00

Settings 0.00–599.00 Hz

- Determines the start frequency of the DC brake before the drive ramps to stop. When this setting is less than Pr.01-09 (Start-up Frequency), the start frequency for the DC brake begins at the minimum frequency.


Output frequency
DC Brake Time at Start-up
07-02
Pr.01-09 Start-up Frequency
Pr.07-04 DC Brake Frequency at STOP
DC Brake Time at STOP
07-03
Run/Stop
ON
OFF
Time

DC Brake Output Timing Diagram

- Use the DC brake before running the motor when the load is movable at stop, such as with fans and pumps. The motor is in free running status and in unknown rotation direction before the drive starts up. Execute the DC brake before you start the motor.
- Use the DC brake at STOP when you need to brake the motor quickly or to control the positioning, such as with cranes or cutting machines.

07-05 Voltage Increasing Gain

Default: 100

Settings 1–200%

- When using speed tracking, adjust Pr.07-05 to slow down the increasing voltage gain if there are errors such as oL or oc; however, the speed tracking time will be longer.

✓ 07-06 Restart after Momentary Power Loss

Default: 0

Settings 0: Stop operation
1: Speed tracking by speed before the power loss
2: Speed tracking by minimum output frequency

- Determines the operation mode when the drive restarts from a momentary power loss.
- The power system connected to the drive may power off momentarily due to many reasons. This function allows the drive to keep outputting voltages after the drive is repowered and does not cause the drive to stop.
- 1: Frequency tracking begins before momentary power loss and accelerates to the master Frequency command after the drive output frequency and motor rotator speed are synchronous. Use this setting when there is a lot of inertia with little resistance on the motor load. For example, in equipment with a large inertia flywheel, there is NO need to wait until the flywheel stops completely after a restart to execute the operation command; therefore, it saves time.
- 2: Frequency tracking starts from the minimum output frequency and accelerates to the master Frequency command after the drive output frequency and motor rotator speed are synchronous. Use this setting when there is little inertia and large resistance.
- This function is only valid when the RUN command is enabled.

✓ 07-07 Allowed Power Loss Duration

Default: 2.0

Settings 0.0–20.0 sec.

- Determines the maximum time of allowable power loss. If the duration of a power loss exceeds this parameter setting, the AC motor drive stops output after the power recovers.
- Pr.07-06 is valid when the maximum allowable power loss time is ≤ 20 seconds and the AC motor drive displays “Lv”. If the AC motor drive is powered off due to overload, even if the maximum allowable power loss time is ≤ 20 seconds, Pr.07-06 is invalid after the power recovers.

✓ 07-08 Base Block Time

Default: Depending on the model power

Settings 0.0–5.0 sec. (Depending on the model power)

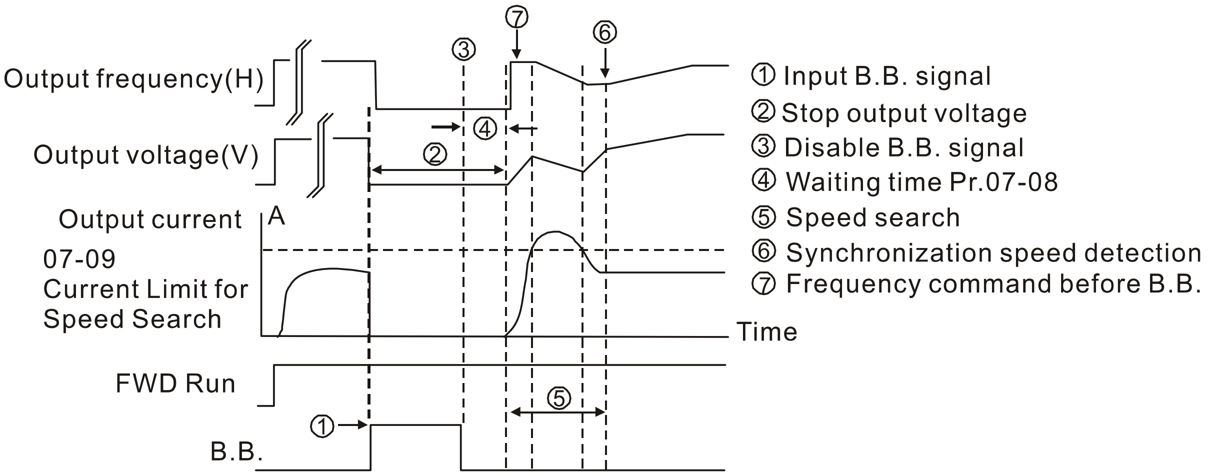
- When momentary power loss is detected, the AC motor drive blocks its output and then waits for a specified period of time (determined by Pr.07-08, called Base Block Time) before resuming operation. Set this parameter to the time that allows the residual voltage at the output side to decrease to 0 V before activating the drive again.
- This parameter is not only for the B.B. time, but also is the re-start delay time after free run.
- The RUN command during a free run operation is memorized, and runs or stops with the last frequency command after the delay time.
- This delay time is only applicable in “Re-start after coast to stop” status, and does not limit ramp to stop. The coast to stop can be caused by various control command source, or by errors.

Following table is the recommended setting for re-start delay time of each model power. You must set Pr.07-08 according to this table (the default of each model power is also based on this table).

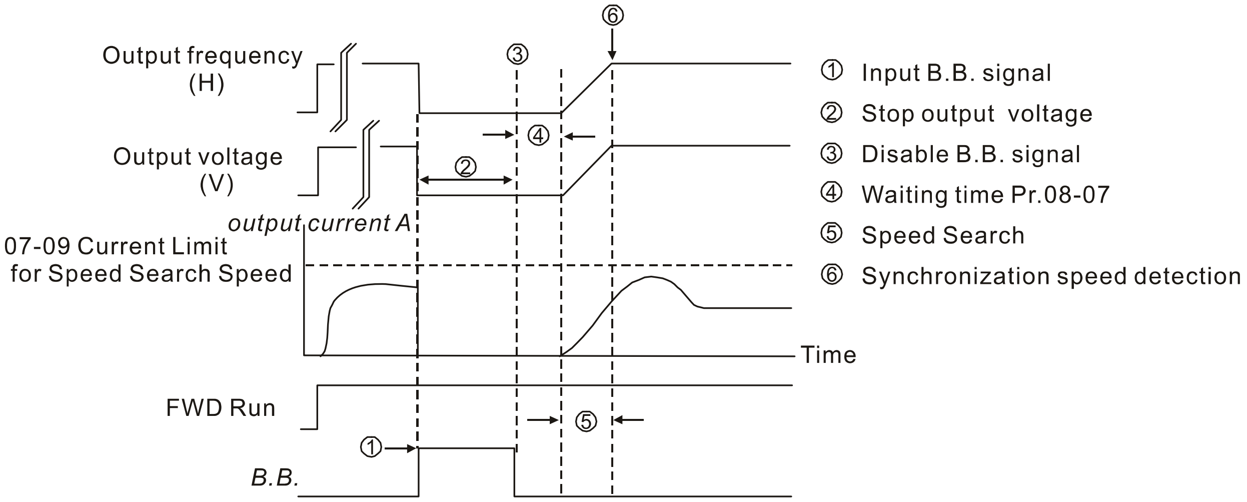
kW	0.75	1.5	2.2	3.7	4.0	5.5	7.5	11.0	15.0	18.5	22.0
HP	1	2	3	5	5.5	7.5	10	15	20	25	30
Delay time (sec.)	0.3	0.4	0.5	0.6	0.7	0.7	0.8	0.9	1	1.1	1.2

kW	30.0	37.0	45.0	55.0	75.0	90.0	110.0	132.0	160.0	185.0	200.0
HP	40	50	60	75	100	125	150	175	215	250	270
Delay time (sec.)	1.3	1.4	1.5	1.6	1.7	1.8	1.9	2.0	2.1	2.2	2.3

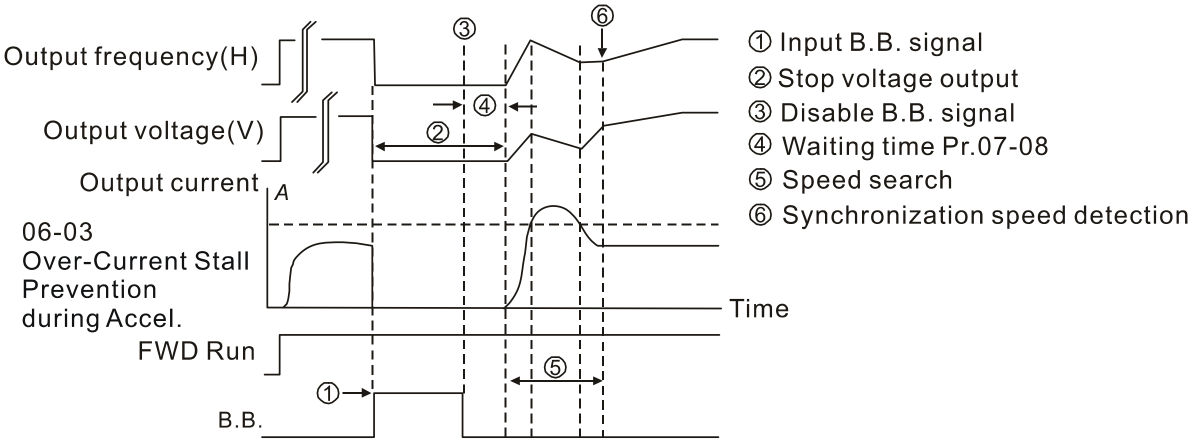
kW	220.0	250.0	280.0	315.0	355.0	400.0	500.0	560.0	630.0
HP	300	340	375	425	475	530	675	750	850
Delay time (sec.)	2.3	2.4	2.5	2.6	2.7	2.8	2.9	3.2	3.4



B.B. Search with last output frequency downward timing chart



B.B. Search with minimum output frequency upward timing chart



B.B. Search with minimum output frequency upward timing chart

07-09 Current Limit for Speed Tracking

Default: 100

Settings 20–200% (100% corresponds to the light-duty rated current of the drive)

🕮 The AC motor drive executes speed tracking only when the output current is greater than the value set in Pr.07-09.

🕮 The maximum current for speed tracking affects the synchronous time. The larger the parameter setting is, the faster the synchronization occurs. However, if the parameter setting is too large, the overload protection function may be activated.

07-10 Restart after Fault Action

Default: 0

Settings 0: Stop operation
1: Speed tracking by current speed
2: Speed tracking by minimum output frequency

🕮 Faults include: bb, oc, ov, and occ. To restart after oc, ov and occ, you cannot set Pr.07-11 to 0.

07-11 Number of Times of Restart after Fault

Default: 0

Settings 0–10

🕮 After fault (oc, ov, and occ) occurs, the AC motor drive can reset and restart automatically up to 10 times. If Pr. 07-11 is set to 0, the drive resets or restarts automatically after faults occur. The drive starts according to the Pr.07-10 setting after restarting after fault.

🕮 If the number of faults exceeds the Pr.07-11 setting, the drive does not restart and reset until you press RESET manually and execute the operation command again.

07-12 Speed Tracking during Start-up

Default: 0

Settings 0: Disable
1: Speed tracking by the maximum output frequency
2: Speed tracking by the motor frequency start-up
3: Speed tracking by the minimum output frequency

📖 Speed tracking is suitable for punch, fans and other large inertia loads. For example, a mechanical punch usually has a large inertia flywheel, and the general stop method is coast to stop. If it needs to be restarted again, the flywheel may take 2–5 minutes or longer to stop. This parameter setting allows you to start the flywheel operating again without waiting until the flywheel stops completely.

📖 When using PM, Pr.07-12 ≠ 0, the speed tracking function is enabled. When Pr.07-12 = 1, 2 or 3, the output frequency converts to the actual rotor speed from zero-speed.

📖 When using SynRM control mode, only Pr.07-12 = 3 (speed tracking by the minimum output frequency) is enabled.

✎ 07-13 dEb Function Selection

Default: 0

Settings 0: Disable

1: dEb with auto-acceleration / auto-deceleration, the drive does not output the frequency after the power is restored.

2: dEb with auto-acceleration / auto-deceleration, the drive outputs the frequency after the power is restored

---

📖 dEb (Deceleration Energy Backup) lets the motor decelerates to stop when momentary power loss occurs. When the power loss is instantaneous, use this function to let the motor decelerate to zero speed. If the power recovers at this time, the drive restarts the motor after the dEb return time.

📖 Lv return level: Default value depends on the drive power model

Models for frame A, B, C, D = Pr.06-00 + 60V/30V (230V models)

Models for frame E and above = Pr.06-00 + 80V/40V (230V models)

📖 Lv level: Default = Pr.06-00

📖 During dEb operation, other protection such as ryF, ov, oc, occ and EF may interrupt it, and these error codes are recorded.

📖 The STOP (RESET) command does not work during the dEb auto-deceleration, and the drive continues decelerating to stop. To make the drive coast to stop immediately, use another function (EF) instead.

📖 The B.B. function does not work when executing dEb. The B.B. function is enabled after the dEb function finishes.

📖 Even though the Lv warning does not display during dEb operation, if the DC bus voltage is lower than the Lv level, MOx = 10 (Low voltage warning) still operates.

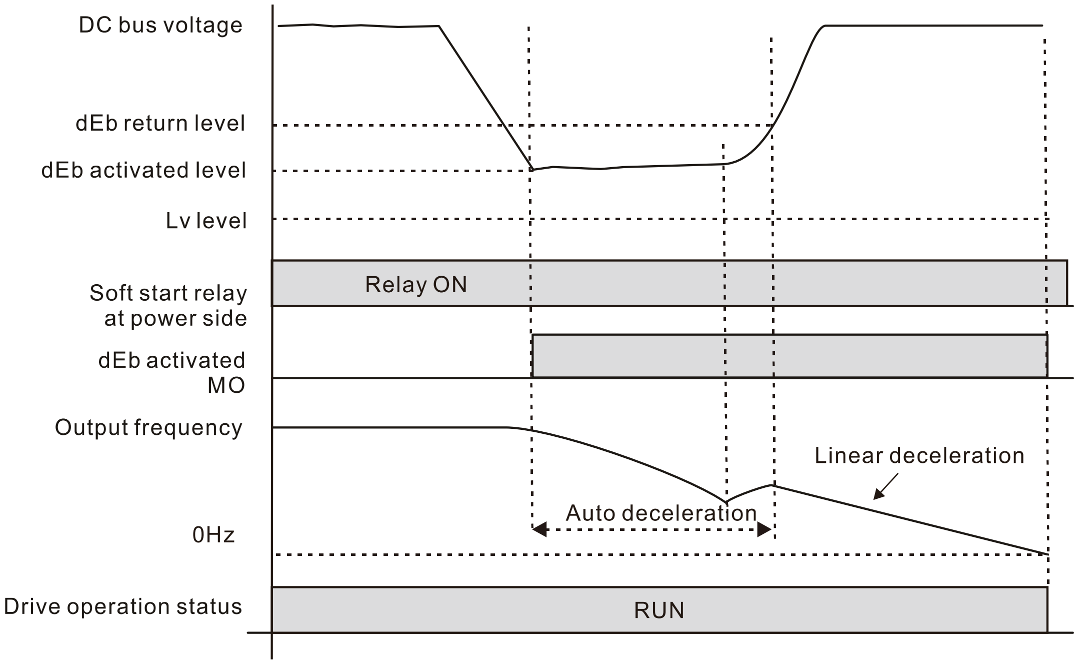
📖 The following explains the dEb action:

When the DC voltage drops below the dEb setting level, the dEb function starts to work (soft start relay remains closed), and the drive executes auto-deceleration.

- Situation 1: Momentary power loss, or too low and unstable power voltage, or power supply sliding down because of sudden heavy load.

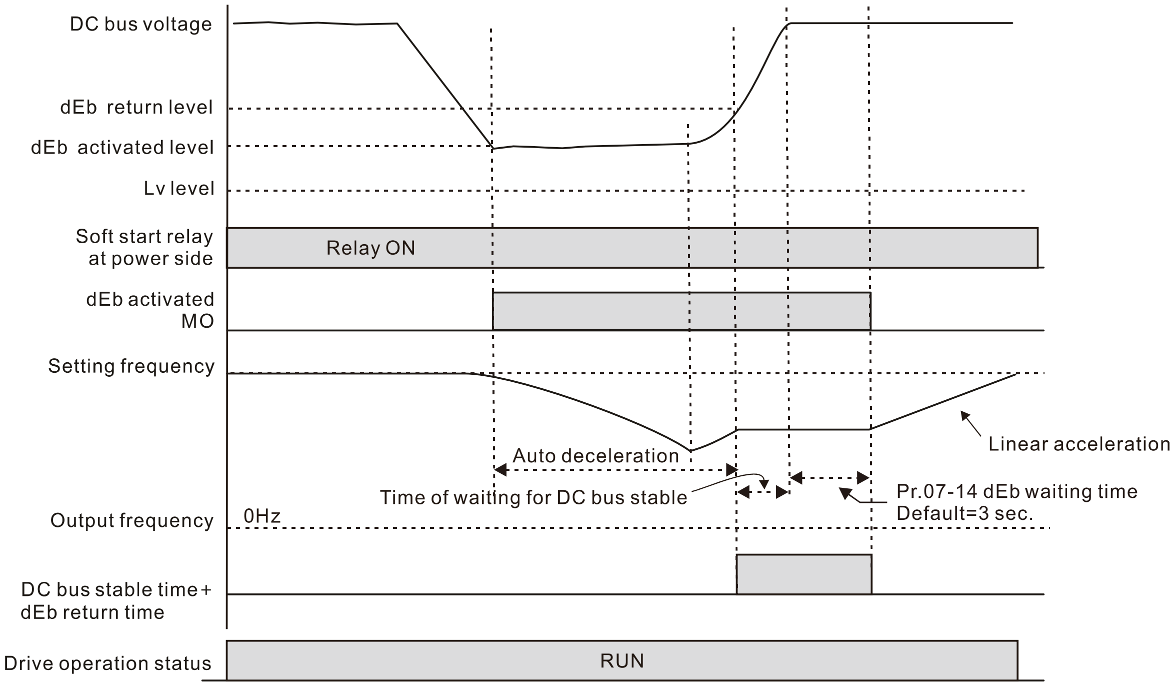
  Pr.07-13 = 1, "dEb active, DC bus voltage returns, output frequency does not return" and power recovers.

  When the power recovers and DC bus voltage exceeds the dEb return level, the drive linearly decelerates to 0 Hz and stops. The keypad displays the "dEb" warning until you manually reset it, so you can see the reason for the stop.



- Situation 2: Momentary power loss or too low and unstable power voltage, or power supply sliding down because of sudden heavy load.

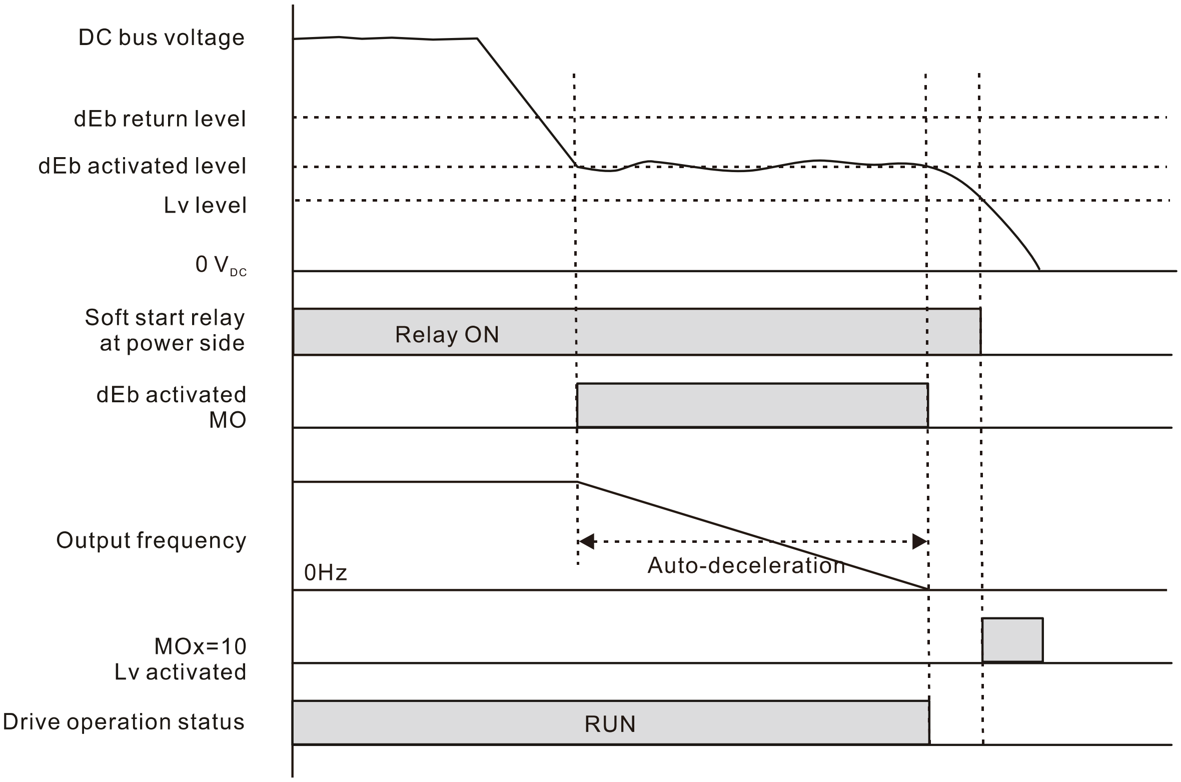
  Pr.07-13 = 2 "dEb active, DC bus voltage returns, output frequency returns" and power recovers. During the dEb deceleration (includes 0 Hz run), if the power recovers to a voltage higher than dEb return level, the drive maintains the frequency for the set time of Pr.07-14 (default = 3 sec.) and then accelerates again. The "dEb" warning on the keypad is automatically cleared.



- Situation 3: Unexpected power shut down or power loss

  Pr.07-13 = 1 ”dEb active, DC bus voltage returns, the output frequency does not return” and the power does not recover.

  The keypad displays the “dEb” warning and the drive stops after decelerating to the lowest operating frequency. When the DC bus voltage is lower than the Lv level, the drive disconnects the soft start relay until the power completely runs out.



- Situation 4:

  Pr.07-13 = 2 “dEb active, DC bus voltage returns, the output frequency returns” and power does not recover.

  The drive decelerates to 0 Hz. The DC bus voltage continues to decrease until the voltage is lower than the Lv level, and then the drive disconnects the soft-start relay. The keypad displays “dEb” warning until the drive completely runs out of power.

- Situation 5:

  Pr.07-13 = 2 “dEb low voltage control, when the speed is lower than 1/4 rated motor speed, DC bus voltage rises to 350 V_{DC} / 700 V_{DC}, the drive ramps to stop .

  The drive decelerates to 0 Hz. The DC bus voltage continues to decrease until the voltage is lower than the Lv level, and then the drive disconnects the soft-start relay. The soft-start relay closes again after the power recovers and the DC bus voltage is higher than the Lv return level. When the DC bus voltage is higher than the dEb return level, the drive maintains the frequency for the set time of Pr.07-14 (default = 3 sec.) and starts to accelerate linearly, and the dEb warning on the keypad is automatically cleared.

- Situation 6:

  Pr.07-13 = 4, dEb high-voltage control

  When dEb occurs, the DC bus voltage control level rises to 350 V_{DC} / 700 V_{DC} to ramp to stop.

Even though the power recovers and the frequency does not return, dEb activates until the motor decelerates to 0 Hz.

(1) When dEb activates, it sends dEb warning. When the output frequency reaches 0 Hz, the operation status is STOP and disables the dEb function, the dEb warning continues.

(2) If power does not recover, the DC bus voltage drops until reaches the Lv level, the drive LvS error occurs (keypad displays LvS error that covers the dEb display), the Soft Start Relay will be OFF.

✎ 07-15 Dwell Time at Acceleration

Default: 0.00

Settings 0.00–600.00 sec.

✎ 07-16 Dwell Frequency at Acceleration

Default: 0.00

Settings 0.00–599.00 Hz

✎ 07-17 Dwell Time at Deceleration

Default: 0.00

Settings 0.00–600.00 sec.

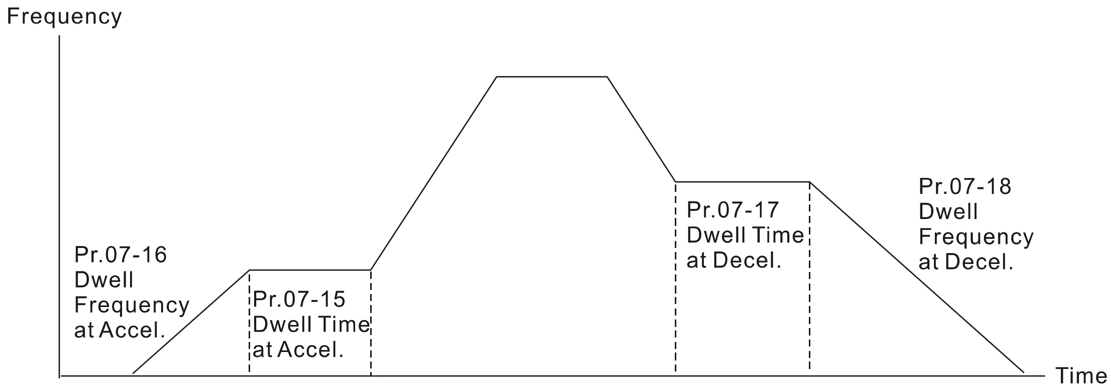
✎ 07-18 Dwell Frequency at Deceleration

Default: 0.00

Settings 0.00–599.00 Hz

🕮 In the heavy load situation, Dwell can make stable output frequency temporarily.

🕮 For heavy load applications, use Pr.07-15–Pr.07-18 to avoid ov or oc protection.



Dwell at acceleration / deceleration

✎ 07-19 Fan Cooling Control

Default: 0

Settings 0: Fan is always ON

1: Fan is OFF after AC motor drive stops for one minute

2: Fan is ON when the AC motor drive runs; fan is OFF when the AC motor drive stops

3: Fan turns ON when temperature (IGBT) reaches around 60°C

4: Fan is always OFF

🕮 Use this parameter to control the fan.

🕮 0: Fan runs immediately when the drive power is turned ON.

1: Fan runs when the AC motor drive runs. One minute after the AC motor drives stops, the fan is OFF.

2: Fan runs when the AC motor drive runs and stops immediately when AC motor drive stops.

3: Fan is ON when IGBT or capacitance temperature is > 60°C
Fan is OFF when IGBT and capacitance temperature are both < 40°C, and the drive stops running

Setting 4: Fan is always OFF

The control parameter for the applicable fan of each frame are as below:

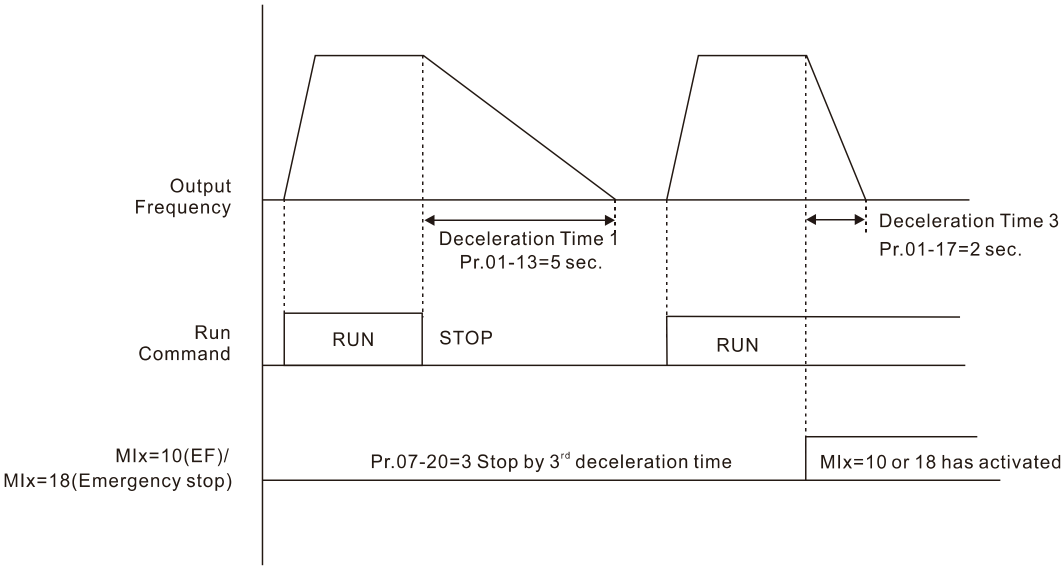
Frame	Heat Sink Fan	Capacitor Fan
A	Pr.07-19	No capacitor fan
B	Pr.07-19	Pr.07-19
C	Pr.07-19	Pr.07-19 230V models: always ON
D0	Pr.07-19	Pr.07-19
D	Pr.07-19	ON
E	Pr.07-19	Pr.07-19
F	Pr.07-19	Pr.07-19
G	Pr.07-19	No capacitor fan
H	Pr.07-19	No capacitor fan

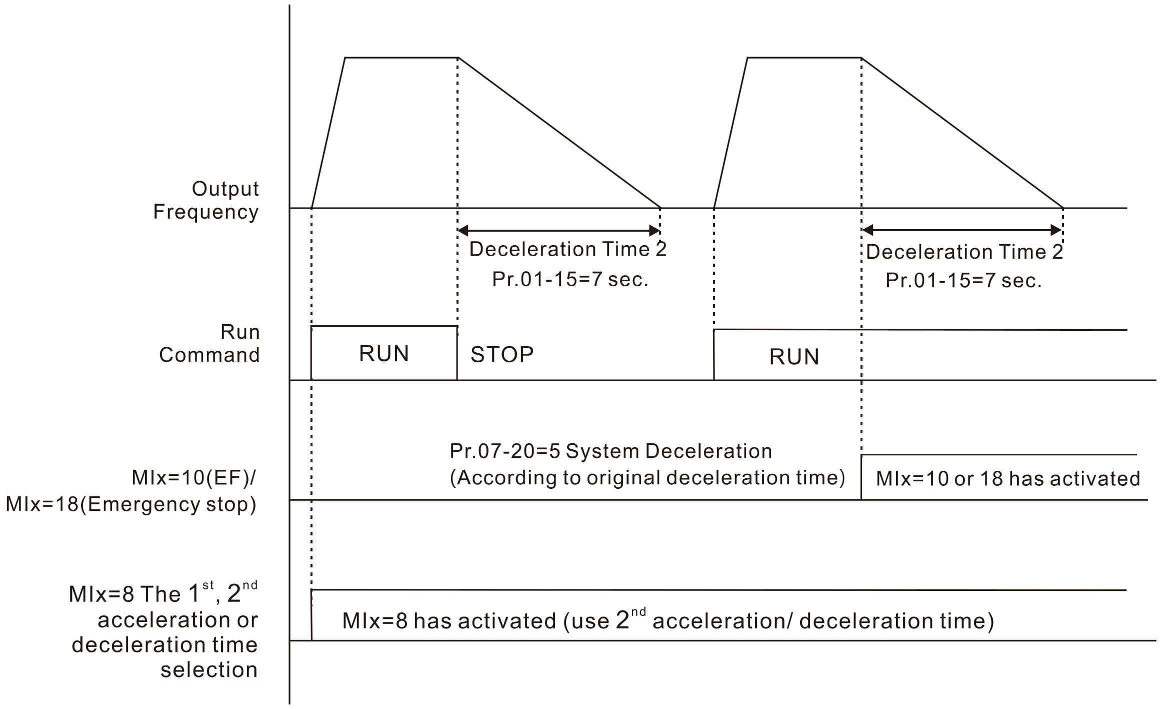
07-20 Emergency Stop (EF) & Force to Stop Selection

Default: 0

Settings
0: Coast to stop
1: Stop by the first deceleration time
2: Stop by the second deceleration time
3: Stop by the third deceleration time
4: Stop by the fourth deceleration time
5: System deceleration
6: Automatic deceleration

When the multi-function input terminal setting is set to 10 (EF input) or 18 (force to stop) and the terminal contact is ON, the drive stops according to the setting of this parameter.




Output Frequency
Deceleration Time 2
Pr.01-15=7 sec.
Deceleration Time 2
Pr.01-15=7 sec.
Run Command
RUN
STOP
RUN
MIx=10(EF)/
MIx=18(Emergency stop)
Pr.07-20=5 System Deceleration
(According to original deceleration time)
MIx=10 or 18 has activated
MIx=8 The 1st, 2nd acceleration or deceleration time selection
MIx=8 has activated (use 2nd acceleration/ deceleration time)

07-21 Automatic Energy-saving (AES) Selection

Default: 0

Settings 0: Disabled

1: Power factor energy-saving improvement (for VF and SVC control modes)

2: Automatic energy-saving optimization (for VF and SVC control modes)

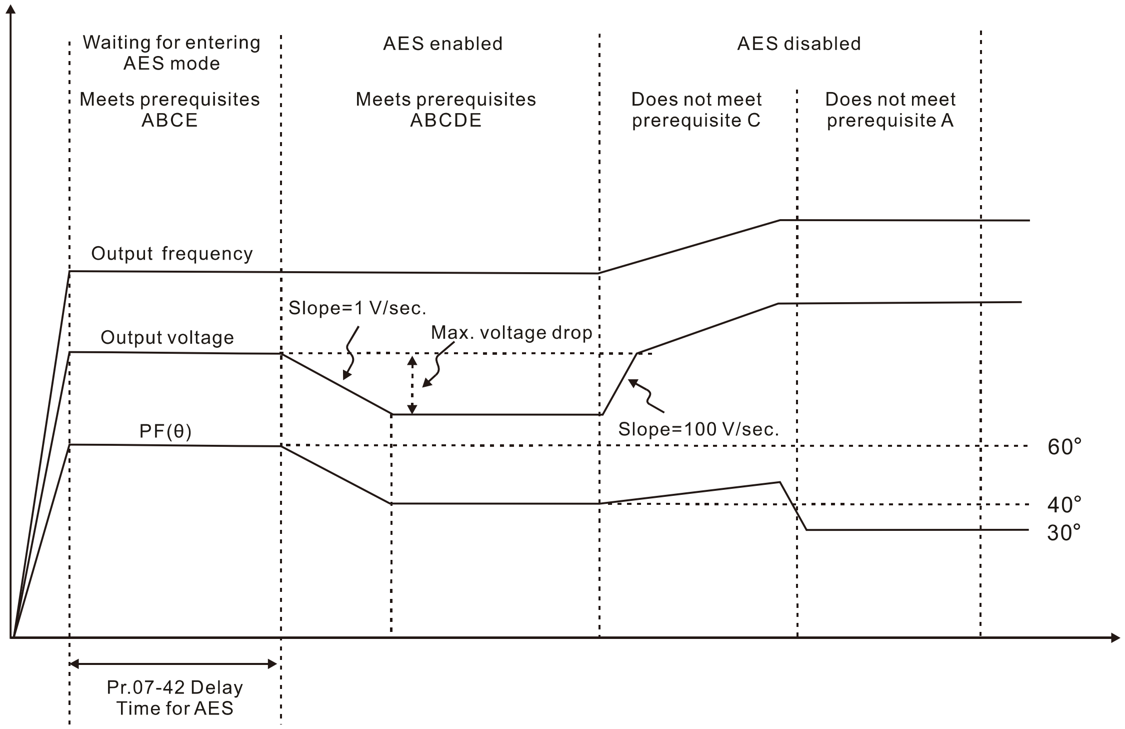
🕮 Different control modes for Pr.07-21:

Settings / Control mode	Induction Motor (IM)		Permanent Magnet Synchronous Motor (PM)		Synchronous Reluctance Motor (SynRM)
	VF	SVC	PMSVC	PMFOC	FOC
1: Power factor energy-saving improvement	✓	✓			
2: Automatic energy-saving optimization	✓	✓			

🕮 Power factor energy-saving improvement (Pr.07-21 = 1):

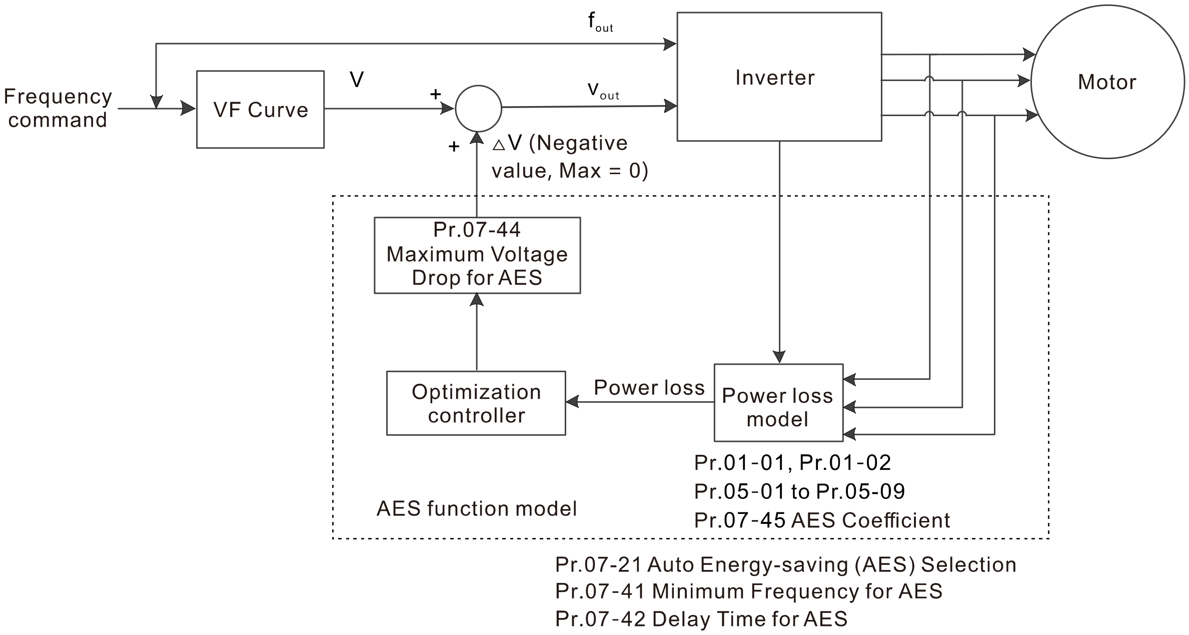
- When the automatic energy-saving function is enabled, the drive runs with full-voltage during acceleration and deceleration, and runs with the optimal voltage that is automatically calculated by the load power during constant operation. It is not recommended to use this function for applications that require frequent load changes or when the load is close to full-load during operation.
- The prerequisites for valid power factor energy-saving improvement (Pr.07-21 = 1) are:
  A. Power factor angle is larger than Pr.07-43 (Targeted Power Factor Angle for AES)
  B. Output frequency is larger than Pr.07-41 (Minimum Frequnecy for AES)
  C. The drive is in a steady-state output frequency status
  D. Time for steady-state output frequency is larger than Pr.07-42 (Delay Time for AES)
  E. Output current is smaller than or equal to 90% of the drive’s rated current

- The prerequisites for invalid power factor energy-saving improvement (Pr.07-21 = 1) are:
  1. A changing output frequency
  2. Output current is lager than 90% of the drive's rated current



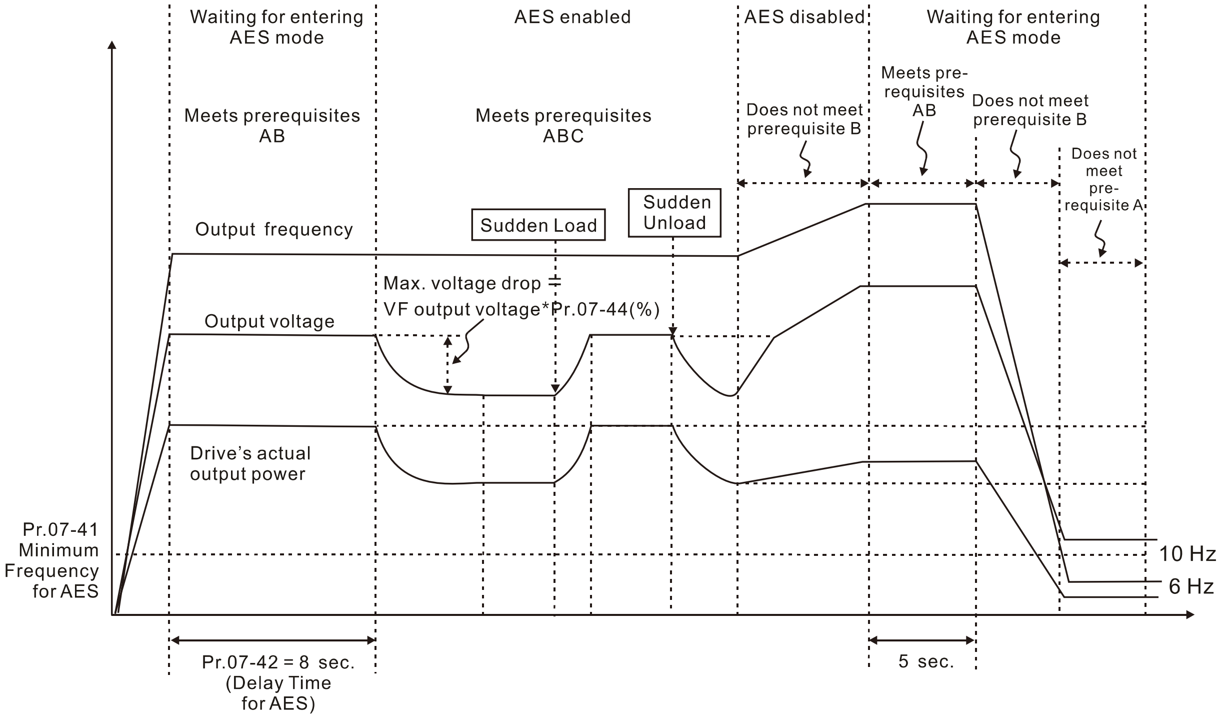
📖 Automatic energy-saving optimization (Pr.07-21 = 2):

- Controls the output voltage to minimize the motor's losses for optimal energy-saving. The motor's losses are calculated by motor parameter auto-tuning and energy-saving coefficient.
- Automatic energy-saving optimization control is according to the block diagram below:



- The prerequisites for valid automatic energy-saving optimization (Pr.07-21 = 2) are:
  A. Output frequency is larger than Pr.07-41 (Miminum Frequency for AES)
  B. The drive is in a steady-state output frequency status
  C. Time for steady-state output frequency is larger than Pr.07-42 (Delay Time for AES)

- The prerequisites for invalid automatic energy-saving optimization (Pr.07-21 = 2) are:
  1. A changing output frequency
  2. The loss model automatically determines the voltage drops when the drive is in normal and heavy duty. If there is no more voltage that can be adjusted, that is, the voltage drop is already optimized, AES is invalid.



📖 The energy-saving function is invalid during the drive's acceleration and deceleration. To make it valid, the prerequisites need to be verified again.

✎ 07-22 Energy-saving Gain

Default: 100

Settings 10–1000%

📖 When Pr.07-21 is set to 1, use this parameter to adjust the energy-saving gain. The default is 100%. If the result is not satisfactory, adjust it by decreasing the setting value. If the motor oscillates, then increase the setting value.

📖 In certain applications such as high speed spindles, the temperature rise in the motor is a major concern. When the motor is not in working state, reduce the motor current to a lower level. Reduce this parameter setting to meet this requirement.

✎ 07-23 Automatic Voltage Regulation (AVR) Function

Default: 0

Settings 0: Enable AVR
1: Disable AVR
2: Disable AVR during deceleration

📖 The rated voltage of the motor is usually 200–240 V_{AC} (380–480 V_{AC}), 60 Hz / 50 Hz and the input voltage of the AC motor drive may vary between 170–264 V_{AC} (323–528 V_{AC}), 50 Hz / 60 Hz. Therefore, when the AC motor drive is used without AVR function, the output voltage is the same as the input voltage. When the motor runs at the voltage exceeding 12–20% of the rated voltage, it causes higher temperature, damaged insulation, and unstable torque output, which result in losses due to shorter motor lifetime.

- The AVR function automatically regulates the output voltage of the AC motor drive to the motor's rated voltage when the input voltage exceeds the motor's rated voltage. For example, if the V/F curve is set at 200 V_{AC} / 50 Hz and the input voltage is at 200–264 V_{AC}, then the drive automatically reduces the output voltage to the motor to a maximum of 200 V_{AC} / 50 Hz. If the input voltage is at 170–200 V_{AC}, the output voltage to motor is in direct proportion to the input voltage.
- 0: When the AVR function is enabled, the drive calculates the output voltage according to the actual DC bus voltage. The output voltage does NOT change when the DC bus voltage changes.
- 1: When the AVR function is disabled, the drive calculates the output voltage according to the actual DC bus voltage. The output voltage changes with the DC bus voltage, and may cause insufficient current, over-current or oscillation.
- 2: The drive disables the AVR function only during deceleration to stop, and at this time, you can accelerate the braking to achieve the same result.
- When the motor ramps to stop, disable the AVR function to shorten the deceleration time. Then, use with the auto-acceleration and auto-deceleration functions to make the motor's deceleration more stable and quicker.

✎ 07-24 Torque Command Filter Time (V/F and SVC Control Mode)

Default: 0.500

Settings 0.001–10.000 sec.

- When the time constant setting is too large, the control is stable but the control response is slow. When the time constant setting is too small, the control response is faster but the control may be unstable. For optimal setting, adjust the setting based on the control stability or the control response.

✎ 07-25 Slip Compensation Filter Time (V/F and SVC Control Mode)

Default: 0.100

Settings 0.001–10.000 sec.

- Change the compensation response time with Pr.07-24 and Pr.07-25.
- If you set Pr.07-24 and Pr.07-25 to 10 seconds, the compensation response time is the slowest; however, the system may be unstable if you set the time too short.

✎ 07-26 Torque Compensation Gain

Default: 0

Settings IM: 0–10 (when Pr.05-33 = 0)
PM: 0–5000 (when Pr.05-33 = 1 or 2)

- Only applicable in IMVF and PMSVC control modes.
- With a large motor load, a part of the drive output voltage is absorbed by the stator winding resistor; therefore, the air gap magnetic field is insufficient. This causes insufficient voltage at motor induction and results in excessive output current but insufficient output torque. Auto-torque compensation can automatically adjust the output voltage according to the load and

keep the air gap magnetic fields stable to get the optimal operation.

- In the V/F control, the voltage decreases in direct proportion when decreasing frequency. The torque decreases at low speed because of a decreasing AC resistor and an unchanged DC resistor. The auto-torque compensation function increases the output voltage at low frequency to get a higher starting torque.
- When the compensation gain is set too large, it may cause motor over-flux and result in a too large output current of the drive, motor overheating or trigger the drive's protection function.

ϟ **07-27** Slip Compensation Gain

Default: 0.00

(1.00 in SVC mode)

Settings 0.00–10.00

- Only applicable in IMVF and IMSVC control modes.
- The induction motor needs constant slip to produce electromagnetic torque. It can be ignored at a higher motor speed, such as rated speed or 2–3% of slip.
- However, during the drive operation, the slip and the synchronous frequency are in reverse proportion to produce the same electromagnetic torque. The slip is larger with the reduction of synchronous frequency. Moreover, the motor may stop when the synchronous frequency decreases to a specific value. Therefore, the slip seriously affects the motor speed accuracy at low speed.
- In another situation, when you use an induction motor with the drive, the slip increases when the load increases. It also affects the motor speed accuracy.
- Use this parameter to set the compensation frequency, and reduce the slip to maintain the synchronous speed when the motor runs at the rated current in order to improve the accuracy of the drive. When the drive output current is higher than Pr.05-05 (No-load Current for Induction Motor 1 (A)), the drive compensates the frequency according to this parameter.
- This parameter is set to 1.00 automatically when Pr.00-11 (Speed Control Mode) is changed from V/F mode to vector mode. Otherwise, it is automatically set to 0.00. Apply the slip compensation after load and acceleration. Increase the compensation value from small to large gradually; add the output frequency to the [motor rated slip × Pr.07-27 (Slip Compensation Gain)] when the motor is at the rated load. If the actual speed ratio is slower than expected, increase the parameter setting value; otherwise, decrease the setting value.

ϟ **07-29** Slip Deviation Level

Default: 0.0

Settings 0.0–100.0%

0: No detection

ϟ **07-30** Over-slip Deviation Detection Time

Default:1.0

Settings 0.0–10.0 sec.

✎ 07-31 Over-slip Deviation Treatment

Default: 0

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop
3: No warning

📖 Pr.07-29 to Pr.07-31 set the allowable slip level / time and the over-slip treatment when the drive is running.

✎ 07-32 Motor Oscillation Compensation Factor

Default: 1000

Settings 0–10000
0: Disable

📖 If there are current wave motions which cause severe motor oscillation in some specific area, setting this parameter can effectively improve this situation. (When running with high frequency, set this parameter to 0. When the current wave motion occurs in low frequency and high power, increase the value for Pr.07-32.)

✎ 07-33 Auto-restart Interval of Fault

Default: 60.0

Settings 0.0–6000.0 sec.

📖 When a reset / restart occurs after a fault, the drive uses Pr.07-33 as a timer and starts counting the numbers of faults within this time period. Within this period, if the number of faults does not exceed the setting for Pr.07-11, the counting clears and starts from 0 when the next fault occurs.

✎ 07-38 PMSVC Voltage Feed Forward Gain

Default: 1.00

Settings 0.00–2.00

📖 Adjusts the PMSVC voltage feedback forward gain, and to meet the demand of rapid feedback application.

📖 Pr.07-38 = 1.00 means forward feedback = Ke × motor rotor speed

📖 Refer to Section 12-2 “PMSVC adjustment” for details.

✎ 07-41 Minimum Frequency for AES

Default: 10.00

Settings 0.00–40.00 Hz

📖 The drive’s output frequency must be larger than Pr.07-41 to make the drive determine whether to run in a steady-state output frequency.

📖 In general, larger power and voltage can give more energy-savings; lower power and voltage produce less energy-savings. However, too low power and voltage are not suitable for low-speed operation because it needs a larger starting current. Pr.07-41 is the parameter that limits the minimum frequency when AES is enabled (Pr.07-41 to Pr.01-00 is the frequency range – from minimum to maximum – that you can use for the AES function).

07-42 Delay Time for AES

Default: 5

Settings 0–600 sec.

- When the drive runs in a steady-state output frequency, and exceeds Pr.07-42 setting time, the drive enters the energy-saving mode.

07-43 Targeted Power Factor Angle for AES

Default: 40.00

Settings 0.00–65.00°

- Use this function when Pr.07-21 = 1. If the power factor angle is larger than Pr.07-43, the drive continuously adjusts the energy-saving until it is smaller than Pr.07-43.
- Pr.07-43 is the angle φ between active power and reactive power. The smaller COSφ, the lower the reactive power, and the lower the loss.

07-44 Maximum Voltage Drop for AES

Default: 60.00

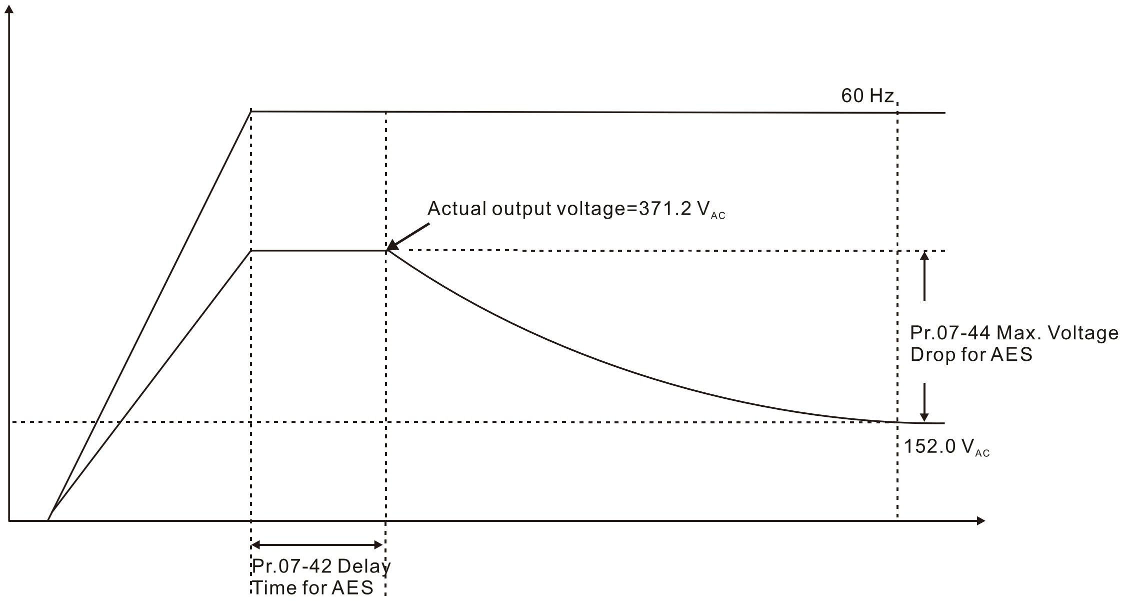
Settings 0.00–70.00%

- Defines the maximum allowed voltage drop when the drive is in energy-saving mode.
- The drive has bigger energy-saving efficiency when running in no-load or light-load. But the output voltage drop is not unlimited. Use Pr.07-44 to limit the maximum ratio (%) of the output voltage drop.

  Example:

  (1) If Pr.01-01 = 60 Hz, Pr.01-02 = 380 V_{AC}, the frequency command is 60 Hz and the actual voltage output is 371.2 V_{AC}, and Pr.07-44 = 60%, then the
  maximum voltage drop = 380V (the voltage command corresponding to the frequency command in the VF table: 60 Hz corresponds to 380V) × 60% = 228 V_{AC}.

  (2) If the frequency command is 30 Hz, the corresponding voltage is 200 V_{AC} in the VF table, and Pr.07-44 = 60%, then the maximum voltage drop = 200V × 60% = 120 V_{AC}.

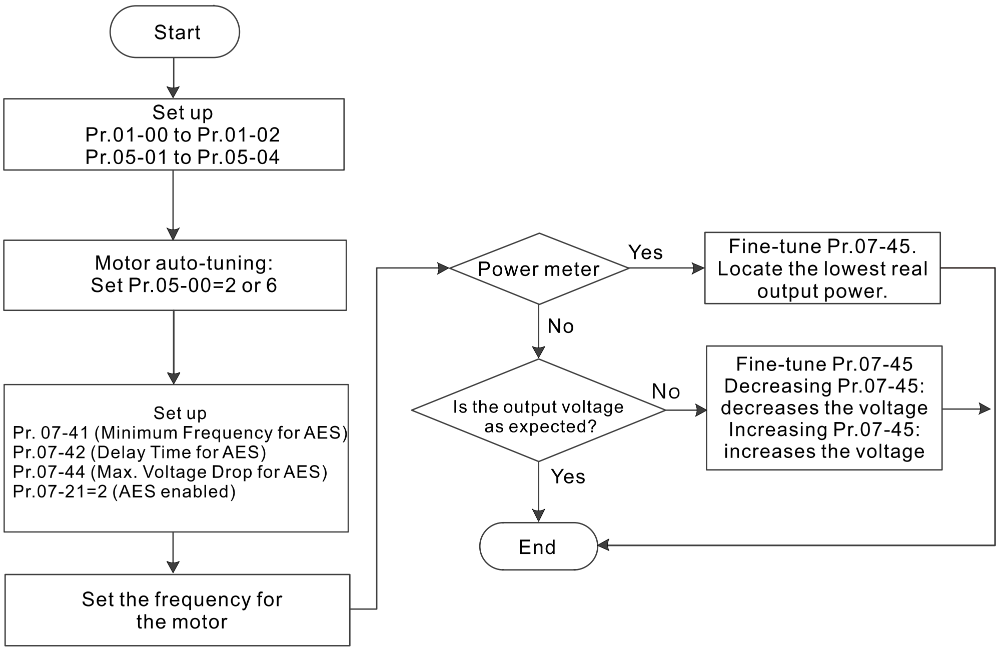


07-45 AES Coefficient

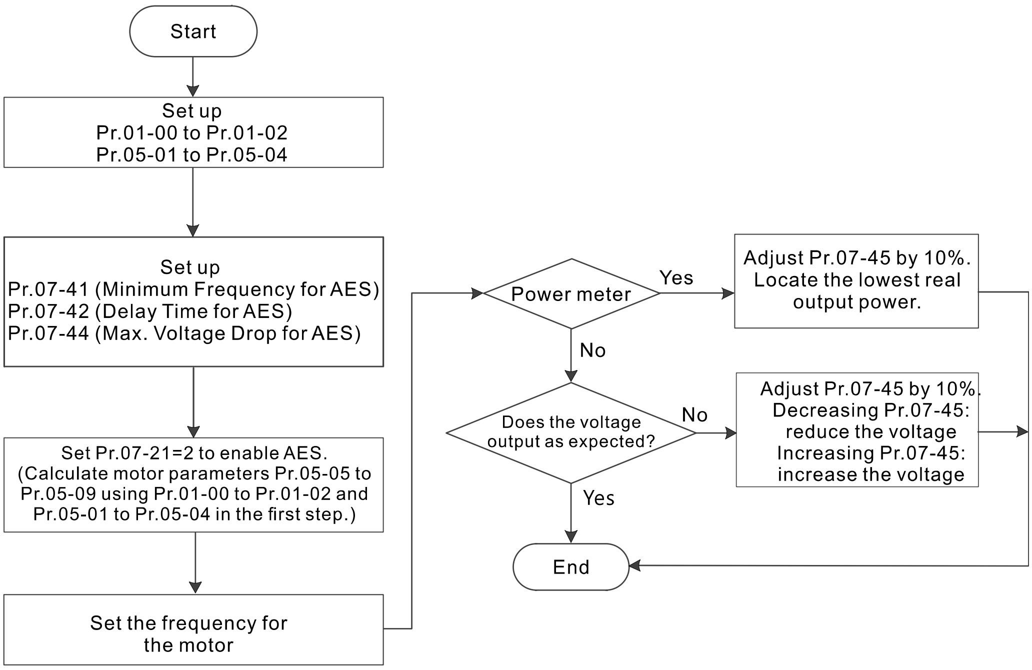
Default: 100

Settings 0–10000%

- Defines the motor power loss constant. Default 100% corresponds to the drive's iron loss constant that is calculated by motor parameter auto-tuning or motor nameplate information.
- Pr.07-45 affects the final steady-state output voltage value for the energy-saving control. The larger the Pr.07-45 setting value, the higher the steady-state output voltage (smaller voltage drop). The smaller the Pr.07-45 setting value, the lower the steady-state output voltage (larger voltage drop).
- See below for the flowchart of AES adjustment with motor parameter auto-tuning (recommended):


Start
Set up
Pr.01-00 to Pr.01-02
Pr.05-01 to Pr.05-04
Motor auto-tuning:
Set Pr.05-00=2 or 6
Set up
Pr. 07-41 (Minimum Frequency for AES)
Pr.07-42 (Delay Time for AES)
Pr.07-44 (Max. Voltage Drop for AES)
Pr.07-21=2 (AES enabled)
Set the frequency for the motor
Power meter
Yes
Fine-tune Pr.07-45. Locate the lowest real output power.
No
Is the output voltage as expected?
No
Fine-tune Pr.07-45
Decreasing Pr.07-45: decreases the voltage
Increasing Pr.07-45: increases the voltage
Yes
End

- See below for the flowchart of AES adjustment without motor parameter auto-tuning (not recommended):


Start
Set up
Pr.01-00 to Pr.01-02
Pr.05-01 to Pr.05-04
Set up
Pr.07-41 (Minimum Frequency for AES)
Pr.07-42 (Delay Time for AES)
Pr.07-44 (Max. Voltage Drop for AES)
Set Pr.07-21=2 to enable AES.
(Calculate motor parameters Pr.05-05 to Pr.05-09 using Pr.01-00 to Pr.01-02 and Pr.05-01 to Pr.05-04 in the first step.)
Set the frequency for the motor
Power meter
Yes
Adjust Pr.07-45 by 10%. Locate the lowest real output power.
No
Does the voltage output as expected?
No
Adjust Pr.07-45 by 10%.
Decreasing Pr.07-45: reduce the voltage
Increasing Pr.07-45: increase the voltage
Yes
End

ϟ 07-50 PWM Fan Speed

Default: 60

Settings 60–100%

- 🕮 For different application and environment, adjust the fan speed to expedite the heat dissipation of the drive.
- 🕮 Default for 460V models (45 kW, 55 kW, 75 kW, 90 kW and 110 kW) is 80%; default for other models are 60%.
- 🕮 230V models : 18.5 kW and above models are controlled by PWM fan speed control, and Pr.07-50 is available.
- 🕮 460V models : 22kW and above models are controlled by PWM fan speed control, and Pr.07-50 is available.
- 🕮 575V / 690V models are all controlled by PWM, and Pr.07-50 is available.

08 High-function PID Parameters

⌁ You can set this parameter during operation.

⌁ 08-00 Terminal Selection of PID Feedback

Default: 0

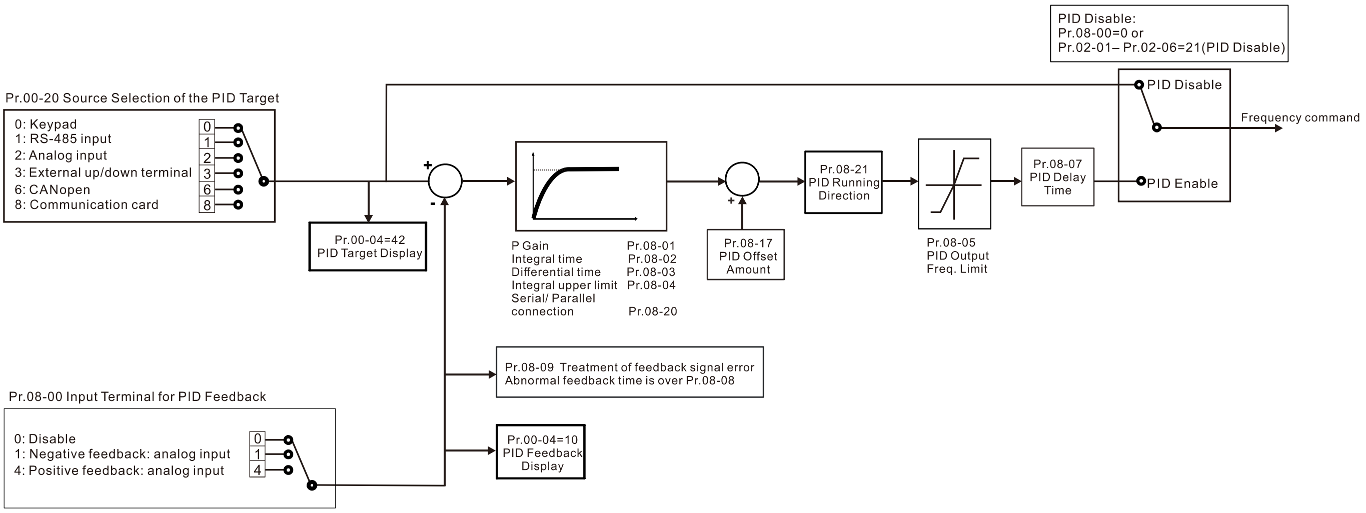
Settings 0: No function

1: Negative PID feedback: by analog input (Pr.03-00–03-02)

4: Positive PID feedback: by analog input (Pr.03-00–03-02)

- Pr.08-00 ≠ 0 enables the PID function.
- Negative feedback:
  Error = +Target value (set point) – Feedback. Use negative feedback when the detection value increases if the output frequency increases.
- Positive feedback:
  Error = -Target value (set point) + Feedback. Use positive feedback when the detection value decreases if the output frequency increases.
- When Pr.08-00 ≠ 7 or ≠ 8, the input value is disabled. The setting value does not remain when the drive is powered off.
- When Pr.08-00 ≠ 0, the related applicable parameters include:
  - Pr.00-20 (Master frequency command source (AUTO) / Source selection of the PID target)
  - Pr.03-00–03-02
    When Pr.00-20 = 2 (External analog input), set Pr.03-00–03-02 = 4 (PID tartget value)
    When Pr.08-00 = 2 or 4, set Pr.03-00–03-02 = 5 (PID feedback signal)

  Refer to the following description for details.


PID Disable:
Pr.08-00=0 or
Pr.02-01– Pr.02-06=21(PID Disable)
Pr.00-20 Source Selection of the PID Target
0: Keypad
1: RS-485 input
2: Analog input
3: External up/down terminal
6: CANopen
8: Communication card
0
1
2
3
6
8
PID Disable
Frequency command
PID Enable
+
-
+
Pr.00-04=42
PID Target Display
P Gain Pr.08-01
Integral time Pr.08-02
Differential time Pr.08-03
Integral upper limit Pr.08-04
Serial/ Parallel connection Pr.08-20
Pr.08-17
PID Offset
Amount
Pr.08-21
PID Running
Direction
Pr.08-05
PID Output
Freq. Limit
Pr.08-07
PID Delay
Time
Pr.08-09 Treatment of feedback signal error
Abnormal feedback time is over Pr.08-08
Pr.08-00 Input Terminal for PID Feedback
0: Disable
1: Negative feedback: analog input
4: Positive feedback: analog input
0
1
4
Pr.00-04=10
PID Feedback
Display

00-20 Master Frequency Command Source (AUTO) / Source Selection of the PID Target

Default: 0

Settings 0: Digital keypad

1: RS-485 communication input

2: External analog input (Refer to Pr.03-00)

3: External UP/DOWN terminal

6: CANopen communication card

8: Communication card (does not include CANopen card)

03-00 Analog Input Selection (AVI1)

Default: 1

03-01 Analog Input Selection (ACI)

Default: 0

03-02 Analog Input Selection (AVI2)

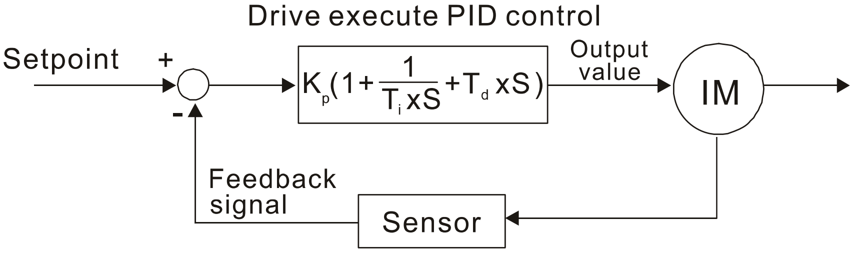
Default: 0

Settings 4: PID target value
5: PID feedback signal

Common applications for PID control

1. Flow control: Use a flow sensor to feedback the flow data and perform accurate flow control.
2. Pressure control: Use a pressure sensor to feedback the pressure data and perform precise pressure control.
3. Air volume control: Use an air volume sensor to feedback the air volume data to achieve excellent air volume regulation.
4. Temperature control: Use a thermocouple or thermistor to feedback temperature data for comfortable temperature control.
5. Speed control: Use a speed sensor feedback motor shaft speed or input another machine speed as a target value for synchronous control.

PID control loop:



K_P Proportional Gain (P), T_i Integral Time (I), T_d Differential Time (D), S Calculation

Concept of PID control

Proportional gain (P):

The output is proportional to input. With only proportional gain control, there is always a steady-state error.

Adjustment: Turn off the Ti and Td, or remain Ti and Td in constant value, then adjust the proportional gain (P).

Increase: Faster status feedback, but excessive adjustment increases the overshoot.

Decrease: Smaller overshoot, but excessive adjustment slows down the transient response.

🕮 Integral time(I):

The controller output is proportional to the integral of the controller input. When an automatic control system is in a steady state and a steady-state error occurs, the system is called a System with Steady-state Error. To eliminate the steady-state error, add an “integral part” to the controller. The integral time controls the relation between integral part and the error. The integral part increases over time even if the error is small. It gradually increases the controller output to eliminate the error until it is zero. This stabilizes the system without a steady-state error by using proportional gain control and integral time control.

Adjustment: The integral time (I) accumulates from the time difference, if the vibration cycle is longer than the setting for integral time, the integration enhances. Increase the integral time (I) to reduce the vibration.

Increase: Reduce the overshoot, excessive adjustment causes worse transient response.

Decrease: Faster transient response, but the transient time will be longer, and takes more time to achieve the steady state. Excessive adjustment causes larger overshoot.

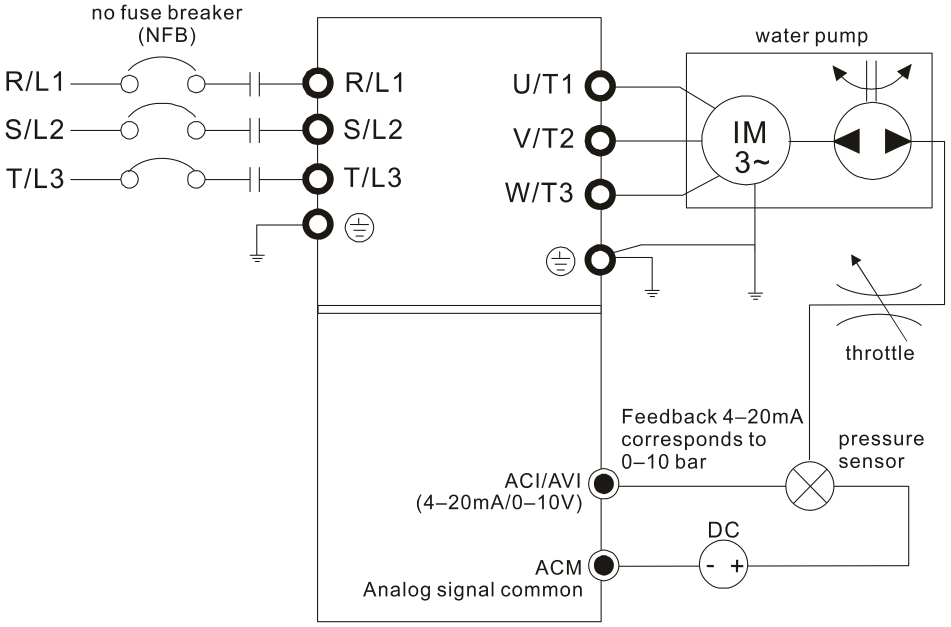
🕮 Differential control (D):

The controller output is proportional to the differential of the controller input. During elimination of the error, oscillation or instability may occur. Use the differential control to suppress these effects by acting before the error. That is, when the error is near zero, the differential control should be zero. Use proportional gain (P) and differential control (D) to improve the system state during PID adjustment.

Adjustment: When the vibration cycle is shorter and continuous, it means that the differential time setting is too large, and causes excessive output. Decrease the setting of D gain to reduce the vibration. If the D gain is set to 0, adjust the PID control again.

Using PID control in a constant pressure pump feedback application:

Set the application's constant pressure value (bar) to be the set point of PID control. The pressure sensor sends the actual value as the PID feedback value. After comparing the PID set point and PID feedback, an error displays. The PID controller calculates the output by using proportional gain (P), integral time (I) and differential time (D) to control the pump. It controls the drive to use a different pump speed and achieves constant pressure control by using a 4–20 mA signal corresponding to 0–10 bar as feedback to the drive.



- Pr.00-04 = 10 (Display PID feedback (b) (%))
- Pr.01-12 Acceleration Time is set according to actual conditions.
- Pr.01-13 Deceleration Time is set according to actual conditions.
- Pr.00-21 = 0, operate through the digital keypad
- Pr.00-20 = 0, the digital keypad controls the set point.
- Pr.08-00 = 1 (Negative PID feedback from analog input)
- ACI analog input Pr.03-01 = 5, PID feedback signal.
- Pr.08-01–08-03 is set according to actual conditions:
  If there is no oscillation in the system, increase Pr.08-01 (Proportional Gain (P))
  If there is no oscillation in the system, reduce Pr.08-02 (Integral Time (I))
  If there is no oscillation in the system, increase Pr.08-03 (Differential Time (D))
- Refer to Pr.08-00–08-21 for PID parameter settings.

08-01 Proportional Gain (P)

Default: 1.0

Settings 0.0–100.0

🕮 1.0: Kp gain is 100%; if the setting is 0.5, Kp gain is 50%.

🕮 Sets the proportional gain to determine the deviation response speed. The higher the proportional gain, the faster the response speed. Eliminates the system deviation; usually used to decrease the deviation and get faster response speed, it also reduces the steady-state error. If you set the value too high, overshoot occurs and it may cause system oscillation and instability.

📖 If you set the other two gains (I and D) to zero, proportional control is the only effective parameter.

↯ 08-02 Integral Time (I)

Default: 1.00

Settings 0.00–100.00 sec.
0.00: No integral

📖 Use the integral controller to eliminate the deviation during stable system operation. The integral control does not stop working until the deviation is zero. The integral is affected by the integral time. The smaller the integral time, the stronger integral action. It is helpful to reduce overshoot and oscillation for a stable system. Accordingly, the speed to lower the steady-state deviation decreases. The integral control is often used with the other two controls for the PI controller or PID controller.

📖 Sets the integral time of the I controller. When the integral time is long, there is a small I controller gain, with slower response and slow external control. When the integral time is short, there is a large gain of I controller gain, with faster response and rapid external control.

📖 When the integral time is too short, it may cause overshoot or oscillation for the output frequency and system.

📖 Set Integral Time to 0.00 to disable the I controller.

↯ 08-03 Differential Time (D)

Default: 0.00

Settings 0.00–1.00 sec.

📖 Use the differential controller to show the system deviation change, as well as to preview the change in the deviation. You can use the differential controller to eliminate the deviation in order to improve the system state. Using a suitable differential time can reduce overshoot and shorten adjustment time; however, the differential operation increases noise interference. Note that a too large differential causes more noise interference. In addition, the differential shows the change and the output is 0 when there is no change. Note that you cannot use the differential control independently. You must use it with the other two controllers for the PD controller or PID controller.

📖 Sets the D controller gain to determine the deviation change response. Using a suitable differential time reduces the P and I controllers overshoot to decrease the oscillation for a stable system. A differential time that is too long may cause system oscillation.

📖 The differential controller acts on the change in the deviation and cannot reduce the interference. Do not use this function when there is significant interference.

↯ 08-04 Upper limit of Integral Control

Default: 100.0

Settings 0.0–100.0%

📖 Defines an upper bound for the integral gain (I) and therefore limits the master frequency. The formula is: Integral upper bound = Maximum Output Frequency (Pr.01-00) x Pr.08-04 %.

📖 An excessive integral value causes a slow response due to sudden load changes and may cause motor stall or machine damage. If so, decrease it to a proper value.

✎ 08-05 PID Output Command Limit

Default: 100.0

Settings 0.0–110.0%

📖 Defines the percentage of the output command limit during the PID control. The formula is Output Command Limit = Maximum Operation Frequency (Pr.01-00 x Pr.08-05 %).

✎ 08-06 PID Feedback Value Display

Default: Read only

Settings -200.00–200.00%

✎ 08-07 PID Delay Time

Default: 0.0

Settings 0.0–35.0 sec.

08-20 PID Mode Selection

Default: 0

Settings 0: Serial connection
1: Parallel connection

📖 0: Serial connection, use conventional PID control structure.

📖 1: Parallel connection, the proportional gain, integral gain and differential gain are independent. You can customize the P, I and D value to fit your application.

📖 Pr.08-20 determines the primary low pass filter time when in PID control. Setting a large time constant may slow down the drive's response speed.

📖 PID control output frequency is filtered with a primary low pass function. This function can filter a mix frequencies. A long primary low pass time means the filter degree is high and a short primary low pass time means the filter degree is low.

📖 Inappropriate delay time setting may cause system oscillation.

📖 PI Control:

Controlled only by the P action, so the deviation cannot be entirely eliminated. In general, to eliminate residual deviations, use the P + I control. When you use the PI control, it eliminates the deviation caused by the targeted value changes and the constant external interferences. However, if the I action is too powerful, it delays the response when there is rapid variation. You can use the P action by itself to control the loading system with the integral components.

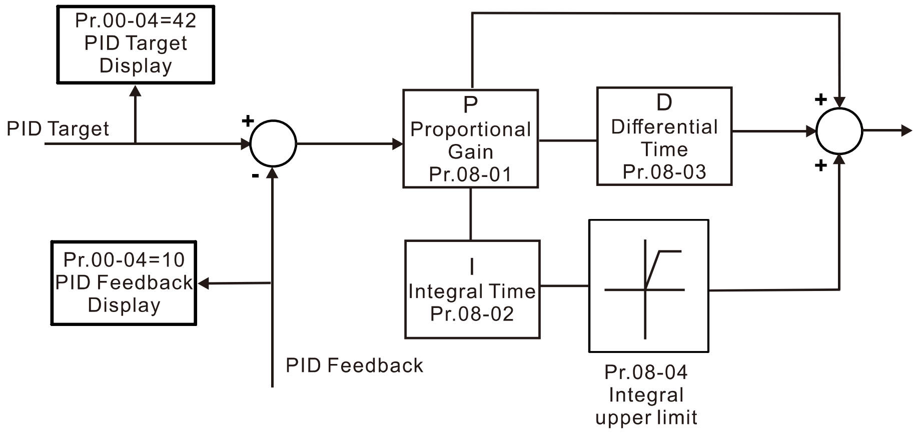
📖 PD Control:

When deviation occurs, the system immediately generates an operation load that is greater than the load generated only by the D action to restrain the deviation increment. If the deviation is small, the effectiveness of the P action decreases as well. The control objects include applications with integral component loads, which are controlled by the P action only. Sometimes, if the integral component is functioning, the whole system may oscillate. In this case, use the PD control to reduce the P action's oscillation and stabilize the system. In other words, this control is useful with no brake function's loading over the processes.

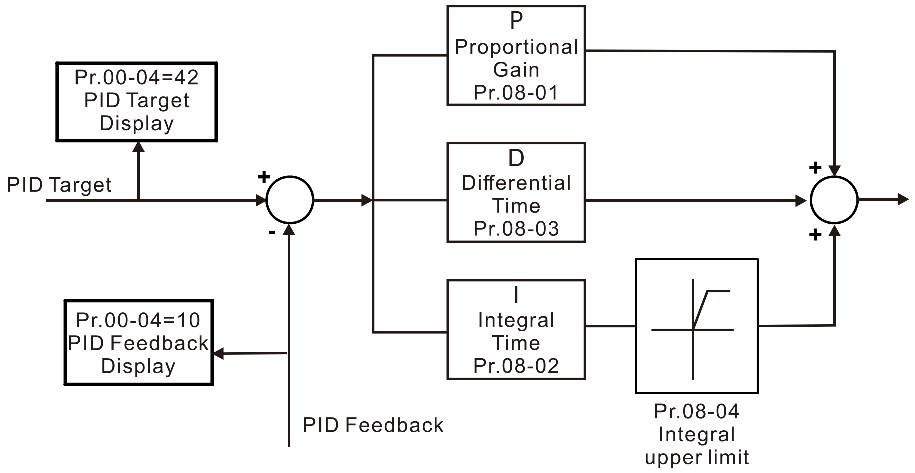
📖 PID Control:

Use the I action to eliminate the deviation and the D action to reduce oscillation; then combine this with the P action for the PID control. Use the PID method for a control process with no deviations, high accuracies and a stable system.

Serial connection



Parallel connection



✎ 08-08 Feedback Signal Detection Time

Default: 0.0

Settings 0.0–3600.0 sec.

🕮 Valid only when the feedback signal is ACI (4–20 mA).

🕮 This parameter sets the detection time for abnormal PID signal feedback. You can also use it when the system feedback signal response is extremely slow. (Setting the detection time to 0.0 disables the detection function.)

✎ 08-09 Feedback Signal Fault Treatment

Default: 0

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop
3: Warn and operate at last frequency

🕮 Valid only when the feedback signal is ACI (4–20 mA).

🕮 Sets the treatments when the PID feedback signal is abnormal.

✓ 08-10 Sleep Level

Default: 0.00

Settings 0.00–599.00 Hz or 0–200.00%

📖 Determines the sleep level, and if the sleep time and the wake-up level are enabled or disabled. When Pr.08-10 = 0: Disabled; when Pr.08-10 ≠ 0: Enabled.

✓ 08-11 Wake-up Level

Default: 0.00

Settings 0.00–599.00 Hz or 0–200.00%

📖 When Pr.08-18 = 0, the unit for Pr.08-10 and that for Pr.08-11 switch to frequency. The settings become 0.00–599.00 Hz.

📖 When Pr.08-18 = 1, the unit for Pr.08-10 and that for Pr.08-11 switch to percentage. The settings are between 0–200.00%.

📖 The percentage is based on the current command value, not the maximum value. For example, if the maximum value is 100 kg, and the current command value is 30 kg, then if Pr.08-11 = 40%, the value is 12 kg.

📖 Pr.08-10 uses the same logic for calculation.

✓ 08-12 Sleep Delay Time

Default: 0.0

Settings 0.0–6000.0 sec.

📖 When the frequency command is smaller than the sleep frequency and less than the sleep time, the frequency command is equal to the sleep frequency. However, the frequency command remains at 0.00 Hz until the frequency command becomes equal to or larger than the wake-up frequency.

✓ 08-13 PID Feedback Signal Error Deviation Level

Default: 10.0

Settings 1.0–50.0%

✓ 08-14 PID Feedback Signal Error Deviation Detection Time

Default: 5.0

Settings 0.1–300.0 sec.

📖 When the PID control function is normal, it should calculate the value within a period of time that is close to the target value.

📖 Refer to the PID control diagram for details. When executing PID feedback control, if |PID reference target value – detection value| > Pr.08-13 PID Feedback Signal Error Deviation Level and exceeds Pr.08-14 setting, it is regarded as a PID control fault, and the multi-function output terminal setting 15 (PID feedback error) activates.

✓ 08-16 PID Compensation Selection

Default: 0

Settings 0: Parameter setting (Pr.08-17)

1: Analog input

- 0: The setting for Pr.08-17 gives the PID compensation value.
- 1: Set the analog input (Pr.03-00–Pr.03-02) to 13, then the PID compensation value of analog input is displayed on Pr.08-17. At this time, Pr.08-17 is read only.

✓ 08-17 PID Compensation

Default: 0.0

Settings -100.0–100.0%

- The PID compensation value = maximum PID target value × Pr.08-17. For example, if the maximum operation frequency Pr.01-00 = 60.00 Hz, Pr.08-17 = 10.0%, the PID compensation value increases the output frequency 6.00 Hz. 60.00 Hz × 100.00% × 10.0% = 6.00 Hz

08-18 Sleep Mode Function Setting

Default: 0

Settings 0: Refer to PID output command

1: Refer to PID feedback signal

- 0: The unit for Pr.08-10 and that for Pr.08-11 switch to frequency. The settings are between 0.00–599.00 Hz.
- 1: The unit for Pr.08-10 and that for Pr.08-11 switch to percentage. The settings are between 0–200.00%.

✓ 08-19 Wake-up Integral Limit

Default: 50.0

Settings 0.0–200.0%

- The wake-up integral limit for the drive prevents suddenly running at high speed when the drive wakes up. Defines the wake-up integral frequency limit = (Pr.01-00 × Pr.08-19%)
- Reduces the reaction time from sleep to wake-up.

08-21 Enable PID to Change the Operation Direction

Default: 0

Settings 0: Operation direction cannot be changed

1: Operation direction can be changed

✓ 08-22 Wake-up Delay Time

Default: 0.00

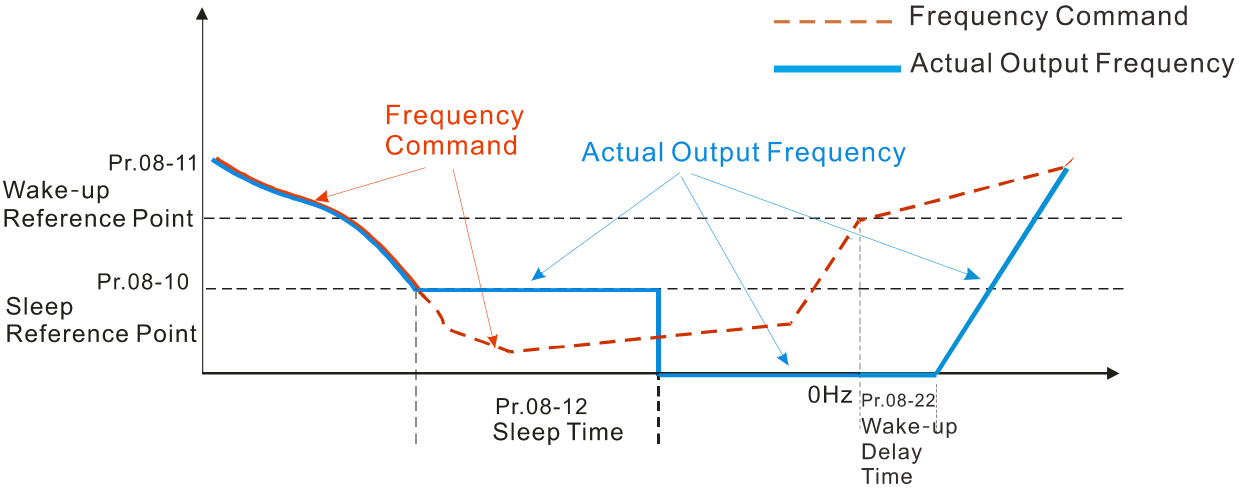
Settings 0.00–600.00 sec.

- Refer to Pr.08-18 for more information.

There are three scenarios for the sleep and wake-up frequency. Refer to following explanations:

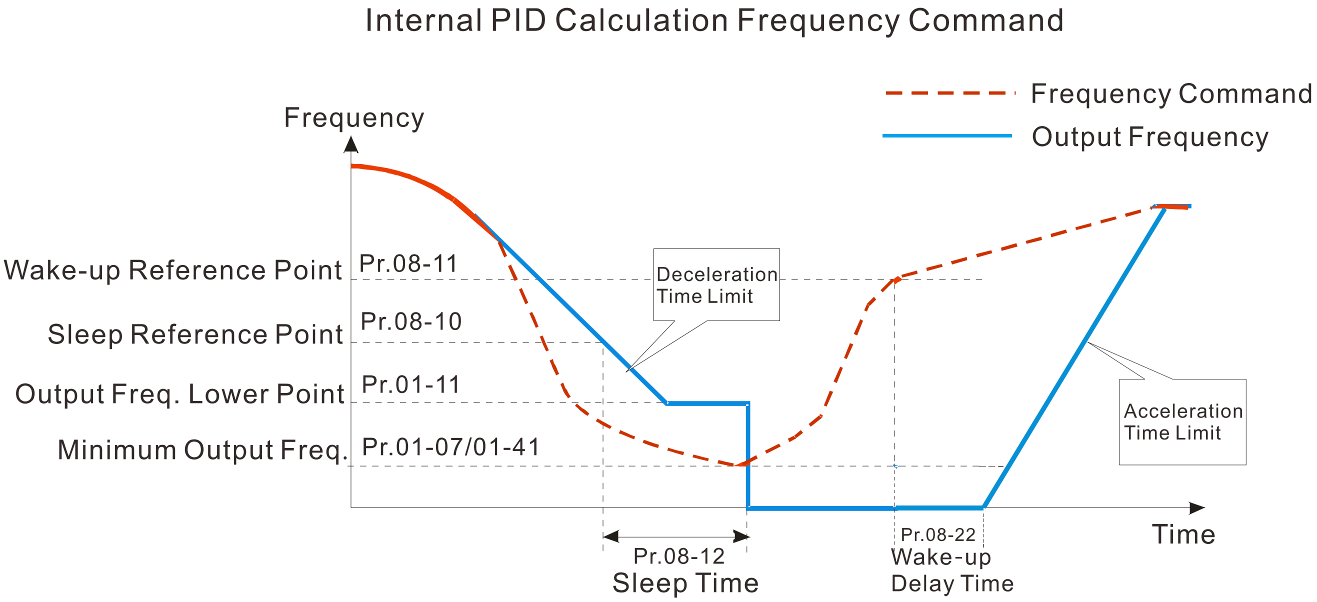
1. Frequency Command (PID is not in use, Pr.08-00 = 0. Works only in VF mode)

   When the output frequency ≤ the sleep frequency, and the drive reaches the preset sleep time, then the drive is in sleep mode (0 Hz). When the Frequency command reaches the wake-up frequency, the drive starts to count the wake-up delay time. When the drive reaches the wake-up delay time, it starts to catch up to reach the Frequency command value by the acceleration time.



2. Internal PID Calculation Frequency Command (PID is in use, Pr.08-00 ≠ 0 and Pr.08-18 = 0)

   When the PID calculation Frequency command reaches the sleep frequency, the drive starts to count the sleep time and the output frequency starts to decrease. If the drive exceeds the preset sleep time, then the drive is in sleep mode (0 Hz). If the drive does not reach the preset sleep time, it remains at the lower frequency limit (if there is a preset of lower limit), or it remains at the minimum output frequency set at Pr.01-07 and waits until it reaches the sleep time before it going into sleep mode (0 Hz). When the PID calculated Frequency command reaches the wake-up frequency, the drive starts to count the wake-up delay time. Once it reaches the wake-up delay time, the drive starts to catch up to reach the PID Frequency command value by the acceleration time.



3. PID Feedback Value Rate Percentage (PID is in use, Pr.08-00 ≠ 0 and Pr.08-18 = 1)

When the PID feedback value reaches the sleep level percentage, the drive starts to count the sleep time and the output frequency starts to decrease. If the drive exceeds the preset sleep time, then the drive is in sleep mode (0 Hz). If the drive does not reach the preset sleep time, it remains at the lower frequency limit (if there is a preset of lower limit.), or it remains at the minimum output frequency set for Pr.01-07 and waits until it reaches the sleep time before going into sleep mode (0 Hz).

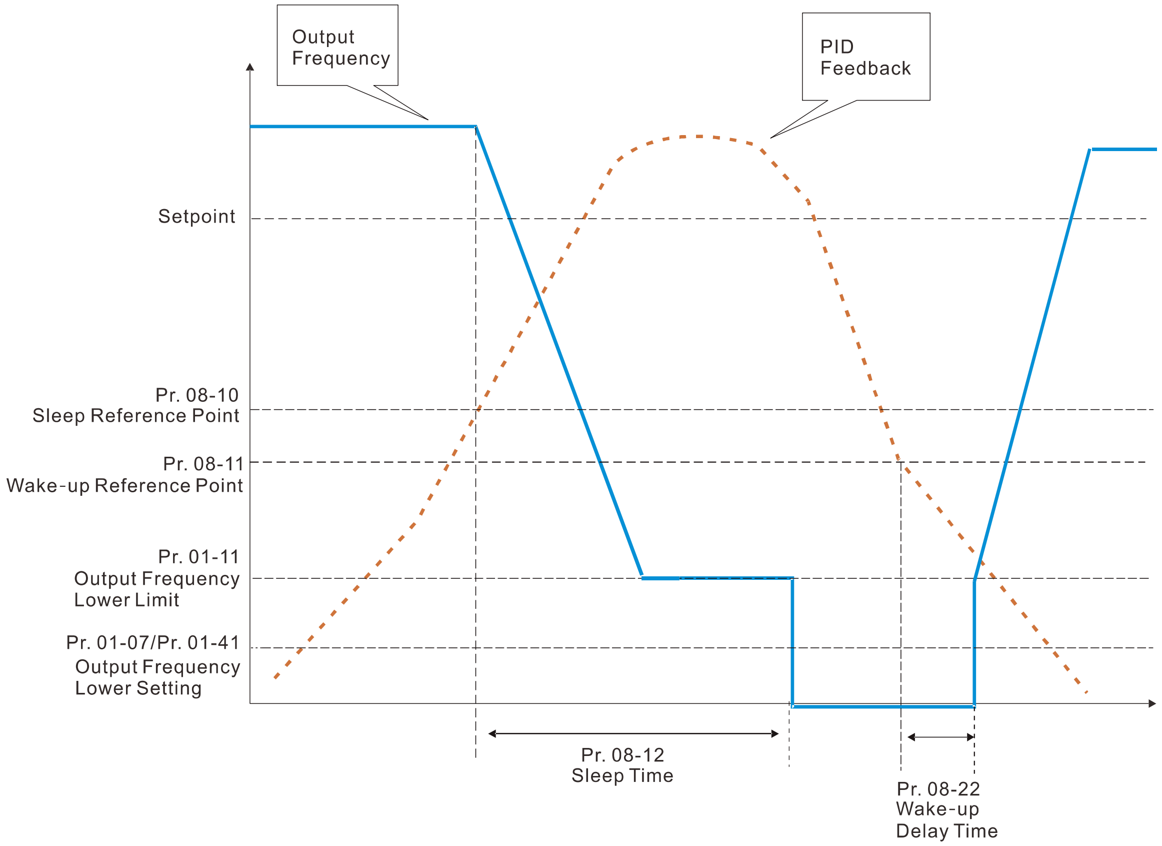
When the PID feedback value reaches the wake-up percentage, the drive starts to count the wake-up delay time. Once it reaches the wake-up delay time, the drive starts to catch up to reach the PID Frequency command value by the acceleration time.

Example 01: PID negative feedback

- Pr.08-10 must > Pr.08-11
- 30 kg is the reference
- Set the parameter:

  Pr.03-00 = 5 (AVI1 is PID feedback)
  Pr.08-00 = 1 (PID negative feedback: AVI1 simulation input function select)
  Pr.08-10 = 40% (Sleep reference: 12 kg = 40% × 30 kg)
  Pr.08-11 = 20% (Wake-up reference: 6 kg = 20% × 30 kg)
  Case 01: If feedback > 12 kg, frequency decreases.
  Case 02: If feedback < 6 kg, frequency increases.

Area	PID Physical quantity
Sleep area	> 12 kg, the drive goes into sleep, the motor goes into sleep
Excessive area	between 6 kg and 12 kg, the drive remains in current state
Wake-up area	< 6 kg, the drive wakes-up, the motor wakes-up



Example 02: PID positive feedback

- Pr.08-10 must < Pr.08-11
- 30 kg is the reference
- Set the parameter:

  Pr.03-00 = 5 (AVI1 is PID feedback)

  Pr.08-00 = 4 (PID positive feedback: AVI1 simulation input function select)

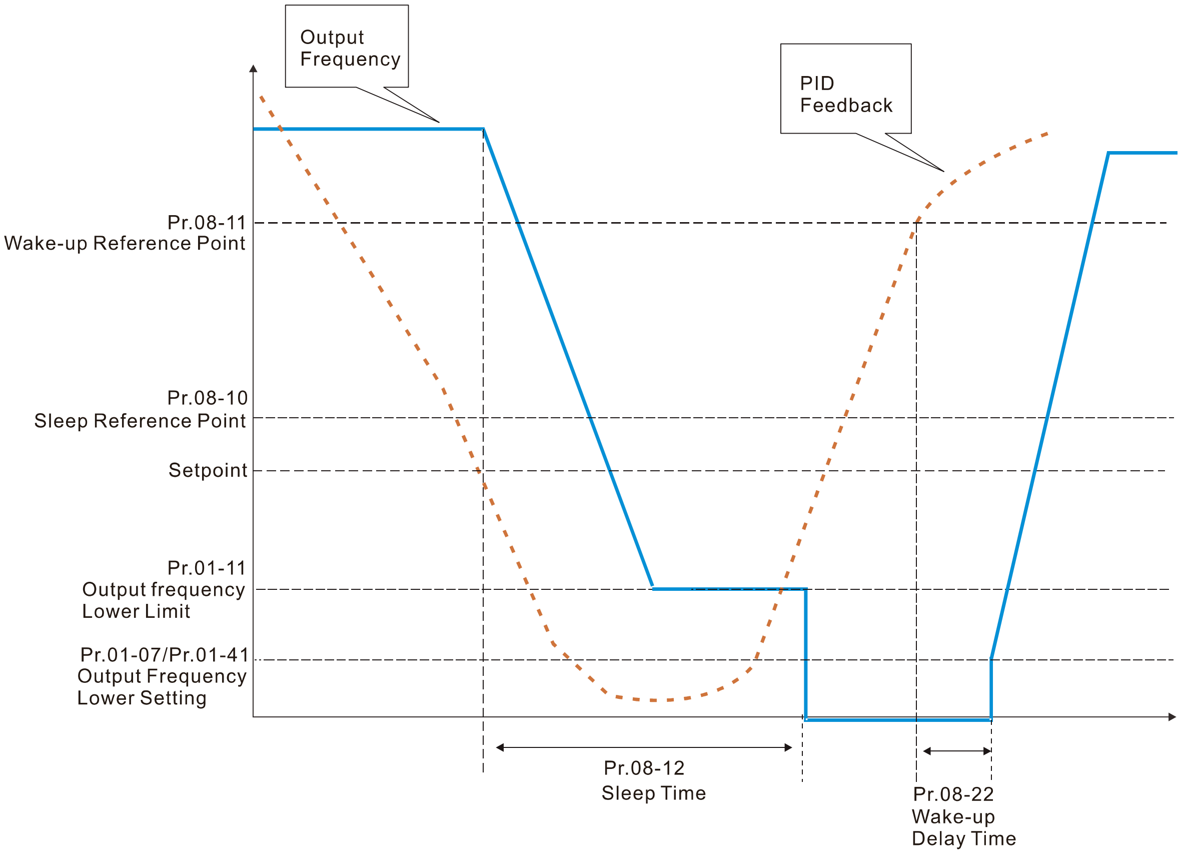
  Pr.08-10 = 110% (Sleep reference: 33 kg = 110% × 30 kg)

  Pr.08-11 = 120% (Wake-up reference: 36 kg = 120% × 30 kg)

  Case 01: If feedback < 33 kg, frequency decreases.

  Case 02: If feedback > 36 kg, frequency increases.

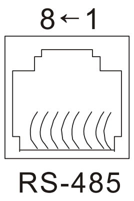
Area	**PID Physical quantity**
Sleep area	> 36 kg, the drive goes into sleep, the motor goes into sleep
Excessive area	between 33 kg and 36 kg, the drive remains in the current state
Wake-up area	< 33 kg, the drive wakes-up



09 Communication Parameters

✎ You can set this parameter during the operation.

When using the communication interface, the diagram on the right shows the communication port pin definitions. We recommend that you connect the AC motor drive to your PC by using Delta IFD6530 orIFD6500 as a communication converter.



Modbus RS-485
Pin 1, 2, 6: Reserved
Pin 3, 7: SGND
Pin 4: SG-
Pin 5: SG+
Pin 8: +10VS

✎ 09-00 Communication Address

Default: 1

Settings 1–254

📖 Sets the communication address for the drive if the AC motor drive is controlled through RS-485 serial communication. The communication address for each AC motor drive must be unique.

✎ 09-01 COM1 Transmission Speed

Default: 9.6

Settings 4.8–115.2 Kbps

📖 Sets the transmission speed between the computer and the AC motor drive.

📖 Options are 4.8 Kbps, 9.6 Kbps, 19.2 Kbps, 38.4 Kbps, 57.6 Kbps or 115.2 Kbps; otherwise, the transmission speed is set to the default 9.6 Kbps.

✎ 09-02 COM1 Transmission Fault Treatment

Default: 3

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop
3: No warning, no fault and continue operation

📖 Determines the treatment when an error is detected that the host controller does not continuously transmit data to the AC motor drive during Modbus communication. The detection time is based on the Pr.09-03 setting.

✎ 09-03 COM1 Time-out Detection

Default: 0.0

Settings 0.0–100.0 sec.

📖 Sets the communication transmission time-out value.

✎ 09-04 COM1 Communication Protocol

Default: 1

Settings 1: 7, N, 2 (ASCII)
2: 7, E, 1 (ASCII)
3: 7, O, 1 (ASCII)
4: 7, E, 2 (ASCII)
5: 7, O, 2 (ASCII)
6: 8, N, 1 (ASCII)

7: 8, N, 2 (ASCII)
8: 8, E, 1 (ASCII)
9: 8, O, 1 (ASCII)
10: 8, E, 2 (ASCII)
11: 8, O, 2 (ASCII)
12: 8, N, 1 (RTU)
13: 8, N, 2 (RTU)
14: 8, E, 1 (RTU)
15: 8, O, 1 (RTU)
16: 8, E, 2 (RTU)
17: 8, O, 2 (RTU)

📖 Control by PC (Computer Link)

When using the RS-485 serial communication interface, you must specify each drive's communication address in Pr.09-00. The computer then implements control using the drives' individual addresses.

📖 Modbus ASCII (American Standard Code for Information Interchange): Each byte of data is the combination of two ASCII characters. For example, one byte of data: 64 Hex, shown as '64' in ASCII, consists of '6' (36Hex) and '4' (34Hex).

1. **Code Description**

The communication protocol is in hexadecimal, ASCII: "0"…"9", "A"…"F", every hexadecimal value represents an ASCII code. The following table shows some examples:

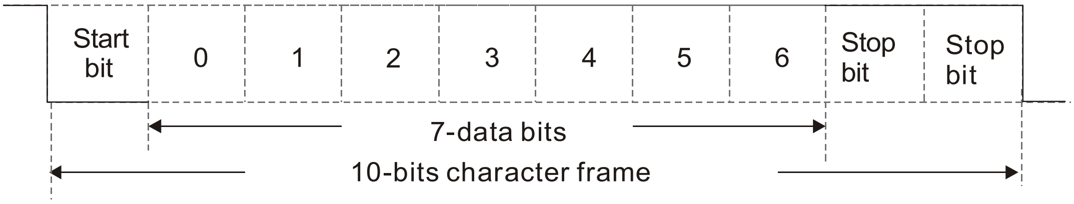
Character	'0'	'1'	'2'	'3'	'4'	'5'	'6'	'7'
ASCII code	30H	31H	32H	33H	34H	35H	36H	37H

Character	'8'	'9'	'A'	'B'	'C'	'D'	'E'	'F'
ASCII code	38H	39H	41H	42H	43H	44H	45H	46H

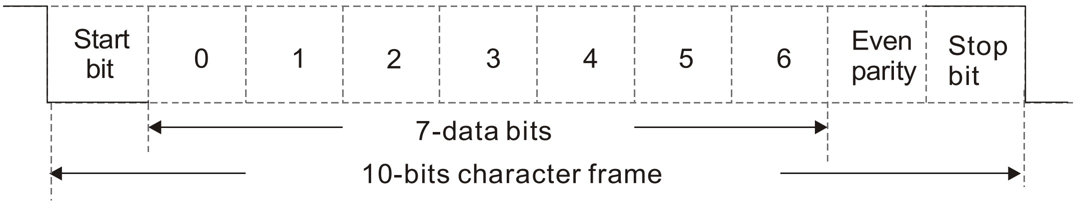
2. **Data Format**

10-bit character frame (For ASCII):

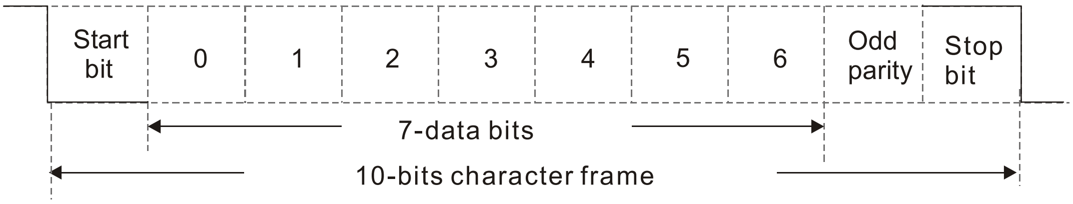
(7, N, 2)



(7, E, 1)

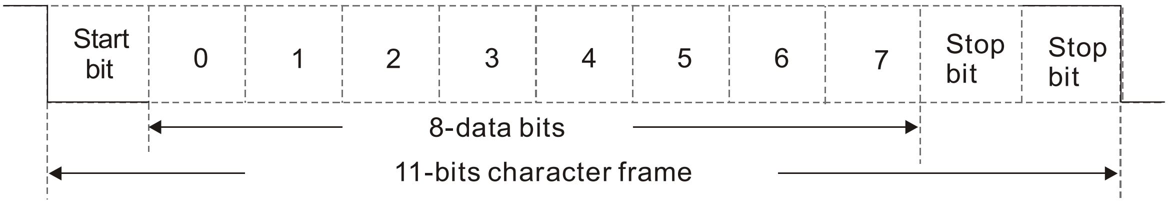


(7, O, 1)

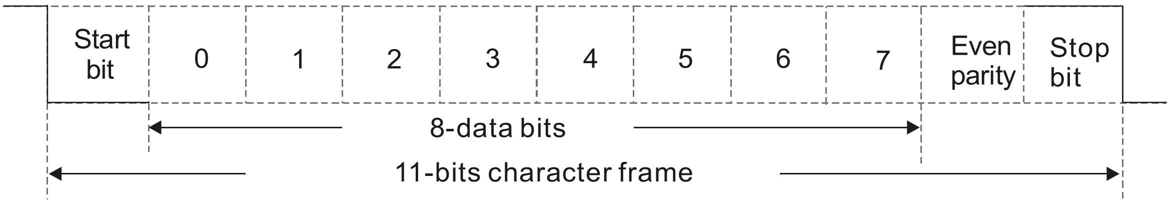


11-bit character frame (For RTU):

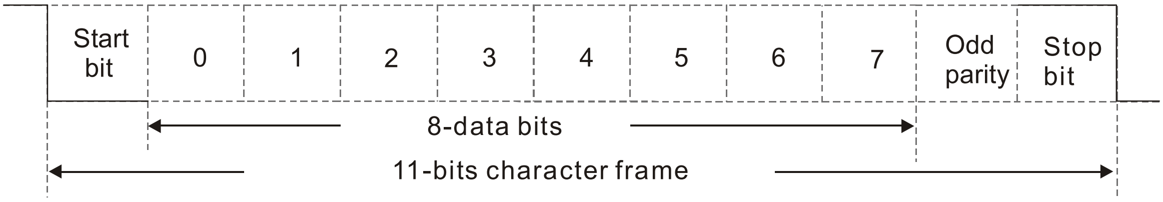
(8, N, 2)



(8, E, 1)



(8, O, 1)



3. Communication Protocol

3.1 Communication Data Frame:

ASCII mode

STX	Start character = ‘:’ (3AH)
Address High	Communication address: one 8-bit address consists of 2 ASCII codes
Address Low	
Function High	Command code: one 8-bit command consists of 2 ASCII codes
Function Low	
DATA (n-1)	Contents of data: n × 8-bit data consist of 2n ASCII codes n ≤ 16, maximum of 32 ASCII codes
…….	
DATA 0	
LRC Check High	LRC checksum: one 8-bit checksum consists of 2 ASCII codes
LRC Check Low	
END High	End characters: END1 = CR (0DH), END0 = LF(0AH)
END Low	

RTU mode

START	Defined by a silent interval of larger than / equal to 10 ms
Address	Communication address: 8-bit binary address
Function	Command code: 8-bit binary command
DATA (n-1)	Contents of data: n × 8-bit data, $n \leq 16$
…….	
DATA 0	
CRC Check Low	CRC checksum: one 16-bit CRC checksum consists of 2 8-bit binary characters
CRC Check High	
END	Defined by a silent interval of larger than / equal to 10 ms

3.2 Communication Address (Address)

00H: broadcast to all AC motor drives

01H: AC motor drive of address 01

0FH: AC motor drive of address 15

10H: AC motor drive of address 16

:

FEH: AC motor drive of address 254

3.3 Function (Function code) and DATA (data characters)

03H: read data from register

06H: write single register

10H: write continuous multiple data

Example: Reading two continuous data from register address 2102H, AMD address is 01H.

ASCII mode:

Command Message:

STX	‘:’
Address	‘0’
	‘1’
Function	‘0’
	‘3’
Starting register	‘2’
	‘1’
	‘0’
	‘2’
Number of register (count by word)	‘0’
	‘0’
	‘0’
	‘2’
LRC Check	‘D’
	‘7’
END	CR
	LF

Response Message

STX	‘:’
Address	‘0’
	‘1’
Function	‘0’
	‘3’
Number of register (count by byte)	‘0’
	‘4’
Content of starting register 2102H	‘1’
	‘7’
	‘7’
	‘0’
Content of register 2103H	‘0’
	‘0’
	‘0’
	‘0’
LRC Check	‘7’
	‘1’
END	CR

RTU mode:

Command Message:

Address	01H
Function	03H
Starting data register	21H
	02H
Number of register (count by word)	00H
	02H
CRC Check Low	6FH
CRC Check High	F7H

Response Message

Address	01H
Function	03H
Number of register (count by byte)	04H
Content of register address 2102H	17H
	70H
Content of register address 2103H	00H
	00H
CRC Check Low	FEH
CRC Check High	5CH

06H: single write, write single data to register.

Example: Writing data 6000 (1770H) to register 0100H. AMD address is 01H.

ASCII mode:

Command Message:

STX	‘:’
Address	‘0’
	‘1’
Function	‘0’
	‘6’
Target register	‘0’
	‘1’
	‘0’
	‘0’
Register content	‘1’
	‘7’
	‘7’
	‘0’
LRC Check	‘7’
	‘1’
END	CR
	LF

Response Message

STX	‘:’
Address	‘0’
	‘1’
Function	‘0’
	‘6’
Target register	‘0’
	‘1’
	‘0’
	‘0’
Register content	‘1’
	‘7’
	‘7’
	‘0’
LRC Check	‘7’
	‘1’
END	CR
	LF

RTU mode:

Command Message:

Address	01H
Function	06H
Target register	01H
	00H
Register content	17H
	70H
CRC Check Low	86H
CRC Check High	22H

Response Message

Address	01H
Function	06H
Target register	01H
	00H
Register content	17H
	70H
CRC Check Low	86H
CRC Check High	22H

10H: write multiple registers (can write at most 20 sets of data simultaneously).

Example: Set the multi-step speed of an AC motor drive (address is 01H),
Pr.04-00 = 50.00 (1388H), Pr.04-01 = 40.00 (0FA0H).

ASCII Mode

Command Message:

STX	‘:’
ADR 1 ADR 0	‘0’
	‘1’
CMD 1	‘1’
CMD 0	‘0’
Target register	‘0’
	‘4’
	‘0’
	‘0’
Number of register (count by word)	‘0’
	‘0’
	‘0’
	‘2’
Number of register (count by byte)	‘0’
	‘4’
The first data content	‘1’
	‘3’
	‘8’
	‘8’
The second data content	‘0’
	‘F’
	‘A’
	‘0’
LRC Check	‘9’
	‘B’
END	CR
	LF

Response Message

STX	‘:’
ADR 1 ADR 0	‘0’
	‘1’
CMD 1	‘1’
CMD 0	‘0’
Target register	‘0’
	‘4’
	‘0’
	‘0’
Number of register (count by word)	‘0’
	‘0’
	‘0’
	‘2’
LRC Check	‘E’
	‘9’
END	CR
	LF

RTU mode:

Command Message:

ADR	01H
CMD	10H
Target register	04H
	00H
Number of register (Count by word)	00H
	02H
Quantity of data (byte)	04
The first data content	13H
	88H
The second data content	0FH
	A0H
CRC Check Low	‘9’
CRC Check High	‘A’

Response Message:

ADR	01H
CMD 1	10H
Target register	04H
	00H
Number of register (Count by word)	00H
	02H
CRC Check Low	40H
CRC Check High	F8H

3.4 Checksum

(1) ASCII mode (LRC Check):

LRC (Longitudinal Redundancy Check) is calculated by summing up the values of the bytes from ADR1 to last data character then calculating the hexadecimal representation of the 2’s-complement negation of the sum.

For example,

01H+03H+21H+02H+00H+02H=29H, the 2’s-complement negation of 29H is D7H.

(2) RTU mode (CRC Check):

CRC (Cyclical Redundancy Check) is calculated by the following steps:

Step 1: Load a 16-bit register (called CRC register) with FFFFh.

Step 2: Exclusive OR the first 8-bit byte of the command message with the low order byte of the 16-bit CRC register, putting the result in the CRC register.

Step 3: Examine the LSB of CRC register.

Step 4: If the LSB of CRC register is 0, shift the CRC register one bit to the right, fill MSB with zero, then repeat step 3. If the LSB of CRC register is 1, shift the CRC register one bit to the right, fill MSB with zero, Exclusive OR the CRC register with the polynomial value A001H, then repeat step 3.

Step 5: Repeat step 3 and 4 until you perform eight shifts. This processes a complete 8-bit byte.

Step 6: Repeat step 2 through 5 for the next 8-bit byte of the command message. Continue doing this until all bytes are processed. The final contents of the CRC register are the CRC value. When transmitting the CRC value in the message, the upper and lower bytes of the CRC value must be swapped, that is, the lower order byte is transmitted first.

The following is an example of CRC generation using C language.

The function takes two arguments:

Unsigned char* data ← a pointer to the message buffer

Unsigned char length ← the quantity of bytes in the message buffer

The function returns the CRC value as a type of unsigned integer.

```
Unsigned int crc_chk(unsigned char* data, unsigned char length)
 {
        int j;
        unsigned int reg_crc=0xffff;
        while(length--){
              reg_crc ^= *data++;
              for(j=0;j<8;j++){
                    if(reg_crc & 0x01){   /* LSB(b0)=1 */
                          reg_crc=(reg_crc>>1) ^ 0xa001;
                    }else{
                          reg_crc=reg_crc >>1;
                    }
              }
        }
        return reg_crc;                        // return register CRC
  }
```

4. Address list

AC motor drive parameters (GGxx)

Modbus address	Function
GGnnH	GG is the parameter group, nn is the parameter number; for example, the address of Pr.04-10 is 040AH.

Control command (20xx)

Modbus address	R/W	Function	
2000H	RW	bit1–0	00B: No function
			01B: Stop
			10B: Run
			11B: JOG + RUN
		bit3–2	Reserved
		bit5–4	00B: No function
			01B: FWD
			10B: REV
			11B: Change direction
		bit7–6	00B: 1st acceleration / deceleration
			01B: 2nd acceleration / deceleration
			10B: 3rd acceleration / deceleration
			11B: 4th acceleration / deceleration
		bit11–8	0000B: Master speed
			0001B: 1st Step speed frequency
			0010B: 2nd Step speed frequency
			0011B: 3rd Step speed frequency
			0100B: 4th Step speed frequency
			0101B: 5th Step speed frequency
			0110B: 6th Step speed frequency
			0111B: 7th Step speed frequency
			1000B: 8th Step speed frequency
			1001B: 9th Step speed frequency
			1010B: 10th Step speed frequency
			1011B: 11th Step speed frequency
			1100B: 12th Step speed frequency
			1101B: 13th Step speed frequency
			1110B: 14th Step speed frequency
			1111B: 15th Step speed frequency
		bit12	1: Enable bit06–11 function
		bit15	Reserved
2001H	RW	Frequency command (XXX.XX Hz)	

Modbus address	R/W	Function	
2002H	RW	bit0	1: E.F. ON
		bit1	1: Reset
		bit2	1: Base block (B.B) ON
		bit15–3	Reserved

Status monitor read only (21xx)

Modbus address	R/W	Function	
2100H	R	High byte: Warn Code Low Byte: Error Code	
2101H	R	bit1–0	AC motor drive operation status 00B: Drive stops 01B: Drive decelerating 10B: Drive standby 11B: Drive operating
		bit2	1: JOG Command
		bit4–3	Operation Direction 00B: FWD run 01B: From REV run to FWD run 10B: From FWD run to REV run 11B: REV run
		bit8	1: Master frequency controlled by communication interface
		bit9	1: Master frequency controlled by analog/external signal
		bit10	1: Operation command controlled by communication interface
		bit11	1: Parameter locked
		bit12	1: Enable to copy parameters from keypad
		bit15–13	Reserved
2102H	R	Frequency command (XXX.XX Hz)	
2103H	R	Output frequency (XXX.XX Hz)	
2104H	R	Output current (XX.XX A). When current is higher than 655.35, it shifts the decimal as (XXX.X A). The decimal can refer to High byte of 211F.	
2105H	R	DC bus Voltage (XXX.X V)	
2106H	R	Output voltage (XXX.X V)	
2107H	R	Current step number of multi-step speed operation	
2108H	R	Reserved	
2109H	R	Counter value	
210AH	R	Power factor angle (XXX.X)	
210CH	R	Actual motor speed (XXXXX rpm)	
210DH	R	Reserved	

Modbus address	R/W	Function
210EH	R	Reserved
210FH	R	Power output (X.XXX kW)
2116H	R	Multi-function display (Pr.00-04)
211BH	R	Maximum Operation Frequency (Pr.01-00) or Maximum User-defined Value (Pr.00-26) When Pr.00-26 is 0, this value is equal to Pr.01-00 setting When Pr.00-26 is not 0, and the command source is keypad, this value = Pr.00-24 × Pr.00-26 / Pr.01-00 When Pr.00-26 is not 0, and the command source is 485, this value = Pr.09-10 × Pr.00-26 / Pr.01-00
211FH	R	High byte: decimal of current value (display)

Status monitor read only (22xx)

Modbus address	RW	Function
2200H	R	Display output current (A). When current is higher than 655.35, it shifts the decimal as (XXX.X A). The decimal can refer to High byte of 211F.
2201H	R	Display counter value ©
2202H	R	Actual output frequency (XXXXX Hz)
2203H	R	DC bus voltage (XXX.X V)
2204H	R	Output voltage (XXX.X V)
2205H	R	Power angle (XXX.X)
2206H	R	Display actual motor speed kW of U, V, W (XXXX.X kW)
2207H	R	Display motor speed in rpm estimated by the drive or encoder feedback (XXXXX rpm)
2208H	R	Display positive/negative output torque in %, estimated by the drive (XXX.X %)
2209H	R	Reserved
220AH	R	PID feedback value after enabling PID function (XXX.XX %)
220BH	R	Display signal of AVI1 analog input terminal, 0–10 V corresponds to 0.00–100.00% (1.) (see NOTE 2 in Pr.00-04)
220CH	R	Display signal of ACI analog input terminal, 4–20 mA / 0–10 V corresponds to 0.00–100.00% (2.) (see NOTE 2 in Pr.00-04)
220DH	R	Display signal of AVI2 analog input terminal, -10 V–10 V corresponds to -100.00–100% (3.) (see NOTE 2 in Pr.00-04)
220EH	R	IGBT temperature of drive power module (XXX.X°C)
220FH	R	The temperature of capacitance (XXX.X°C)
2210H	R	The status of digital input (ON/OFF), refer to Pr.02-12 (see NOTE 3 in Pr.00-04)

Modbus address	RW	Function	
2211H	R	The status of digital output (ON/OFF), refer to Pr.02-18 (see NOTE 4 in Pr.00-04)	
2212H	R	The multi-step speed that is executing (S)	
2213H	R	The corresponding CPU pin status of digital input (d.) (see NOTE 3 in Pr.00-04)	
2214H	R	The corresponding CPU pin status of digital output (O.) (see NOTE 4 in Pr.00-04)	
2215H	R	Reserved	
2216H	R	Reserved	
2217H	R	Reserved	
2218H	R	Reserved	
2219H	R	Display times of counter overload (XXX.XX %)	
221AH	R	GFF (XXX.XX %)	
221BH	R	DC bus voltage ripples (XXX.X V)	
221CH	R	PLC register D1043 data (C)	
221DH	R	Reserved	
221EH	R	User page displays the value in physical measure	
221FH	R	Output Value of Pr.00-05 (XXX.XX Hz)	
2220H	R	Number of motor turns when drive operates (saves when drive stops, and resets to zero when operating)	
2221H	R	Operating position of the motor (saves when drive stops, and resets to zero when operating)	
2222H	R	Fan speed of the drive (XXX %)	
2223H	R	Control mode of the drive 0: speed mode	
2224H	R	Carrier frequency of the drive (XXXX kHz)	
2225H	R	Reserved	
2226H	R	Drive status bit1–0	00b: No direction 01b: Forward 10b: Reverse
		bit3–2	01b: Drive ready 10b: Error
		bit4	0b: Motor drive did not output 1b: Motor drive did output
		bit5	0b: No alarm 1b: Alarm
2228H	R	Reserve	
2229H	R	kWh display (XXXX.X)	
222AH	R	Reserve	

Modbus address	RW	Function
222BH	R	Reserve
222CH	R	Reserve
222DH	R	Reserve
222EH	R	PID reference (XXX.XX %)
222FH	R	PID offset (XXX.XX %)
2230H	R	PID output frequency (XXX.XX Hz)
2231H	R	Hardware ID

Remote IO (26xx)

Modbus address	RW	Function
2600H	R	Each bit corresponds to different terminal input contact
2640H	RW	Each bit corresponds to different terminal output contact
2660H	R	AVI1 proportional value
2661H	R	ACI proportional value
2662H	R	AVI2 proportional value
266AH	R	Extension card AI10, 0.0–100.0% (EMC-A22A)
266BH	R	Extension card AI11, 0.0–100.0% (EMC-A22A)
26A0H	RW	AFM1 output proportional value
26A1H	RW	AFM2 output proportional value
26AAH	RW	Extension card AO10, 0.0–100.0% (EMC-A22A)
26ABH	RW	Extension card AO11, 0.0–100.0% (EMC-A22A)

5. **Exception response:**

When the drive is using the communication connection, if an error occurs, the drive responds to the error code and sets the highest bit (bit7) of the command code to 1 (function code AND 80H), then responds to the control system to signal that an error occurred.

If the keypad displays “CE-XX” as a warning message, “XX” is the error code at that time. Refer to the table of error codes for communication error for reference.

Example:

ASCII mode:

STX	‘:’
Address	‘0’
	‘1’
Function	‘8’
	‘6’
Exception code	‘0’
	‘2’
LRC Check	‘7’
	‘7’
END	CR
	LF

RTU mode:

Address	01H
Function	86H
Exception code	02H
CRC Check Low	C3H
CRC Check High	A1H

The explanation of exception codes:

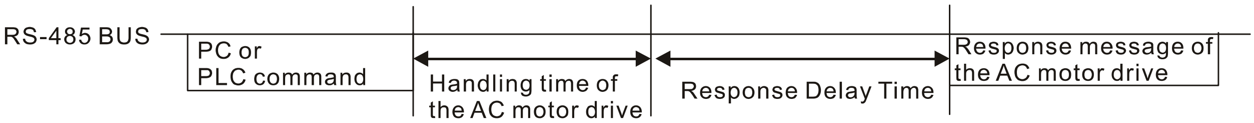
Exception code	Explanation
1	Function code is not supported or unrecognized.
2	Address is not supported or unrecognized.
3	Data is not correct or unrecognized.
4	Failure to execute this function code
10	Transformation for over-time duration

✔ 09-09 Communication Response Delay Time

Default: 2.0

Settings 0.0–200.0 ms

📖 If the host controller does not finish the transmitting / receiving process, you can use this parameter to set the response delay time after the AC motor drive receives communication command as shown in the following picture.


RS-485 BUS
PC or PLC command
Handling time of the AC motor drive
Response Delay Time
Response message of the AC motor drive

09-10 Communication Main Frequency

Default: 60.00

Settings 0.00–599.00 Hz

📖 When you set Pr.00-20 to 1 (RS-485 serial communication input), the AC motor drive saves the last Frequency command into Pr.09-10 when there is abnormal power off or momentary power loss. When power is restored, the AC motor drive operates with the frequency in Pr.09-10 if no new Frequency command input. When a Frequency command of RS-485 changes (the frequency command source must be set as Modbus), this parameter also changes.

✔ 09-11 Block Transfer 1
✔ 09-12 Block Transfer 2
✔ 09-13 Block Transfer 3
✔ 09-14 Block Transfer 4
✔ 09-15 Block Transfer 5
✔ 09-16 Block Transfer 6
✔ 09-17 Block Transfer 7
✔ 09-18 Block Transfer 8
✔ 09-19 Block Transfer 9
✔ 09-20 Block Transfer 10
✔ 09-21 Block Transfer 11
✔ 09-22 Block Transfer 12
✔ 09-23 Block Transfer 13
✔ 09-24 Block Transfer 14
✔ 09-25 Block Transfer 15
✔ 09-26 Block Transfer 16

Default: 0000

Settings 0000–FFFFh

🕮 There is a group of block transfer parameters available in the AC motor drive (Pr.09-11–Pr.09-26). Using communication code 03H, you can store the parameters (Pr.09-11–Pr.09-26) that you want to read.

🕮 For example: according to the Address List (as shown in the table below), Pr.01-42 is shown as 012A. Set Pr.09-11 to 012Ah (the minimum voltage of Pr.01-42 M2 is 2.0 V), and use Pr.09-11 (communication address 090B) to read the communication parameter, the read value is 2.0.

AC motor drive parameters	GGnnH	GG is the parameter group, nn is the parameter number; for example, the address of Pr.04-10 is 040AH.

🕮 Mind if the transfer parameters are read only. If the data is written to read-only paraemters from the upper unit, a communication error may occur.

09-30 Communication Decoding Method

Default: 1

Settings 0: Decoding Method 1 (20xx)

1: Decoding Method 2 (60xx)

🕮 The EtherCAT communication card only supports Decoding Method 2 (60xx).

		Decoding Method 1	Decoding Method 2
Source of Operation Control	Digital Keypad	Digital keypad controls the drive action regardless of decoding method 1 or 2.	
	External Terminal	External terminal controls the drive action regardless of decoding method 1 or 2.	
	RS-485	Refer to address: 2000h–20FFh	Refer to address: 6000h–60FFh
	CANopen	Refer to index: 2020-01h–2020-FFh	Refer to index: 2060-01h–2060-FFh
	Communication Card	Refer to address: 2000h–20FFh	Refer to address: 6000h–60FFh
	PLC	PLC commands controls the drive action regardless of decoding method 1 or 2.	

09-31 Internal Communication Protocol

Default: 0

Settings 1: BACnet

0: Modbus 485

-1: Internal Communication Slave 1

-2: Internal Communication Slave 2

-3: Internal Communication Slave 3

-4: Internal Communication Slave 4

-5: Internal Communication Slave 5

-6: Internal Communication Slave 6

-7: Internal Communication Slave 7

-8: Internal Communication Slave 8

-10: Internal Communication Master

-12: Internal PLC Control

🕮 When it is defined as internal communication, refer to Section 16-10 for Main Control Terminal of Internal Communication.

🕮 When it is defined as internal PLC control, refer to Section 16-12 for Remote IO Control Application (using MODRW).

09-33 PLC Command Force to 0

Default: 0000

Setting bit0: Before PLC scans, set the PLC target frequency = 0

📖 Defines whether the Frequency command or the Speed command must be cleared to zero or not before the PLC starts the next scan.

09-35 PLC Address

Default: 2

Settings 1–254

09-36 CANopen Slave Address

Default: 0

Settings 0: Disable
0–127

09-37 CANopen Speed

Default 0

Settings 0: 1 Mbps
1: 500 Kbps
2: 250 Kbps
3: 125 Kbps
4: 100 Kbps (Delta only)
5: 50 Kbps

09-39 CANopen Warning Record

Default: Ready only

Settings bit0: CANopen Guarding Time-out
bit1: CANopen Heartbeat Time-out
bit2: CANopen SYNC Time-out
bit3: CANopen SDO Time-out
bit4: CANopen SDO Buffer Overflow
bit5: CANopen hardware disconnection warning (Can Bus Off)
bit6: Error protocol of CANopen
bit8: The setting values of CANopen indexes are fail
bit9: The setting value of CANopen address is fail
bit10: The checksum value of CANopen indexes is fail

09-40 CANopen Decoding Method

Default: 1

Settings 0: Disable (Delta-defined decoding method)
1: Enable (CANopen DS402 Standard protocol)

09-41 CANopen Communication Status

Default: Read Only

Settings 0: Node Reset State
1: Com Reset State
2: Boot up State

3: Pre-operation State
4: Operation State
5: Stop State

09-42 CANopen Control Status

Default: Read Only

Settings 0: Not ready for use state
1: Inhibit start state
2: Ready to switch on state
3: Switched on state
4: Enable operation state
7: Quick stop active state
13: Error reaction activation state
14: Error state

09-45 CANopen Master Function

Default: 0

Settings 0: Disable
1: Enable

09-46 CANopen Master Address

Default: 100

Settings 0–127

09-49 CANopen Extension Setting

Default: 0002h

Settings bit0: Update Index 604F and 6050 to Acceleration / Deceleration time 1
    bit0 = 0: Enabled (default)
    bit0 = 1: Disabled
bit1: Distinguish the CANopen identity code by models or by series
    bit1 = 0: Distinguish the CANopen identity code by models
    bit1 = 1: Distinguish the CANopen identity code by series

---

🕮 bit0 = 0, the drive directly controls Acceleration time 1 (Pr.01-12) and Deceleration time 1 (Pr.01-13).

🕮 bit1 = 0: each model of different series of drives has its own EDS file, this setting is more complicated to use.
bit1 = 1: distinguish the CANopen identity code by the drive's serie, which requires only one EDS file.

09-50 BACnet MS / TP Node Address

Default: 10

Settings 0–127

09-51 BACnet Baud Rate

Default: 38.4

Settings 9.6–76.8 Kbps

09-52 BACnet Device ID L

Default: 10

Settings 0–65535

09-53 BACnet Device ID H

Default: 0

Settings 0–63

09-55 BACnet Max Address

Default: 127

Settings 0–127

09-56 BACnet Password

Default: 0

Settings 0–65535

09-60 Identifications for Communication Card

Default: Read only

Settings 0: No communication card
1: DeviceNet Slave
2: Profibus-DP Slave
3: CANopen Slave / Master
4: Modbus-TCP Slave
5: EtherNet / IP Slave
8: BACnet IP
12: PROFINET

09-61 Firmware Version of Communication Card

Default: Read only

Settings Read only

09-62 Product Code

Default: Read only

Settings Read only

09-63 Error Code

Default: Read only

Settings Read only

ϟ **09-70** Communication Card Address (for DeviceNet or PROFIBUS)

Default: 1

Settings DeviceNet: 0–63
Profibus-DP: 1–125

⚡ 09-71 Communication Card Speed Setting (for DeviceNet)

Default: 2

Settings Standard DeviceNet:
0: 125 Kbps
1: 250 Kbps
2: 500 Kbps
3: 1 Mbps (Delta only)
Non standard DeviceNet : (Delta only)
0: 10 Kbps
1: 20 Kbps
2: 50 Kbps
3: 100 Kbps
4: 125 Kbps
5: 250 Kbps
6: 500 Kbps
7: 800 Kbps
8: 1 Mbps

⚡ 09-72 Additional Settings for Communication Card Speed (for DeviceNet)

Default: 0

Settings 0: Standard DeviceNet
In this mode, the baud rate can only be 125 Kbps, 250 Kbps, and 500 Kbps in standard DeviceNet speed.
1: Non-standard DeviceNet
In this mode, the DeviceNet baud rate can be same as that for CANopen (0–8).

🕮 Use this parameter with Pr.09-71.

🕮 0: The baud rate can only be set to 125 Kbps, 250 Kbps and 500 Kbps as a standard DeviceNet speed.

🕮 1: The DeviceNet communication rate can be the same as that for CANopen (setting 0–8).

⚡ 09-75 Communication Card IP Configuration (for Modbus TCP)

Default: 0

Settings 0: Static IP
1: DynamicIP (DHCP)

🕮 0: Set the IP address manually.

🕮 1: IP address is dynamically set by the host controller.

⚡ 09-76 Communication Card IP Address 1 (for Modbus TCP)
⚡ 09-77 Communication Card IP Address 2 (for Modbus TCP)
⚡ 09-78 Communication Card IP Address 3 (for Modbus TCP)
⚡ 09-79 Communication Card IP Address 4 (for Modbus TCP)

Default: 0

Settings 0–65535

🕮 Use Pr.09-76–09-79 with a communication card.

⌁ **09-80** Communication Card Address Mask 1 (for Modbus TCP)

⌁ **09-81** Communication Card Address Mask 2 (for Modbus TCP)

⌁ **09-82** Communication Card Address Mask 3 (for Modbus TCP)

⌁ **09-83** Communication Card Address Mask 4 (for Modbus TCP)

Default: 0

Settings 0–65535

⌁ **09-84** Communication Card Gateway Address 1 (for Modbus TCP)

⌁ **09-85** Communication Card Gateway Address 2 (for Modbus TCP)

⌁ **09-86** Communication Card Gateway Address 3 (for Modbus TCP)

⌁ **09-87** Communication Card Gateway Address 4 (for Modbus TCP)

Default: 0

Settings 0–65535

⌁ **09-88** Communication Card Password (Low word) (for Modbus TCP)

⌁ **09-89** Communication Card Password (High word) (for Modbus TCP)

Default: 0

Settings 0–99

⌁ **09-90** Reset Communication Card (for Modbus TCP)

Default: 0

Settings 0: Disable
1: Reset to defaults

⌁ **09-91** Additional Setting for the Communication Card (for Modbus TCP)

Default: 1

Settings bit0: Enable IP Filter
bit1: Enable internet parameters (1bit)

When the IP address is set, this bit is enabled. After updating the parameters for the communication card, this bit changes to disabled.

bit2: Enable login password (1bit)

When you enter the login password, this bit is enabled. After updating the communication card parameters, this bit changes to disable.

09-92 Communication Card Status (for Modbus TCP)

Default: 0

Settings bit0: Enable password

When the communication card is set with a password, this bit is enabled. When the password is cleared, this bit is disabled.

10 Sensorless Motor Control Parameters

✎ You can set this parameter during operation.

✎ **10-08** Treatment for Speed Observer Feedback Fault

Default: 2

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop

✎ **10-09** Detection Time of Speed Observer Feedback Fault

Default: 1.0

Settings 0.0–10.0 sec.
0: Disable

🕮 When speed observer outputs an abnormal signal, or the rotation direction is different with the detected direction from speed observer, and the fault time exceeds the detection time of speed observer feedback fault (Pr.10-09), a reverse direction of the speed feedback (SdRv) fault occurs. Refer to Chapter 14 for solutions.

✎ **10-10** Speed Observer Stall Level

Default: 115

Settings 0–120%
0: Disable

🕮 Determines the fault level of feedback signal. The maximum operation frequency for Pr.01-00 = 100%

✎ **10-11** Detection Time of Speed Observer Stall

Default: 0.1

Settings 0.0–2.0 sec.

✎ **10-12** Speed Observer Stall Action

Default: 2

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop

🕮 When the drive output frequency exceeds the speed observer stall level (Pr.10-10), the drive starts to count the time. When the error time exceeds the speed observer stall detection time (Pr.10-11), an over speed rotation feedback (SdOr) fault occurs. Refer to Chapter 14 for solutions.

✎ **10-13** Speed Observer Slip Range

Default: 50

Settings 0–50%
0: Disable

10-14 Detection Time of Speed Observer Slip

Default: 0.5

Settings 0.0–10.0 sec.

10-15 Speed Observer Stall and Slip Error Action

Default: 2

Settings 0: Warn and continue operation
1: Fault and ramp to stop
2: Fault and coast to stop

📖 When the value of (rotation speed – motor frequency) exceeds the Pr.10-13 setting, and the detection time exceeds Pr.10-14; the drive starts to count the time. If the detection time exceeds Pr.10-14, a large deviation of speed feedback (SdDe) fault occurs. Refer to Chapter 14 for solutions.

10-31 I/F Mode, Current Command

Default: 40

Settings 0–150% rated current of the motor

📖 Sets the current command for the drive in low speed area (low speed area: frequency command < Pr.10-39). When the motor stalls on heavy-duty start-up or forward / reverse with load, increase the parameter value. If the inrush current is too high and causes oc stall, then decrease the parameter value.

📖 When Pr.00-11 is set to 8 (SynRM Sensorless), the maximum setting value for I/F mode Current command is 15%. The application for this parameter extends to high-speed zone and flux-weakening zone.

📖 When Pr.00-11 is set to 8 (SynRM Sensorless) and the drive operates in flux-weakening zone, if the speed is restricted and cannot accelerate, even causes the observer lost control, adjust the setting for Pr.10-31.

10-32 PM FOC Sensorless Speed Estimator Bandwidth

Default: 5.00

Settings 0.00–600.00 Hz

📖 Sets the speed estimator bandwidth. Adjust the parameter to change the stability and the accuracy of the motor speed.

📖 If there is low frequency vibration (the waveform is similar to the sine wave) during the process, then increase the bandwidth. If there is high frequency vibration (the waveform shows extreme vibration and is like a spur), then decrease the bandwidth.

10-33 PM FOC Sensorless Speed Estimator Bandwidth (Low Speed) (applied to 230V/460V models)

Default: 1.00

Settings 0.00–600.00 Hz

📖 Works only when Speed mode is set as IPM sensorless / SRM sensorless (Pr.00-11 = 7 or 8).

📖 Increase this parameter to enhance the loading performance during start-up and low-speed operation.

- When the motor speed during start-up or operation is lower than the frequency to switch from I/F mode to PM sensorless mode (Pr.10-39), and the motor speed oscillates, adjust the setting for this parameter.
- When Pr.05-33 is set to 3 (SynRM), the unit changes to Pu, the setting upper and lower limit for Pr.10-33 change to 3.00–0.01 and the default is 1.0.

✓ 10-34 PM Sensorless Speed Estimator Low-pass Filter Gain

Default: 1.00

Settings 0.00–655.35

- Changes the response speed of the speed estimator.
- If there is low frequency vibration (the waveform is similar to the sine wave) during the process, then increase the gain. If there is high frequency vibration (the waveform shows extreme vibration and is like a spur), then decrease the gain.
- When Pr.05-33 is set to 3 (SynRM), the setting upper limit is 10.00.

✓ 10-35 AMR (Kp) Gain (applied to 230V / 460V models)

Default: 1.00

Settings 0.00–3.00

- When Pr.00-11 is set to 8 (SynRM), the default for this parameter is 0.40.

✓ 10-36 AMR (Ki) Gain (applied to 230V / 460V models)

Default: 0.20

Settings 0.00–3.00

- When Pr.00-11 is set to 8 (SynRM), the default for this parameter is 2.00.
- AMR is the abbreviation for Active Magnetic Regulator (Kp / Ki), it affects the response of magnetic regulation in flux-weakening zone.
- If the input voltage or DC bus plummets in the flux-weakening zone (for example, a sudden insufficient voltage due to unstable power net, or DC bus plummets because of a sudden loading), causes the ACR diverges and oc fault occurs, then increase the gain. If the Id value of a spur generates large noise in high frequency output current, decrease the gain to reduce the noise. But decreasing the gain will slow down the response speed.

✓ 10-39 Frequency to Switch from I/F Mode to PM Sensorless Mode

Default: 20.00

Settings 0.00–599.00 Hz

- The setting upper limit is the same as that for Pr.01-00 (Maximum operation frequency).
- Sets the frequency for switching from low frequency to high frequency, and sets the switch point for high and low frequencies of the speed observer.
- If the switch frequency is too low, the motor does not generate enough back-EMF to let the speed observer measure the right position and speed of the rotor, causing stall and oc when running at the switch frequency.
- If the switch frequency is too high, the active range of I/F is too wide, which generates a larger current without energy saving. (If the current value for Pr.10-31 is too high, the high switch frequency makes the drive continue to output with Pr.10-31 setting value.)
- When Pr.00-11 is set to 8 (SynRM), the default for this parameter is 10.00 Hz.

✓ 10-40 Frequency to Switch from PM Sensorless Mode to I/F Mode

Default: 20.00

Settings 0.00–599.00 Hz

- The setting upper limit is the same as that for Pr.01-00 (Maximum operation frequency).
- Sets the frequency for switching from high frequency to low frequency, and sets the switch point for high and low frequencies of the speed observer.
- If the switch frequency is too low, the motor does not generate enough back-EMF to let the speed observer measure the right position and speed of the rotor when running at the switch frequency.
- If the switch frequency is too high, the active range of I/F is too wide, which generates a larger current without energy saving. (If the current value for Pr.10-31 is too high, the high switch frequency makes the drive continue to output with Pr.10-31 setting value.)

✓ 10-41 I/F Mode, Id Current Low-Pass Filter Time

Default: 0.2

Settings 0.0–6.0 sec.

- Sets the filter time for Pr.10-31. Smoothly increases the magnetic field to the current command setting value under the I/F mode.
- If you want to slowly increase the size of Id, increase the filter time to avoid a Step phenomenon occurs when starting current output. When decrease the filter time (minimum value is 0), the current rises faster, then a Step phenomenon occurs.

✓ 10-42 Initial Angle Detection Pulse Value

Default: 1.0

Settings 0.0–3.0 times rated current of the motor

- The angle detection is fixed to Pr.10-53 = 2 (High frequency injection) or 3 (Pulse injection).
- The parameter influences the value of the pulse during the angle detection. The larger the pulse, the higher the accuracy of rotator's position. A larger pulse might cause oc.
- Increase the parameter when the running direction and the command are opposite during start-up. If oc occurs at start-up, then decrease the parameter.
- Refer to Section 12-2 Adjustment & Application for detailed motor adjustment procedure.

✓ 10-49 Zero Voltage Time during Start-up

Default: 0.000

Settings 0.000–60.000 sec.

- This parameter is valid only when the setting for Pr.07-12 (Speed Tracking during Start-up) = 0.
- When the motor is in static status at start-up, this increases the accuracy when estimating angles. In order to put the motor in static state, set the three-phase drive output to 0 V to the motor. The Pr.10-49 setting time is the length of time when three-phase output at 0 V.
- It is possible that even when you apply this parameter, the motor cannot go into the static state because of inertia or some external force. If the motor does not go into the static state in 0.2 seconds, increase the setting value appropriately.
- If Pr.10-49 is too high, the start-up time is longer. If it is too low, the braking performance is weak.

10-51 Injection Frequency

Default: 500

Settings 0–1200 Hz

📖 This parameter is a high frequency injection command in PM SVC control mode and usually you do not need to adjust it. If a motor's rated frequency (for example, 400 Hz) is too close to the frequency setting for this parameter (that is, the Default of 500 Hz), it affects the accuracy of the angle detection. Refer to the setting for Pr.01-01 before you adjust this parameter.

📖 If the setting value for Pr.00-17 is lower than Pr.10-51 × 10, then increase the frequency of the carrier wave.

📖 Pr.10-51 is valid only when Pr.10-53 = 2.

📖 When Pr.00-11 is set to 8 (SynRM), the default for this parameter is 400.

10-52 Injection Magnitude

Default:
15.0/ 30.0/ 30.0/ 30.0

Settings 0.0–200.0 V
230V models: 0.0–100.0 V
460V models: 0.0–200.0 V
575V models: 0.0–200.0 V
690V models: 0.0–200.0 V

📖 The parameter is the magnitude command for the high frequency injection signal in IPM Sensorless control mode.

📖 Increasing the parameter can increase the accuracy of the angle estimation, but the electromagnetic noise might be louder if the setting value is too high.

📖 The system uses this parameter when the motor's parameter is "Auto". This parameter influences the angle estimation accuracy.

📖 When the ratio of the salient pole (Lq/Ld) is lower, increase Pr.10-52 to make the angle detection more accurate.

📖 Pr.10-52 is valid only when Pr.10-53 = 2.

📖 When Pr.05-33 is set to 3 (SynRM), the unit is percentage (%); the setting upper limit and lower limit is 50–10%, and the default is 30%.

10-53 PM Initial Rotor Position Detection Method

Default: 0

Settings 0: Disable
1: Using I/F current command (Pr.10-31) to attract the rotor to zero degrees
2: High frequency injection
3: Pulse injection

📖 When the Speed mode is set to PMSVC (Pr.00-11 = 2) or PM Sensorless (Pr.00-11 = 6):

- For IPM application, set Pr.10-53 = 2.
- For SPM application, set Pr.10-53 = 3.
- If the above settings cause problems, then set this parameter to 1.

📖 When the Speed mode is set to SynRM Sensorless (Pr.00-11 = 8), you do not need to set this parameter.

✎ 10-54 Magnetic Flux Linkage Estimate Low-speed Gain (applied to 230V / 460Vmodels)

Default: 100

Settings 10–1000%

- This parameter is valid only when the speed mode is set to PM Sensorlss control mode (Pr.00-11 = 6).
- Increase this parameter to enhance the loading capacity during start-up.
- Low-speed zone means motor speed under 1/5 of motor's rated speed; high-speed zone means speed beyond 1/5 of motor's rated speed.

✎ 10-55 Magnetic Flux Linkage Estimate High-speed Gain (applied to 230V / 460V models)

Default: 100

Settings 10–1000%

- This parameter is valid only when the speed mode is set to PM Sensorless (Pr.00-11 = 6) / SynRM Sensorless control modes (Pr.00-11 = 8).
- Increase this parameter to enhance the loading performance in high-speed zone and improve the response.
- Decrease this parameter when there is a speed oscillation in the flux-weakening zone.
- When Pr.05-33 is set to 3 (SynRM), the unit is Pu; the setting upper and lower limits are 3.0–0.1 and the default is 1.0.

✎ 10-56 Kp of Phase-locked Loop (applied to 230V / 460V models)

Default: 100

Settings 10–1000%

- Increase this parameter to enhance the loading performance in high-speed zone and improve the response.
- Decrease this parameter when there is a high frequency vibration in the speed output frequency.
- When Pr.05-33 is set to 3 (SynRM), the unit is Hz; the setting upper and lower limits are 50–5 and the default is 30.

✎ 10-57 Ki of Phase-locked Loop (applied to 230V / 460V models)

Default: 100

Settings 10–1000%

- Increase this parameter to increase the speed response during acceleration and deceleration.

✎ 10-58 Mutual Inductance Gain Compensation (applied to 230V / 460V models)

Default: 100

Settings 0.00–655.35

- This parameter is valid only when the speed mode is set to SynRM sensorlss control mode (Pr.00-11 = 8).
- If the motor's loading performance during start-up is poor or the speed is lower than the frequency switch from I/F mode to PM sensorless mode (Pr.10-39), adjust this parameter to improve the loading performance.

11 Advanced Parameters (applied to 230V / 460V models)

✓ You can set this parameter during operation.

In this parameter group, ASR stands for Adjust Speed Regulator

11-00 System Control

Default: 0000h

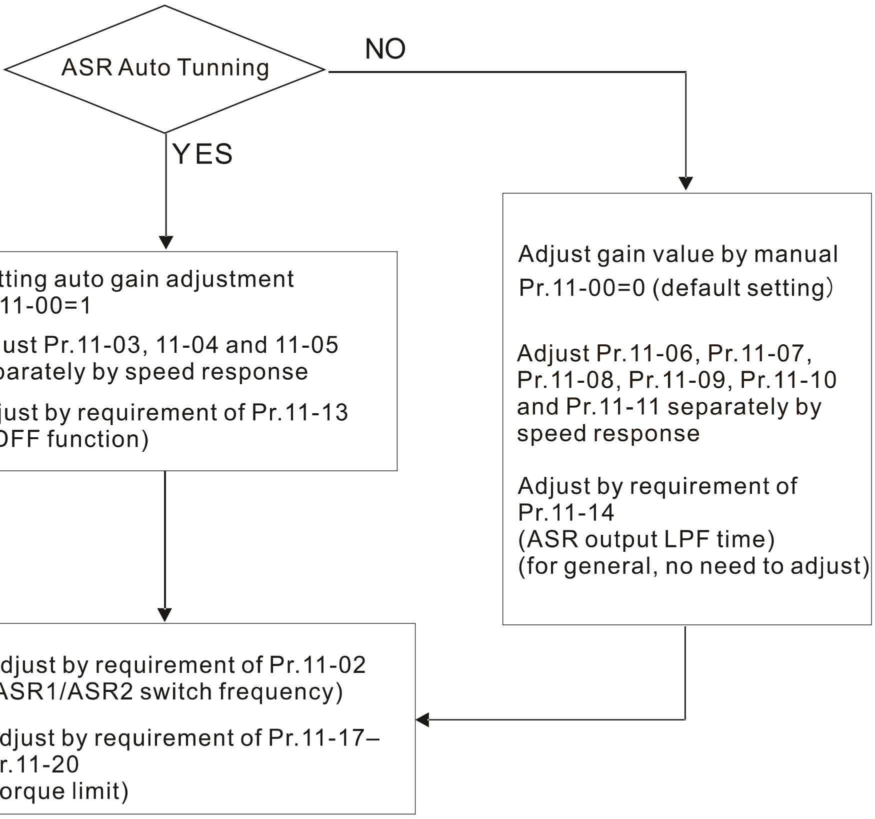
Settings bit0: Auto-tuning for ASR and APR

bit6: 0 Hz linear-cross

bit7: Save or do not save the frequency

- bit0 = 0: Manual adjustment for ASR and APR gain, Pr.11-06–Pr.11-11 are valid and Pr.11-03–Pr.11-05 are invalid.

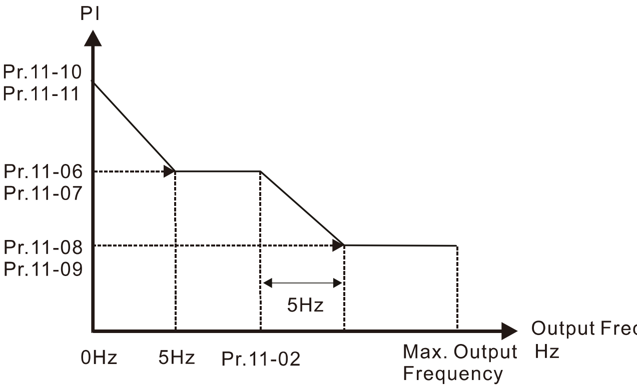
  bit0 = 1: Auto-adjustment for ASR and APR gain, the system automatically generates an ASR setting, Pr.11-06–Pr.11-11 are invalid and Pr.11-03–Pr.11-05 are valid.


ASR Auto Tunning
NO
YES
Setting auto gain adjustment Pr.11-00=1
Adjust Pr.11-03, 11-04 and 11-05 separately by speed response
Adjust by requirement of Pr.11-13 (PDFF function)
Adjust gain value by manual Pr.11-00=0 (default setting)
Adjust Pr.11-06, Pr.11-07, Pr.11-08, Pr.11-09, Pr.11-10 and Pr.11-11 separately by speed response
Adjust by requirement of Pr.11-14 (ASR output LPF time) (for general, no need to adjust)
Adjust by requirement of Pr.11-02 (ASR1/ASR2 switch frequency)
Adjust by requirement of Pr.11-17–Pr.11-20 (torque limit)

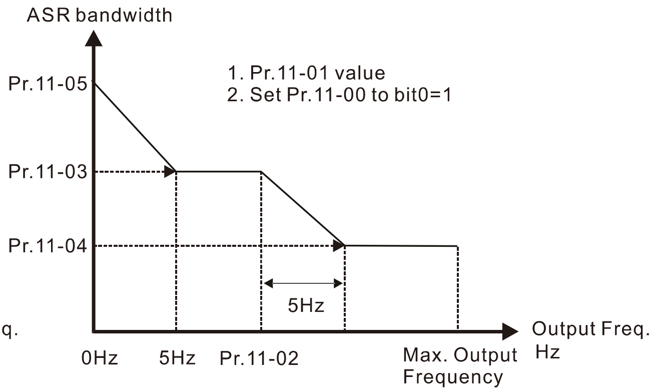
- When the drive needs to keep a certain torque at zero-speed, or it needs a steady frequency output at extreme low speed, increase Pr.11-05 zero-speed bandwidth appropriately. If there is serious output current vibration that cause the drive vibrates in high-speed area, then decrease the high-speed bandwidth.

  For example:

Manual gain	Response: [Pr.11-10, Pr.11-11] > [Pr.11-06, Pr.11-07] > [Pr.11-08, Pr.11-09]
Auto gain	Pr.11-05 = 15 Hz, Pr.11-03 = 10 Hz, Pr.11-04 = 8 Hz



ASR adjustment- manual gain

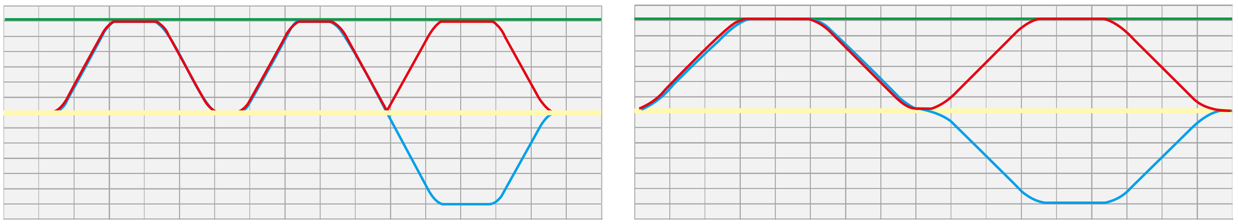


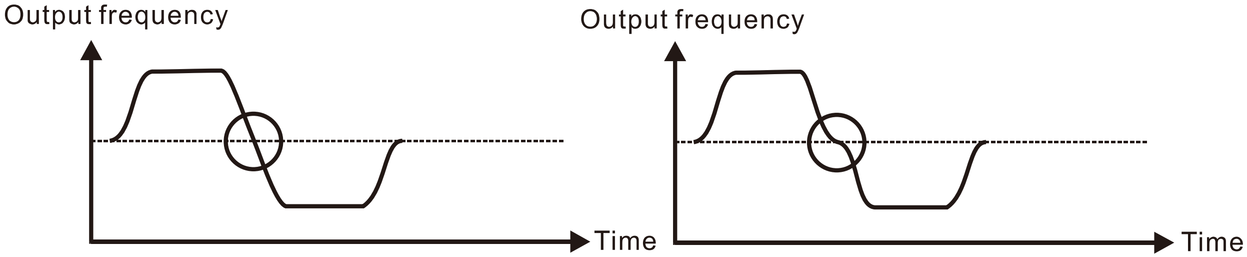
ASR adjustment- auto gain

- bit6 0 Hz linear-cross function: keeps the S-Curve in linear-cross the 0 Hz point when the S-curves for acceleration / deceleration time (Pr.01-24–Pr.01-27) are set, and the forward / reverse run cross 0 Hz.

  bit6 = 1: The S-curves for acceleration / deceleration time (Pr.01-24–Pr.01-27) do NOT affect the drive starts and stops. Forward / reverse rotation crosses the zero point in linear.

  bit6 = 0: The S-curves for acceleration / deceleration time (Pr.01-24–Pr.01-27) affect the drive starts and stops. Forward / reverse rotation crosses the zero point after the S-Curve.





Pr.11-00 bit6 = 1

Pr.11-00 bit6 = 0

- bit 7 = 0: Save the frequency before power is OFF. The keypad displays the saved frequency after cycle the power.

  bit7 = 1: Do not save the frequency before power is OFF. The keypad displays 0.00 Hz after cycle the power.

11-01 Per Unit of System Inertia

Default: 256

Settings 1–65535 (256 = 1PU)

- When Pr.11-01 = 256, it is 1PU. So if you use a 2 HP motor, the 2 HP motor inertia is 6.6 kg-cm^2 according to the rotor inertia table in Pr.05-38. If Pr.11-01 = 10000 after tuning, the system inertia is (10000 / 256) x 6.6 kg-cm^2.

- If the Iq current command from ASR has high-frequency glitch, then decrease the setting. If the response time of sudden loading is too slow, then increase the setting.

✎ **11-02** ASR1 / ASR2 Switch Frequency

Default: 7.00

Settings 5.00–599.00 Hz

- Sets the low-speed and high-speed ASR switching point in the FOC area. Provides flexibility to meet two needs: in the high-speed region of the estimator switch point it has a high response, and in the low-speed region of the estimator switch point it has a lower response. The recommended switching point is higher than Pr.10-39.
- A low setting does not cover Pr.10-39. If the setting is too high, the high-speed range is too narrow.
- When Pr.00-11 is set to 8 (SynRM), the default for this parameter is 10.00 Hz.

✎ **11-03** ASR1 Low-speed Bandwidth

Default: 10

Settings 1–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)

✎ **11-04** ASR2 High-speed Bandwidth

Default: 10

Settings 1–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)

✎ **11-05** Zero-speed Bandwidth

Default: 10

Settings 1–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)

- After estimating inertia and setting Pr.11-00 bit0 = 1 (auto-tuning), you can adjust Pr.11-03, Pr.11-04 and Pr.11-05 separately by speed response. The larger the setting value, the faster the response. Pr.11-02 is the switch frequency between the low-speed / high-speed bandwidth.
- When Pr.00-11 = 8 (SynRM), the setting upper limit is 30, and the default is 5.

✎ **11-06** ASR 1 Gain

Default: 10

Settings 0–40 Hz (IM) / 1–100 Hz (PM) / 1–30 Hz (SynRM)

✎ **11-07** ASR 1 Integral Time

Default: 0.100

Settings 0.000–10.000 sec.

✎ **11-08** ASR 2 Gain

Default: 10

Settings 0–40 Hz (IM) / 0–100 Hz (PM) / 1–30 Hz (SynRM)

✎ **11-09** ASR 2 Integral Time

Default: 0.100

Settings 0.000–10.000 sec.

✎ **11-10** ASR Gain of Zero Speed

Default: 10

Settings 0–40 Hz (IM) / 0–100 Hz (PM) / 1–30 Hz (SynRM)

✎ 11-11 ASR Integral Time of Zero Speed

Default: 0.100

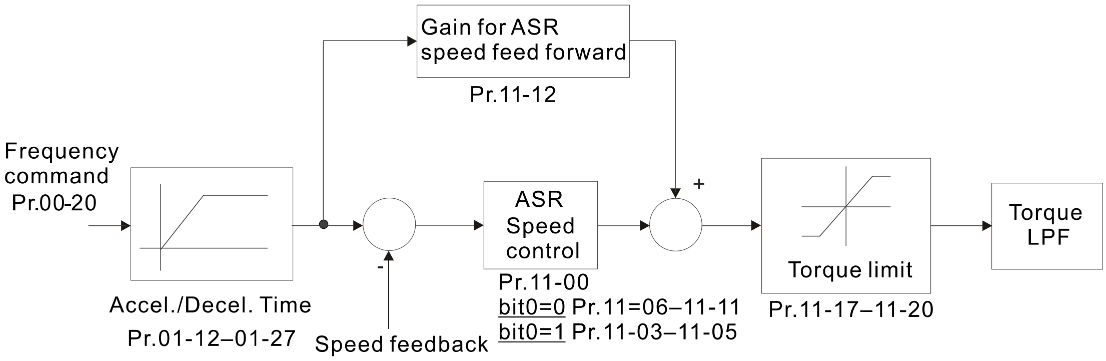
Settings 0.000–10.000 sec.

✎ 11-12 ASR Speed Feed Forward Gain

Default: 0

Settings 0–150%

- This function enables when Pr.11-00 bit0 = 1.
- Increase the setting for Pr.11-12 to reduce the command tracking difference, and improve the speed response. Use this function for speed tracking applications.
- Set Pr.11-01 correctly to get excellent improvement of the speed response.

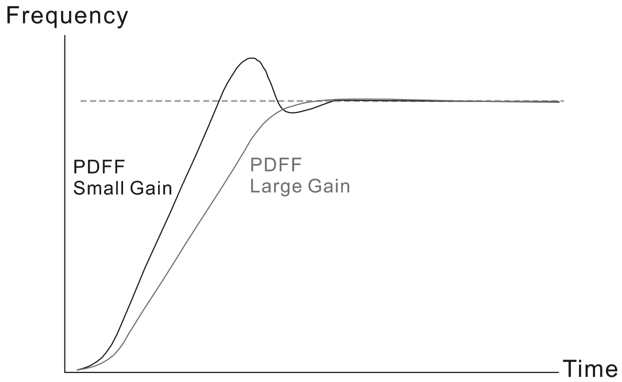


✎ 11-13 PDFF Gain Value

Default: 30

Settings 0–200%

- This parameter is invalid when Pr.05-24 = 1.
- This parameter is valid only when Pr.11-00 bit0 = 1.
- After you estimate and set Pr.11-00 bit0 = 1 (auto-tuning), use Pr.11-13 to reduce overshoot. However, a shift of the curve may occur earlier. In this case, you can set Pr.11-13 = 0 first, and then increase the setting value to "a condition with best acceleration and without overshoot" when the acceleration time meets your application but overshoot occurs.
- Increasing Pr.11-13 improves the overshoot of speed tracking, but an excessive value may reduce the transient response.
- Increasing Pr.11-13 enhances the system stiffness in high-speed steady state, and reduce the speed transient fluctuation at a sudden loading.
- Ensure that you set Pr.11-01 system inertia correctly to get excellent improvement of the speed response.



✎ **11-14** ASR Output Low Pass Filter Time

Default: 0.008

Settings 0.000–0.350 sec.

- Sets the ASR command filter time.

✎ **11-15** Notch Filter Depth

Default: 0

Settings 0–100 dB

✎ **11-16** Notch Filter Frequency

Default: 0.00

Settings 0.0–6000.0 Hz

- A notch filter is a filter that attenuates a signal in a specific frequency band.
- The notch filter also slows down the response speed in the frequency band to avoid mechanical resonance.
- The higher the setting value for Pr.11-15, the better the mechanical resonance is suppressed.
- The notch filter frequency should be equal to the mechanical frequency resonance.
- The notch filter bandwidth is the frequency range in which the notch filter is active.

✎ **11-17** Forward Motor Torque Limit Quadrant I

✎ **11-18** Forward Regenerative Torque Limit Quadrant II

✎ **11-19** Reverse Motor Torque Limit Quadrant III

✎ **11-20** Reverse Regenerative Torque Limit Quadrant IV

Default: 500

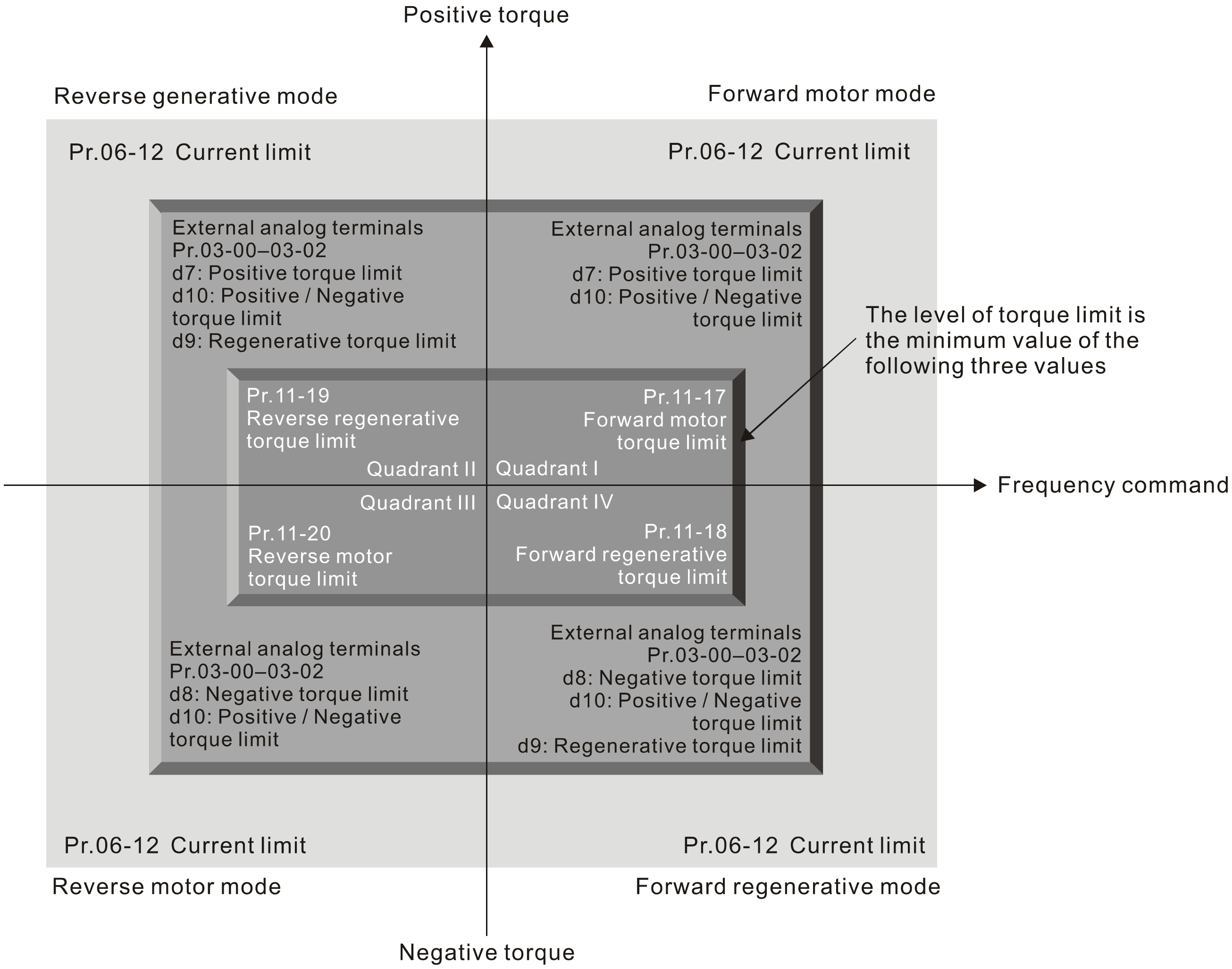
Settings 0–500%

- VF and SVC mode:

  Pr.11-17–Pr.11-20 limit the output current, the percentage base value is the drive’s rated current (not the motor’s rated current). The minimum value between Pr.11-17–11-20 and Pr.06-12 becomes the current output limit. In acceleration and steady state operation, when the output current reaches the limit, the ocA (over-current during acceleration) protection or over-current stall prevention under steady-state operation acts. The output frequency drops, and recovers when the output current is lower than the limit value.
- Calculation equation for the motor rated torque:

  Motor rated torque = $T(N.M)=\dfrac{P(W)}{\omega(rad/s)}$; P(W) value = Pr.05-02 (Pr.05-14);

  ω(rad/s) value = Pr.05-03 (Pr.05-15); $\dfrac{RPM\times 2\pi}{60}=rad/s$


Positive torque
Reverse generative mode
Forward motor mode
Pr.06-12 Current limit
Pr.06-12 Current limit
External analog terminals
Pr.03-00–03-02
d7: Positive torque limit
d10: Positive / Negative torque limit
d9: Regenerative torque limit
External analog terminals
Pr.03-00–03-02
d7: Positive torque limit
d10: Positive / Negative torque limit
The level of torque limit is the minimum value of the following three values
Pr.11-19
Reverse regenerative torque limit
Pr.11-17
Forward motor torque limit
Quadrant II
Quadrant I
Frequency command
Quadrant III
Quadrant IV
Pr.11-20
Reverse motor torque limit
Pr.11-18
Forward regenerative torque limit
External analog terminals
Pr.03-00–03-02
d8: Negative torque limit
d10: Positive / Negative torque limit
External analog terminals
Pr.03-00–03-02
d8: Negative torque limit
d10: Positive / Negative torque limit
d9: Regenerative torque limit
Pr.06-12 Current limit
Pr.06-12 Current limit
Reverse motor mode
Forward regenerative mode
Negative torque

📖 All control mode is based on 100% of the motor rated current except for these four modes: IM: VF, SVC and PM: PMSVC modes.

📖 When Pr.00-11 = 8 (SynRM), the default for Pr.11-17–Pr.11-20 is 200.

✎ **11-21** Flux Weakening Curve for Motor 1 Gain Value

Default: 90

Settings 0–200%

✎ **11-22** Flux Weakening Curve for Motor 2 Gain Value

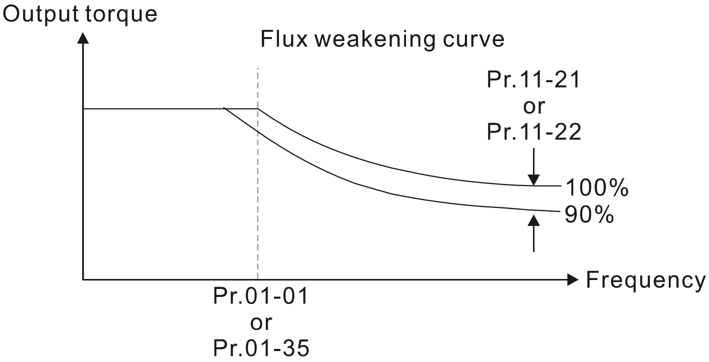
Default: 90

Settings 0–200%

📖 Adjusts the output voltage for the flux-weakening curve.

📖 For the spindle application, use this adjustment method:

1. Run the motor to the highest frequency.
2. Observe the output voltage.
3. Adjust the Pr.11-21 (motor 1) or Pr.11-22 (motor 2) setting to make the output voltage reach the motor rated voltage.
4. The larger the setting value, the greater the output voltage.



✎ 11-23 Flux Weakening Area Speed Response

Default: 65

Settings 0: Disable

0–150%

📖 Controls the speed in the flux weakening area. The larger the value, the faster the acceleration/ deceleration. In normal condition, you do not need to adjust this parameter.

12 Pump Parameters

✓ You can set this parameter during operation.

12-00 Circulation Control

Default: 0

Settings 0: No operation

1: Fixed Time Circulation (by time)

2: Fixed Quantity Circulation

3: Fixed Quantity Control

4: Fixed Time Circulation + Fixed Quantity Circulation

5: Fixed Time Circulation + Fixed Quantity Control

📖 In this mode, the CP2000 can control up to eight motors at a time. The total number of motors is determined by Pr.12-01. In accordance with the Fixed Time Circulation (Pr.12-02), you can adjust the switching time between Start and Stop for each motor. When an operating motor reaches the time setting for Pr.12-02, the CP2000 stops that motor according to the setting for Pr.00-22 (Stop method). After the delay time setting for Pr.12-03, next motor starts operating. See diagram below.

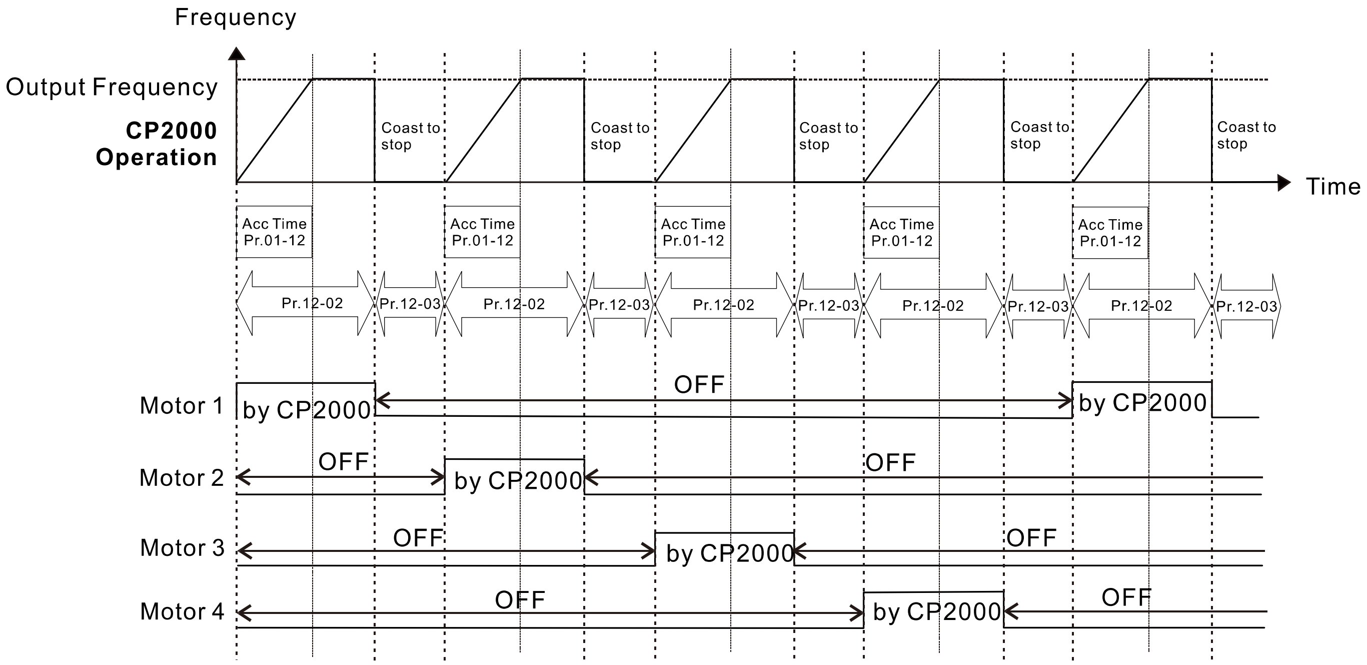


Diagram 12-1: Sequential Diagram of Fixed Time Free Runs Circulation (by time)

📖 Disable Motors' Output

Setting the multi-function input commands as Disable Motors' Output can stop the corresponding motors. The following table lists the settings:

Pr.02-01–Pr.02-06 =	60	61	62	63	64	65	66	67	68
Disable Motors' Output	ALL	1	2	3	4	5	6	7	8

When a motor's output is disabled, this motor coasts to stop.

📖 Wiring: Fixed Time Circulation (by time) can control up to eight motors. Diagram 12-2 shows an example of controlling four motors at the same time.

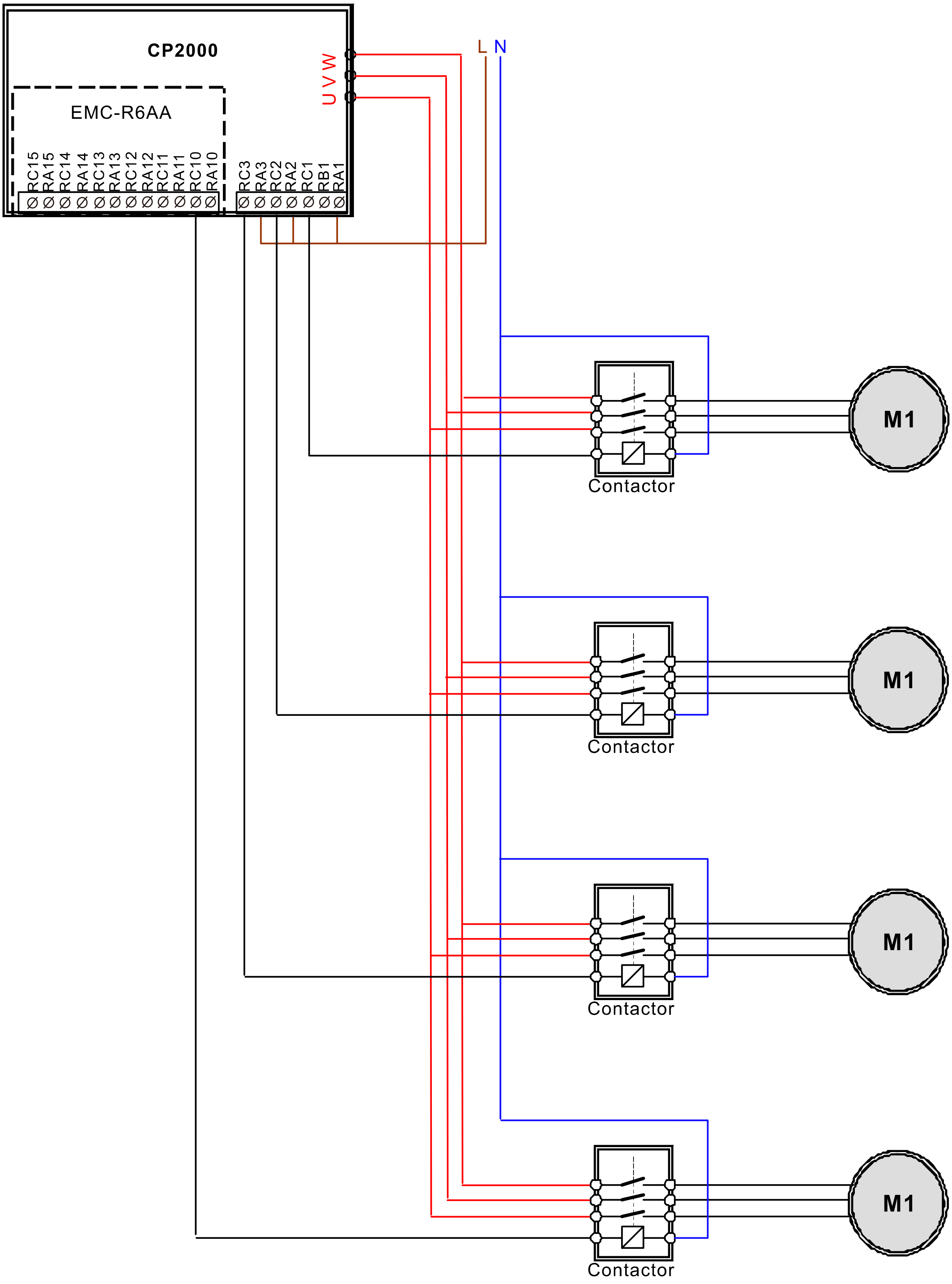


Diagram 12-2: Wiring

12-01 Number of Motors to be Connected

Default: 1

Settings 1–8

📖 Number of Motors: maximum of eight motors. After setting the number of connected motors, the multi-function output terminals automatically follow the setting as shown in the table below.

Pr.12-01	01	02	03	04	05	06	07	08
Pr.02-13	55	55	55	55	55	55	55	55
Pr.02-14		56	56	56	56	56	56	56
Pr.02-15			57	57	57	57	57	57
Pr.02-36				58	58	58	58	58
Pr.02-37					59	59	59	59
Pr.02-38						60	60	60
Pr.02-39							61	61
Pr.02-40								62

Table 1: Setting of Multi-function Output Terminal for Circulating Motors

12-02 Operating Time of Each Motor (minutes)

Default: 0

Settings 0–65500 minutes

📖 Sets the fixed time for circulation. If Pr.12-02 = 0, stop the timing. The currently running motors continue operating until a Stop command is given.

12-03 Delay Time due to the Acceleration (or the Increment) at Motor Switching (seconds)

Default: 1.0

Settings 0.0–3600.0 seconds

📖 Sets the delay time when switching motors. When the currently running motors reach the time setting for Pr.12-02, the CP2000 uses the delay time setting for Pr.12-03 and then switches to run the next motors.

12-04 Delay Time due to the Deceleration (or the Decrement) at Motor Switching (seconds)

Default: 1.0

Settings 0.0–3600.0 seconds

📖 Sets the delay time of motor switching during the deceleration, the unit is second.

↯ 12-05 Delay time due to Fixed Quantity Circulation at Motor Switching (seconds)

Default: 10.0

Settings 0.0–3600.0 seconds

📖 Sets the fixed quantity circulation with PID

Sequential Diagram

In this mode, the CP2000 can control up to four motors to increase flow quantity and pressure range control. When controlling the flow quantity, the motors are in parallel connection. When controlling the pressure range, the motors are in series connection.

To increase the flow quantity or pressure range, the CP2000 increases the first motor's pressure from 0 Hz to the largest operating frequency. If the output frequency reaches the frequency setting for Pr.12-06 and delay time for Pr.12-05, the CP2000 delays the time setting for Pr.12-03. CP2000 then switches to the next motor to use mains electricity and delays the time setting for Pr.12-03 to run the next motor. If necessary, other motors are activated in sequence. See sequential diagram of 12-3 and 12-4.

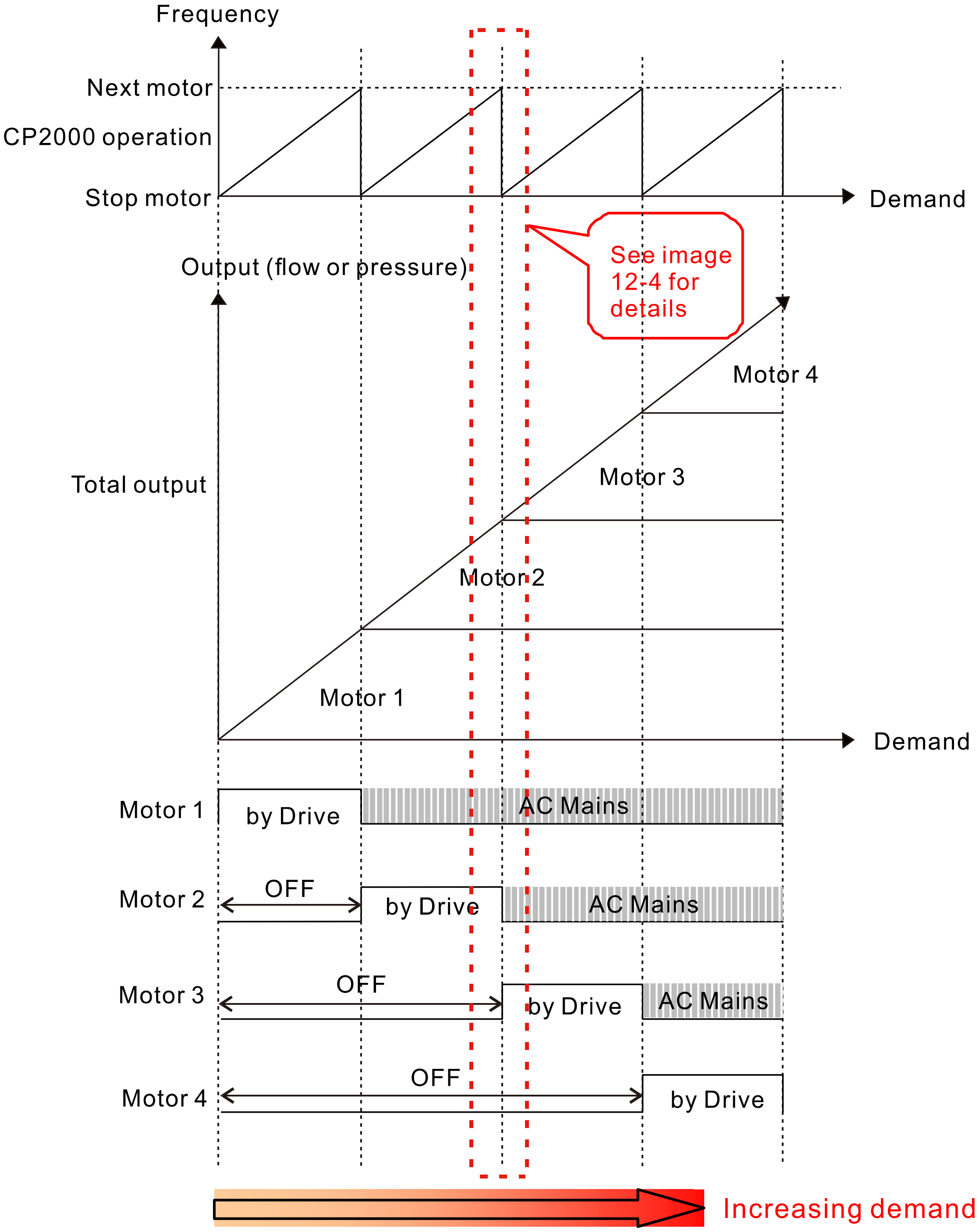


Diagram 12-3: Sequence of Fixed quantity circulation with PID – Increasing Demand

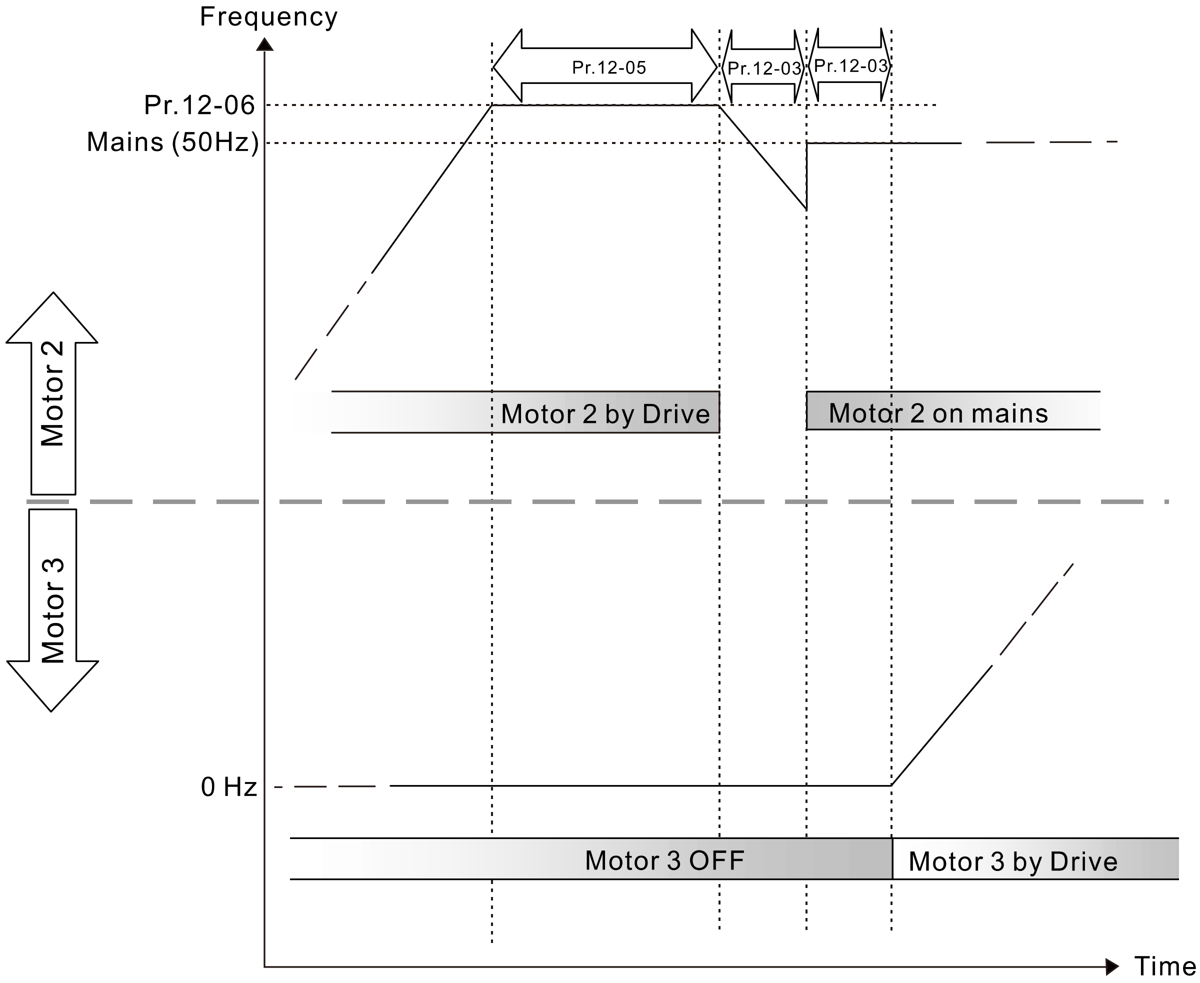


Diagram 12-4: Sequence of switching motors at Fixed Quantity Circulation with PID – Increasing Demands

However, if the decreasing demands for flow quantity and pressure are too big, the CP2000 stops the current operating motors and waits for the delay time setting for Pr.12-04. It continues doing this until the last motor stops using mains electricity. See sequential diagram 12-5 and 12-6 below.

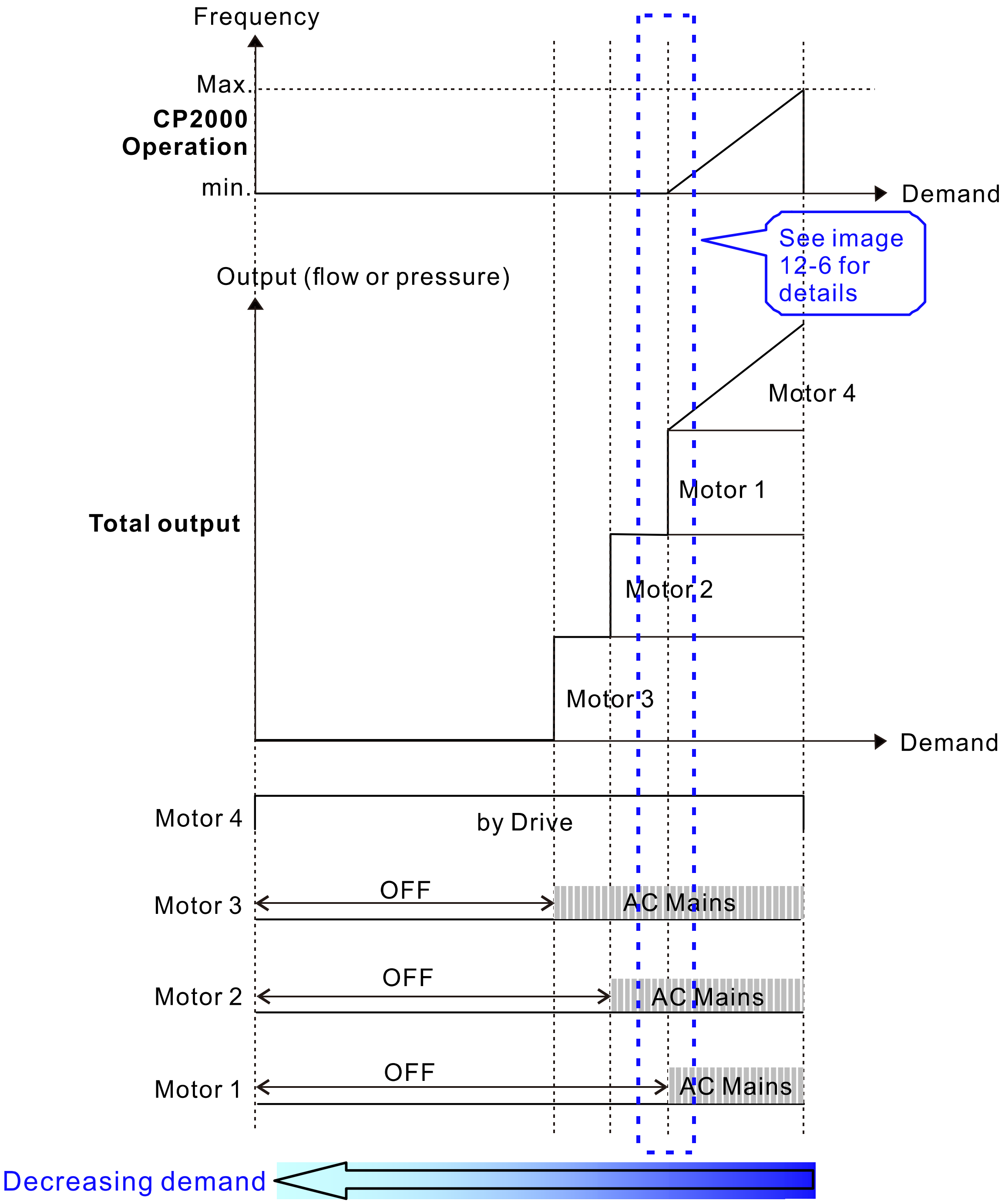


Diagram 12-5: Sequence of Fixed Quantity Circulation with PID – Decreasing Demands

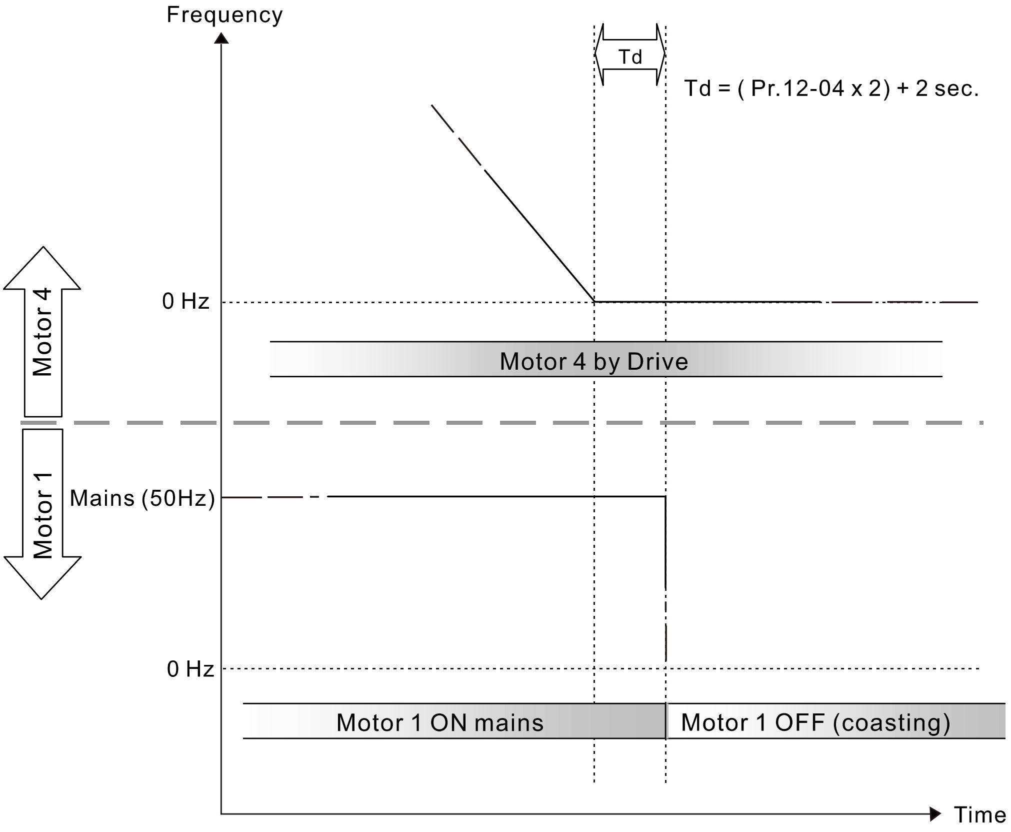


Diagram 12-6: Sequence of switching motors at Fixed Quantity Circulation with PID – Decreasing Demands

📖 Parameter Setting

<table>
<tr><th>Parameter setting</th><th>Description</th></tr>
<tr><td>Pr.12-00=2</td><td>Choose Fixed Quantity Circulation with PID</td></tr>
<tr><td>Pr.12-01=X</td><td>Number of Motors: maximum four motors. After you set the number of motors to be connected at the same time, the multi-function output terminals automatically follow the setting as shown in the table below.
<table>
<tr><td>Pr.12-01</td><td>01</td><td>01</td><td>02</td><td>02</td><td>03</td><td>03</td><td>04</td><td>04</td><td></td></tr>
<tr><td>Pr.02-13</td><td>55</td><td>55</td><td>55</td><td>55</td><td>55</td><td>55</td><td>55</td><td>55</td><td>Motor 1 by Drive</td></tr>
<tr><td>Pr.02-14</td><td></td><td>56</td><td>56</td><td>56</td><td>56</td><td>56</td><td>56</td><td>56</td><td>Motor 1 by Mains</td></tr>
<tr><td>Pr.02-15</td><td></td><td></td><td>57</td><td>57</td><td>57</td><td>57</td><td>57</td><td>57</td><td>Motor 2 by Drive</td></tr>
<tr><td>Pr.02-36</td><td></td><td></td><td></td><td>58</td><td>58</td><td>58</td><td>58</td><td>58</td><td>Motor 2 by Mains</td></tr>
<tr><td>Pr.02-37</td><td></td><td></td><td></td><td></td><td>59</td><td>59</td><td>59</td><td>59</td><td>Motor 3 by Drive</td></tr>
<tr><td>Pr.02-38</td><td></td><td></td><td></td><td></td><td></td><td>60</td><td>60</td><td>60</td><td>Motor 3 by Mains</td></tr>
<tr><td>Pr.02-39</td><td></td><td></td><td></td><td></td><td></td><td></td><td>61</td><td>61</td><td>Motor 4 by Drive</td></tr>
<tr><td>Pr.02-40</td><td></td><td></td><td></td><td></td><td></td><td></td><td></td><td>62</td><td>Motor 4 by Mains</td></tr>
</table>
Table 2: Setting of Multi-function Output Terminal on Circulating Motors</td></tr>
<tr><td>Pr.12-03 = X</td><td>Delay Time due to the Acceleration (or the Increment) at Motor Switching (unit: sec.)</td></tr>
<tr><td>Pr.12-04 = X</td><td>Delay Time due to the Deceleration (or the Decrement) at Motor Switching (unit: sec.)</td></tr>
<tr><td>Pr.12-05 = X</td><td>Delay time while Fixed Quantity Circulation at Motor Switching with PID (unit: sec.)</td></tr>
<tr><td>Pr.12-06 = X</td><td>Frequency when switching motors at Fixed Quantity Circulation (Hz)</td></tr>
<tr><td>Pr.12-09 = X</td><td>Delay time for the next motor output when the demand increases.</td></tr>
</table>

Disable Motor Output

Set the multi-function input commands to Disable Motors' Output can stop corresponding motors. The settings are:

Pr.02-01–Pr.02-06=	60	61	62	63	64	65	66	67	68
Disable Motor's Output	ALL	1	2	3	4	5	6	7	8

When a motor's output is disabled, this motor coasts to stop.

Fixed Quantity Circulation with PID can control up to four motors. Diagram 12-7 below shows an example of controlling 4 motors.

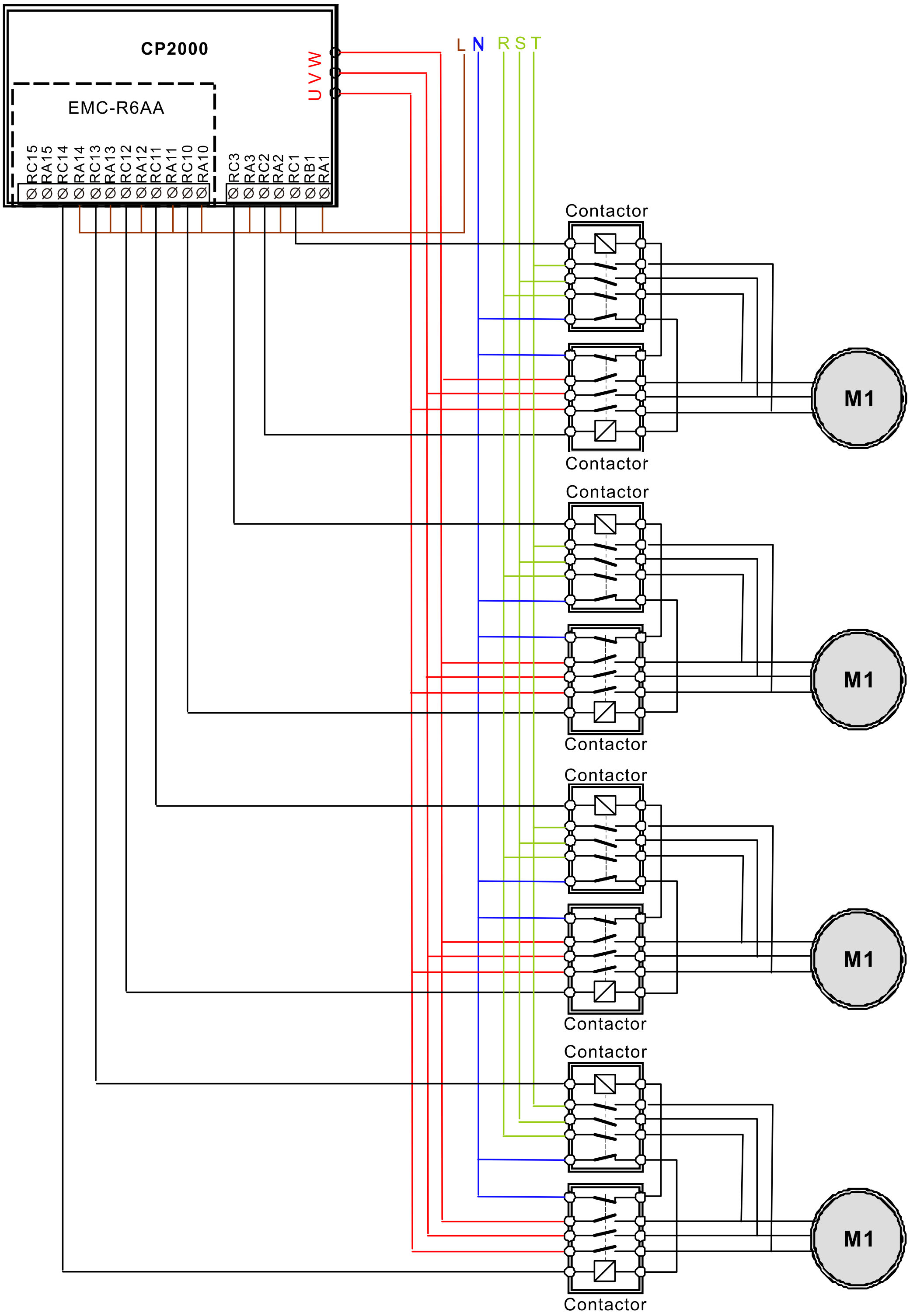


Diagram 12-7

12-06 Frequency when Switching Motors at Fixed Quantity Circulation (Hz)

Default: 60.00

Settings 0.0–599.00 Hz

- Sets the drive's output frequency at which the system prepares to switch motors.

12-07 Action when Fixed Quantity Circulation Breaks Down

Default: 0

Settings 0: Turn off all output
1: Motors powered by mains electricity continues to operate

12-08 Frequency for Stopping Auxiliary Motor (Hz)

Default: 0

Settings 0.00–599.00 Hz

- When the output frequency is smaller than the Pr.12-08 and remains at the time setting for Pr.12-04, the CP2000 shuts down the motors one by one.
- Fixed Quantity Control with PID

  In this mode, the CP2000 can control up to eight motors to increase flow quantity and pressure range control.

  The CP2000 connects directly to a main motor while the rest of the motors use mains electricity and are controlled by a relay. When controlling flow quantity, the motors are in parallel connection. When controlling pressure range, the motors are in series connection.

  To increase the flow quantity or pressure range, the CP2000 increases the main motor's pressure from 0 Hz to the largest operating frequency. If necessary, the CP2000 switches the motors to use mains electricity in sequence. See sequential diagram 12-8 and 12-9.

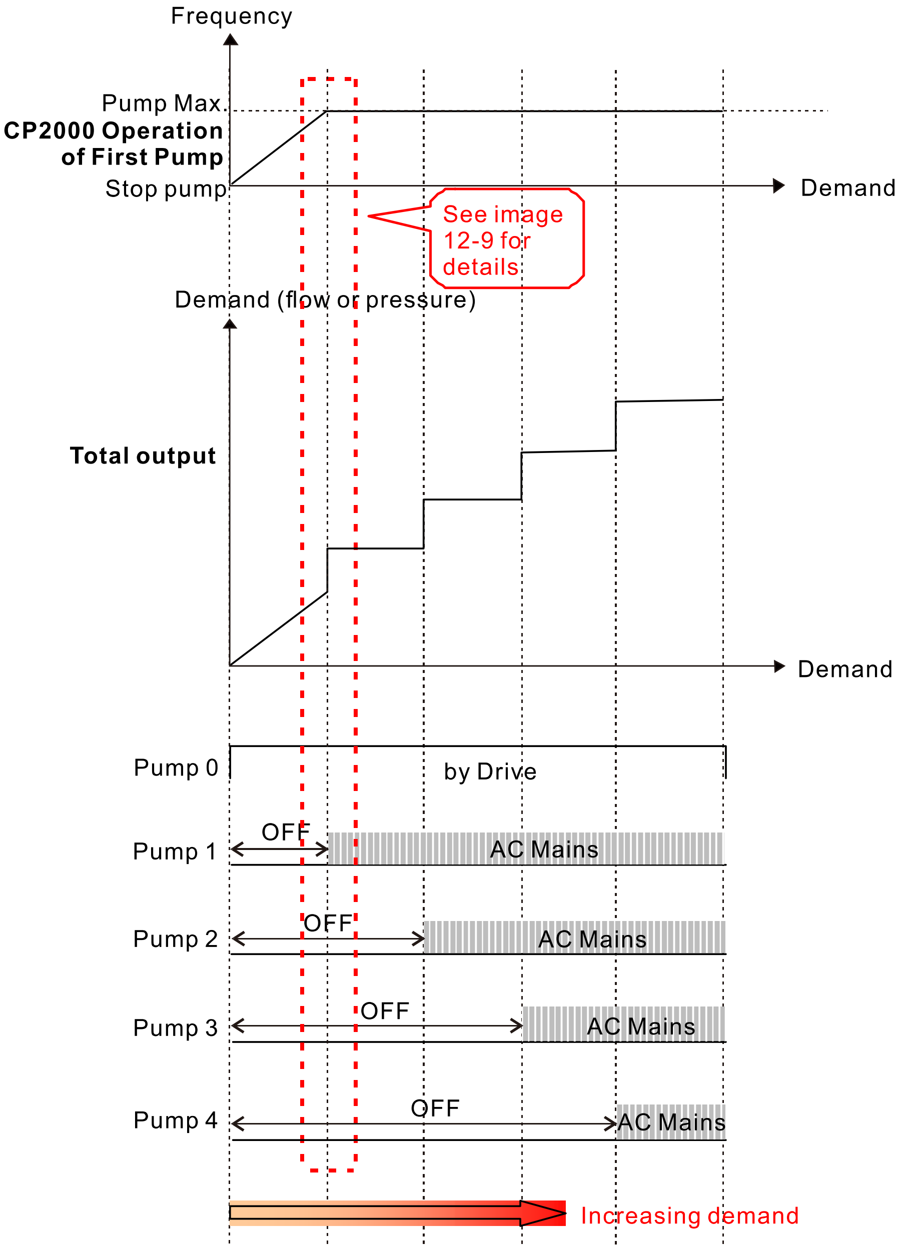


Diagram 12-8: Sequence of Fixed Quantity Control with PID – Increasing Demand

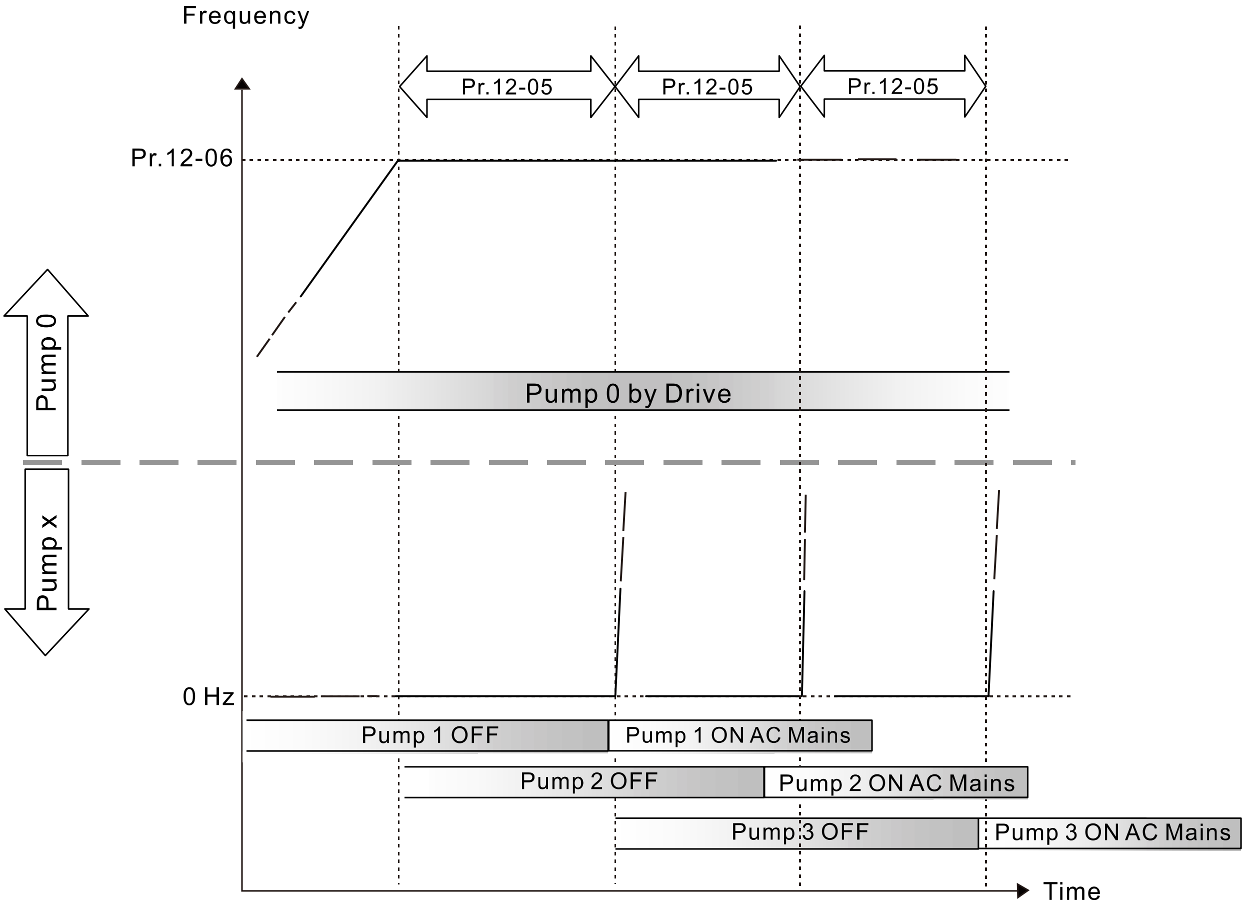


Diagram 12-9: Sequence of switching motors at Fixed Quantity Control with PID – Increasing Demand

However, if the flow quantity or pressure is too large, the CP2000 stops, one by one, the motors use mains electricity until the CP2000 decreases the main motor's frequency to 0 Hz. See Diagram 12-10 and Diagram 12-11.

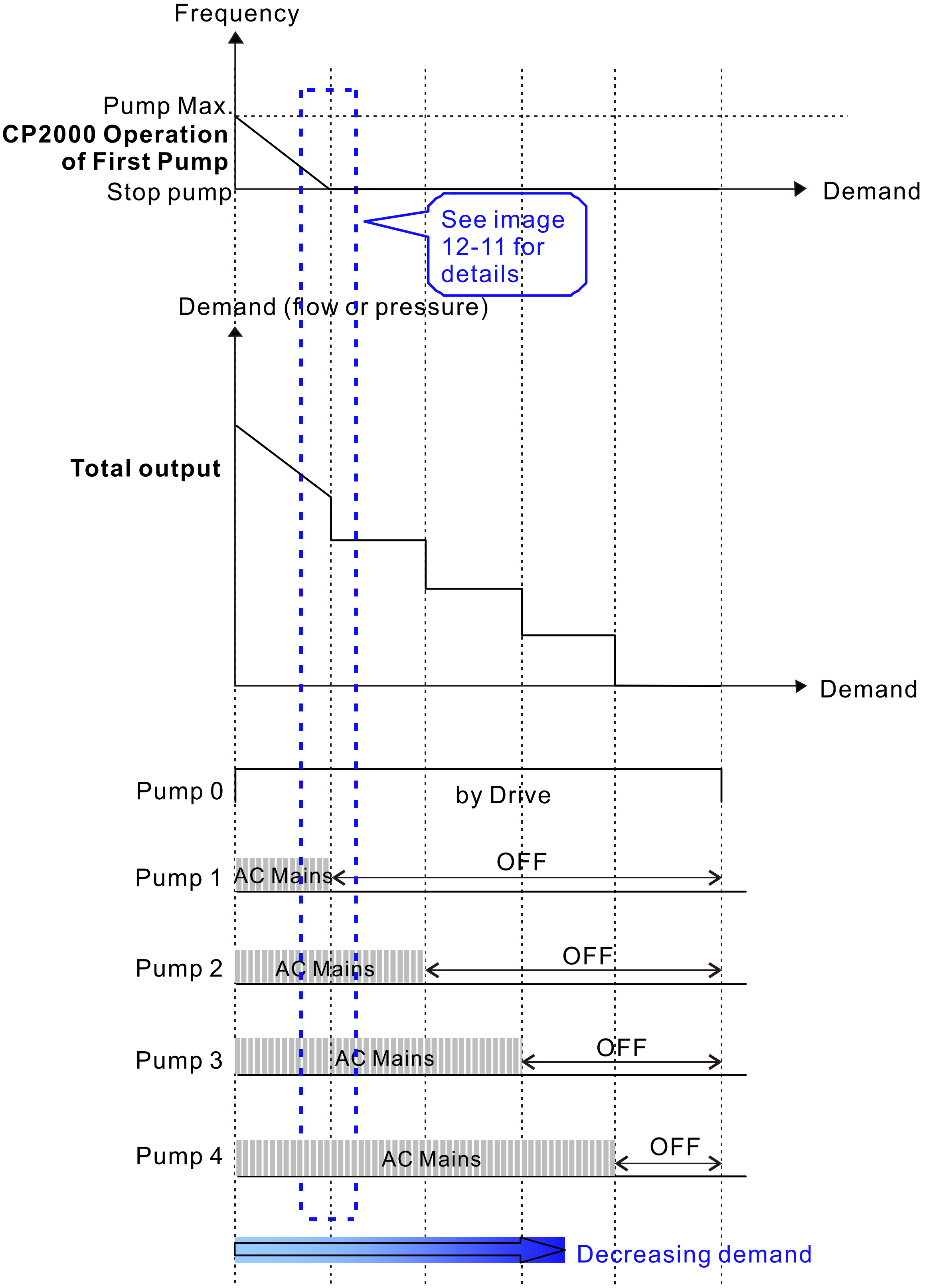


Diagram 12-10: Sequence of Fixed Quantity Control with PID – Decreasing Demand

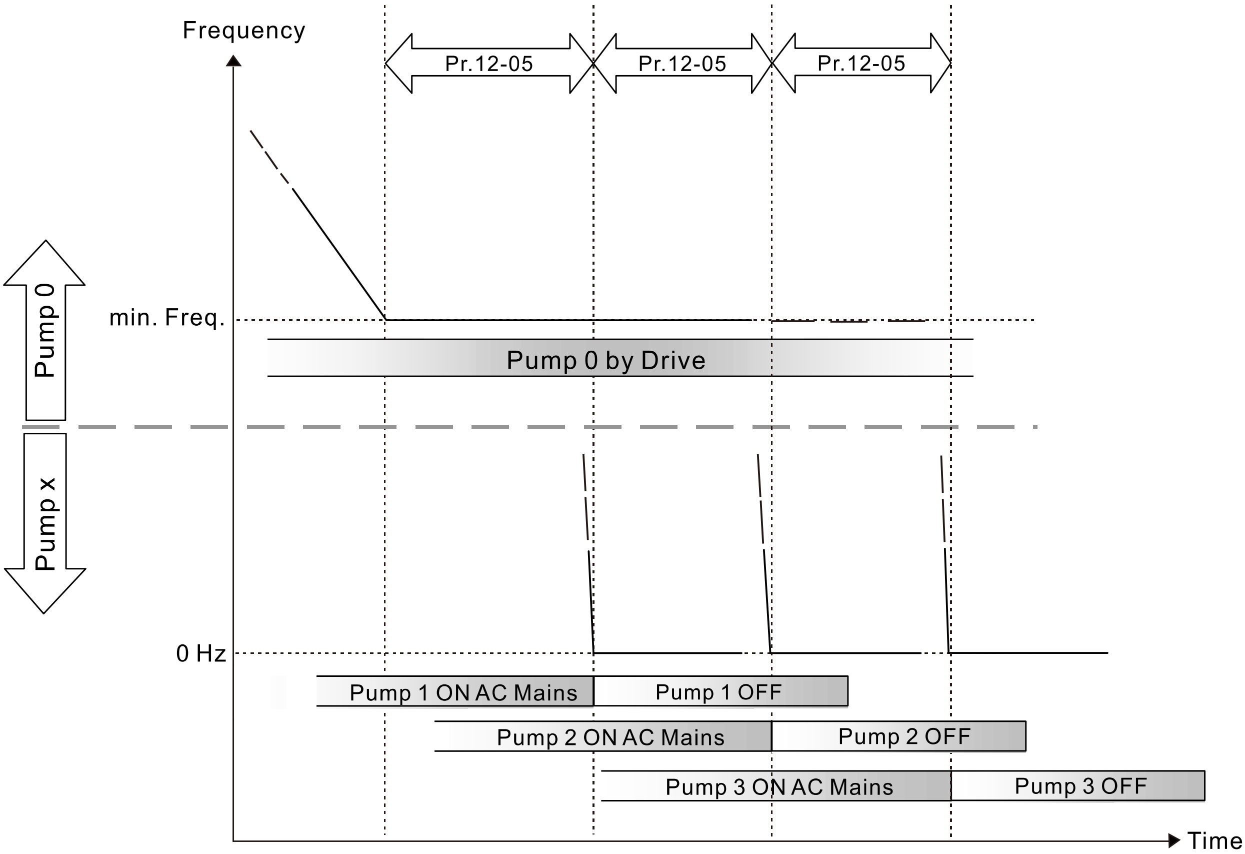


Diagram 12-11: Sequence of switching motors at Fixed Quantity Control with PID – Decreasing Demand

📖 Parameter setting:

Parameter Setting	Description
Pr.12-00 = 3	Choose Fixed Quantity Control
Pr.12-01 = X	Number of Motors: maximum of eight motors. After you set the number of connected motors, the multi-function output terminals automatically follow the setting as shown in the table below.

Pr.12-01	01	02	03	04	05	06	07	08	
Pr.02-13	55	55	55	55	55	55	55	55	Motor 1 by Mains
Pr.02-14		56	56	56	56	56	56	56	Motor 2 by Mains
Pr.02-15			57	57	57	57	57	57	Motor 3 by Mains
Pr.02-36				58	58	58	58	58	Motor 4 by Mains
Pr.02-37					59	59	59	59	Motor 5 by Mains
Pr.02-38						60	60	60	Motor 6 by Mains
Pr.02-39							61	61	Motor 7 by Mains
Pr.02-40								62	Motor 8 by Mains

Table 2: Setting of Multi-function Output Terminal on Circulating Motors

Parameter Setting	Description
Pr.12-05 = X	Delay time for Fixed Quantity Circulation at Motor Switching (seconds)
Pr.12-06 = X	Frequency for switching motors at Fixed Quantity Circulation (Hz)

Disable Motor’s Output

Set the multi-function input commands to Disable Motors’ Output can stop the corresponding motors.

The settings are:

Pr.02-01–Pr.02-06=	60	61	62	63	64	65	66	67	68
Disable Motor’s Output	ALL	1	2	3	4	5	6	7	8

When a motor’s output is disabled, this motor coasts to stop.

Wiring: Fixed Quantity Control can control up to eight motors. Diagram 12-12 is an example of controlling four motors at the same time.

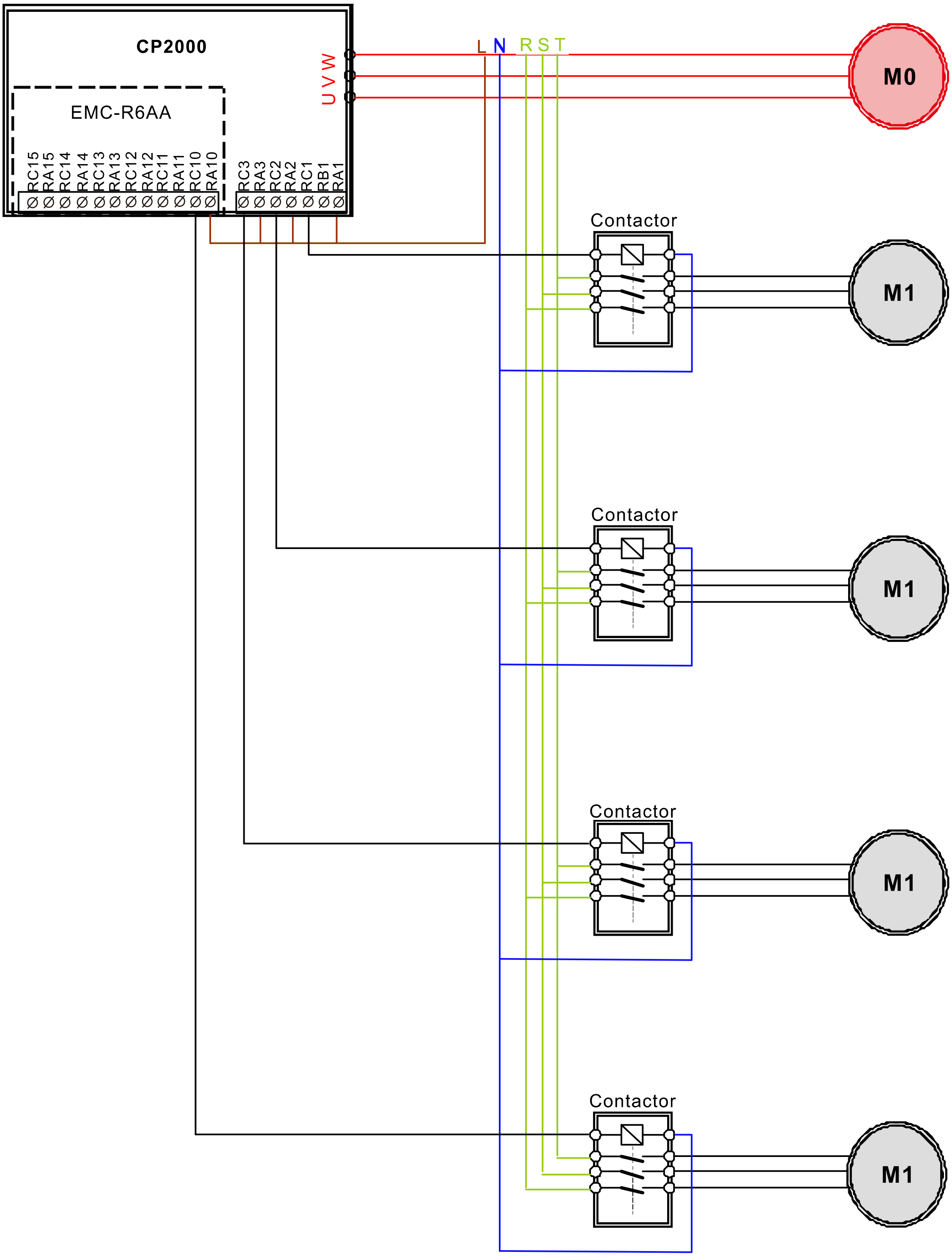


Diagram 12-12

📖 Fixed Time circulation and Fixed quantity circulation with PID

This mode combines Fixed Time Circulation and Fixed Quantity Circulation with PID. This is to prevent motors from becoming rusty if they are not in use for a long period. If some motors are not activated, set the fixed time circulation to run the motors one by one to make sure each of them is running.

If all the motors are running and the water pressure is sufficient, the fixed time circulation is not enabled. If motor 1 and motor 2 run to reach a balance in water pressure and the time reaches the setting for Pr.12-02, motor 1 runs without using mains electricity (runs by the motor drive) and motor 2 decelerates to stop.

When the motor 2 reaches the frequency setting at Pr.12-06 and the time setting for Pr.12-05, it separates from the motor drive (runs on mains electricity). When time reaches the setting for Pr.12-03, motor 2 runs using the mains electricity. Then when the time exceeds the setting for Pr.12-03, motor 3 is enabled by the motor drive. The time sequence Diagram 12-13 is shown as below.

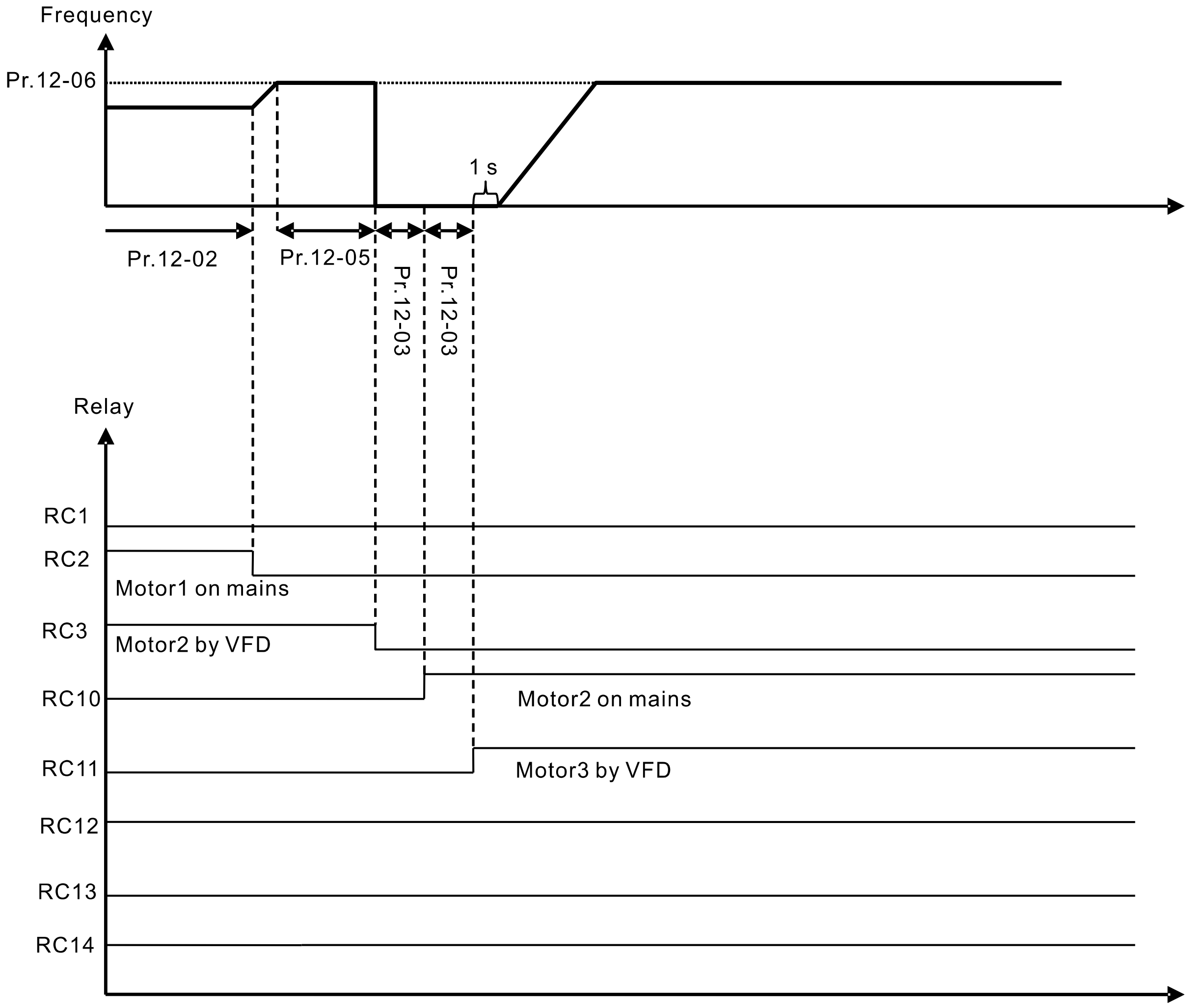


Diagram 12-13 Fixed Time Circulation and Fixed Quantity Control with PID

🕮 Fixed Time Circulation and Fixed Quantity Control with PID

This mode combines Fixed Time Circulation and Fixed Quantity Control with PID. This is to prevent motors from becoming rusty if they are not in use for a long period. If some motors are not activated, set the fixed time circulation to run the motors one by one to make sure each of them is running.

When all the motors are running and water pressure is sufficient, the fixed time circulation is not enabled. If motor 1 and motor 2 run to reach a balance in water pressure and when the time reaches the setting for Pr.12-02, motor 1 runs without using mains electricity (run by the motor drive). When the time reaches the setting for Pr.12-03, motor 3 runs using mains electricity, and the operating time of each motor resets. Once it reaches the time setting for Pr.12-02 again, motor 2 runs without using mains electricity. Then when time reaches the setting for Pr.12-03, motor 4 runs using mains electricity. The time sequence Diagram 12-14 is as shown below

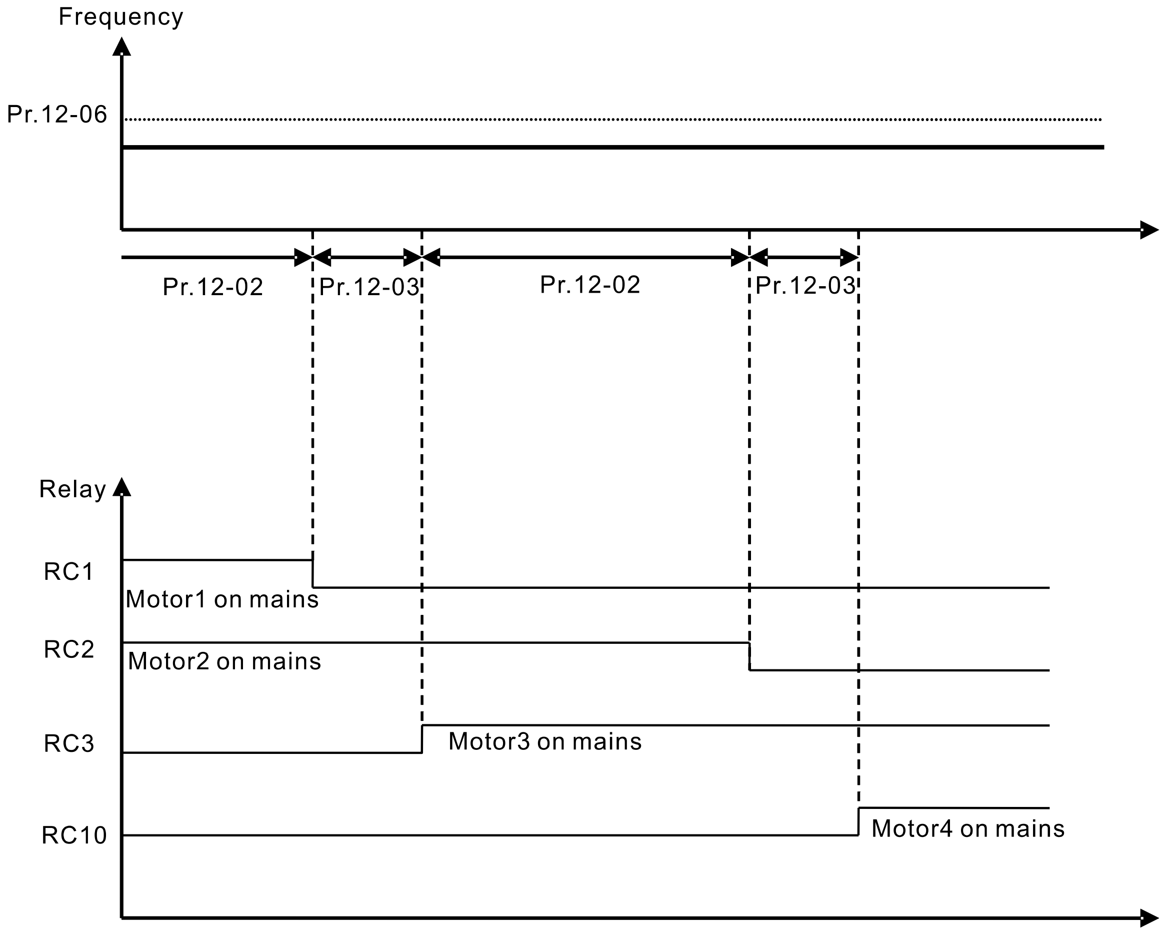


Diagram 12-14: Fixed Time Circulation under Fixed Amount Control Balance

✎ 12-09 Fixed Quantity Circulation Output Delay

Default: 1.0

Settings 1.0–3600.0 sec.

📖 Under Fixed Quantity Circulation (Increment) mode, the first motor of the drive switches to the supply mains through the setting time for Pr.12-03, then switches to the second motor through the setting delay time for Pr.12-09.

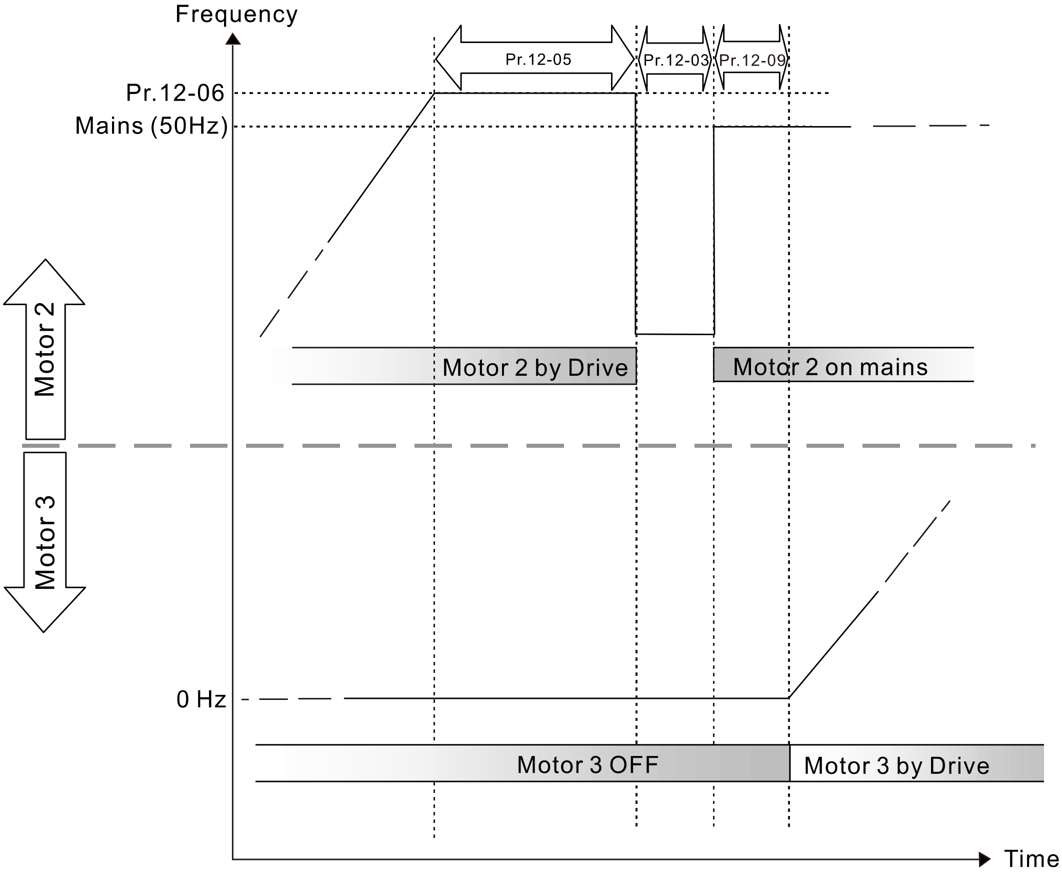


Diagram 12-15: Sequence of output delay for fixed quantity circulation

12-10 Motor 1 Operation Record (min. /sec.)

12-12 Motor 2 Operation Record (min. /sec.)

12-14 Motor 3 Operation Record (min. /sec.)

12-16 Motor 4 Operation Record (min. /sec.)

12-18 Motor 5 Operation Record (min. /sec.)

12-20 Motor 6 Operation Record (min. /sec.)

12-22 Motor 7 Operation Record (min. /sec.)

12-24 Motor 8 Operation Record (min. /sec.)

Default: Read only

Settings Read only

12-11 Motor 1 Operation Record (hour)

12-13 Motor 2 Operation Record (hour)

12-15 Motor 3 Operation Record (hour)

12-17 Motor 4 Operation Record (hour)

12-19 Motor 5 Operation Record (hour)

12-21 Motor 6 Operation Record (hour)

12-23 Motor 7 Operation Record (hour)

12-25 Motor 8 Operation Record (hour)

Default: Read only

Settings Read only

🕮 These parameters record the operation time for Motor 1 to Motor 8. For examples, Pr.12-10 and Pr.12-11 both record the operation time for Motor 1. Pr.12-10 records the operation time in minutes and seconds, whereas Pr.12-11 records the operation time in hours. When Pr.12-10 displays 5959, it means the motor has operated for 59 minutes and 59 seconds. When the motor operates for an hour, Pr.12-11 displays 1 and Pr.12-10 displays 0.

🕮 When circulation control Pr.12-00 = 1–5, the output frequency is > 0 Hz and output current is > 0 A, the motor operation time is recorded.

🕮 When the record reaches the upper limit 65535 hours 59 minutes and 59 seconds, clear the motor operation time manually to keep tracking the operation status of each motor, and the service life of the motor.

Motor No. / Motor Operation Time	Hour	Min./Sec.	Clear Motor Operation Time
Motor 1	Pr.12-11 = 65535 ↓ 65535 hour	Pr.12-10 = 5959 ↓ 59 min.: 59 sec.	Pr.12-26 = 1
Motor 2	Pr.12-13	Pr.12-12	Pr.12-26 = 2
Motor 3	Pr.12-15	Pr.12-14	Pr.12-26 = 3
Motor 4	Pr.12-17	Pr.12-16	Pr.12-26 = 4
Motor 5	Pr.12-19	Pr.12-18	Pr.12-26 = 5
Motor 6	Pr.12-21	Pr.12-20	Pr.12-26 = 6
Motor 7	Pr.12-23	Pr.12-22	Pr.12-26 = 7
Motor 8	Pr.12-25	Pr.12-24	Pr.12-26 = 8
All motors	N/A	N/A	Pr.12-26 = 10

12-26 Clear Motor's Operation Time

Default: 0

Settings 0: No function
1: Clear operation time for motor 1
2: Clear operation time for motor 2
3: Clear operation time for motor 3
4: Clear operation time for motor 4
5: Clear operation time for motor 5
6: Clear operation time for motor 6
7: Clear operation time for motor 7
8: Clear operation time for motor 8
10: Clear operation time for all motors

- Clear the operation time for single motor or all motors as needed.
- 1: The operation time for Motor 1 returns to zero, including operation records in Pr.12-11 (hour) and Pr.12-10 (min. /sec.).
- 10: The operation time for Motor 1–8 (Pr.12-10–Pr.12-25) all return to zero.

12-27 Priority for Circulated Operation

Default: 0

Settings 0: Terminal order
1: Minimum operation time

- Terminal order: the multi-function output terminals corresponded to each circulation control mode (Pr.12-00 = 1–5).
- Minimum operation time: starts in the order from the motor with the minimum operating hours among all running motors.
- The minimum operation time is only applicable for operation time record under fixed time circulation mode (Pr.12-00 = 1), as listed in the circulation mode comparison table below.
- A comparison for each circulation mode

Function / Circulation Control Mode	Pr.12-00 = 1	Pr.12-00 = 2–5
Motor operation time record	v	v
Terminal order	v	v
Minimum operation time	v*	x

* When the drive resumes and starts running after stopping (or turning off) after operating for a period, the motor operates according to the minimum operation time. However, the first operating motor after resuming is the previous running motor before stop or turn-off. If you need to start the motors according to the minimum operation time in sequence immediately after resuming, close the minimum operation time (Pr.12-27 = 0) first and start (Pr.12-27 = 1) again.

- When Pr.12-00 = 1–5, the terminal order (Pr.12-27 = 0) is applicable for the operation time record under all the circulated control modes.
- When Pr.12-00 = 1–5, the terminal order (Pr.12-27 = 0) is the only available selection, and the minimum operation time (Pr.12-27 = 1) is invalid.

📖 When the minimum operation time (Pr.12-27 = 1) is enabled, the drive sorts the operation hours according to the amount of running motors at the moment, and then choose the motor that has the minimum operation hour to start after RUN command.

As Example 1 below shows, the drive starts Motor 2, which having a minimum operation time among all eight motors.

As Example 2 below shows, Motor 8 does not start though it has the minimum operation time, because only Motor 1 to Motor 5 are started. Moreover, if more than one motors have the same minimum operation hour, the number of the motor takes the priority. Therefore, Motor 3 starts rather than Motor 5.

Motor operation time-Example 1

Motor No. / Motor Status	Status	Operating Hour	Operating Min./ Sec.
Motor 1	ON	0	59 59
Motor 2	ON	0	12 12
Motor 3	ON	2	00 00
Motor 4	ON	0	43 11
Motor 5	ON	1	33 00
Motor 6	ON	3	50 05
Motor 7	ON	1	05 22
Motor 8	ON	10	20 21

Motor operation time-Example 2

Motor No. / Motor status	Status	Operating Hour	Operating Min./ Sec.
Motor 1	ON	0	59 59
Motor 2	ON	5	12 12
Motor 3	ON	0	33 00
Motor 4	ON	0	43 11
Motor 5	ON	0	33 00
Motor 6	OFF	3	50 05
Motor 7	OFF	1	05 22
Motor 8	OFF	0	00 01

13 Application Parameters by Industry

✓ This parameter can be set during operation.

13-00 Application Selection

Default: 0

Settings 0: Disabled
1: User-defined Parameter
2: Compressor IM
3: Fan
4: Pump
10: Air Handling Unit, AHU

🕮 After you select the macro, some of the default values adjust automatically according to the application selection.

🕮 Each setting varies with different application selection, and its value is different as well.

🕮 Refer to Section 10-2 for more operation details.

🕮 Group settings: 2: Compressor IM

The following table lists the relevant compressor application parameters.

Pr.	Explanation	Settings
00-11	Speed control mode	0: VF (IM V/F control)
00-16	Load selection	0: Light load
00-17	Carrier frequency	Default setting
00-20	Master frequency command source (AUTO) / Source selection of the PID target	2: External analog input
00-21	Operation command source (AUTO)	1: External terminals.
00-22	Stop method	0: Ramp to stop
00-23	Control of motor direction	1: Disable reverse
01-00	Maximum operation frequency	Default setting
01-01	Output frequency of motor 1	Default setting
01-02	Output voltage of motor 1	Default setting
01-03	Mid-point frequency 1 of motor 1	Default setting
01-04	Mid-point voltage 1 of motor 1	Default setting
01-05	Mid-point frequency 2 of motor 1	Default setting
01-06	Mid-point voltage 2 of motor 1	Default setting
01-07	Minimum output frequency of motor 1	Default setting
01-08	Minimum output voltage of motor 1	Default setting
01-11	Output frequency lower limit	20 (Hz)
01-12	Acceleration time 1	20 (s)
01-13	Deceleration time 1	20 (s)
03-00	Analog input selection (AVI1)	0: No function
03-01	Analog input selection (ACI)	1: Frequency command
05-01	Full-load current for induction motor 1(A)	Default setting

Pr.	Explanation	Settings
05-03	Rated speed for induction motor 1 (rpm)	Default setting
05-04	Number of poles for induction motor 1	Default setting

📖 Group setting 03: Fan

The following table lists the relevant fan setting application parameters.

Pr.	Explanation	Settings
00-11	Speed control mode	0 (V/F control)
00-16	Load selection	0: Light load
00-17	Carrier frequency	Default setting
00-20	Master frequency command source (AUTO) / Source selection of the PID target	2: External analog input
00-21	Operation command source (AUTO)	1: External terminals.
00-22	Stop method	1: Coast to stop
00-23	Control of Motor Direction	1: Disable reverse
00-30	Master frequency command (HAND) source	0: Digital keypad
00-31	Operation command (HAND) source	0: Digital keypad
01-00	Maximum operation frequency	Default setting
01-01	Output frequency of motor 1	Default setting
01-02	Output voltage of motor 1	Default setting
01-03	Mid-point frequency 1 of motor 1	Default setting
01-04	Mid-point voltage 1 of motor 1	Default setting
01-05	Mid-point frequency 2 of motor 1	Default setting
01-06	Mid-point voltage 2 of motor 1	Default setting
01-07	Minimum output frequency of motor 1	Default setting
01-08	Minimum output voltage of motor 1	Default setting
01-10	Output frequency upper limit	50 (Hz)
01-11	Output frequency lower limit	35 (Hz
01-12	Acceleration time 1	15 (s)
01-13	Deceleration time 1	15 (s)
01-43	V/F curve selection	2: 2nd V/F curve
02-05	Multi-function input command 5 (MI5)	16: Rotating speed command from ACI
03-00	Analog input selection (AVI1)	1: Frequency command
03-01	Analog input selection (ACI)	1: Frequency command
03-28	AVI1 terminal input selection	0 (0–10 V)
03-29	ACI terminal input selection	1 (0–10 V)
03-31	AFM output selection	0 (0–10 V)
03-50	Analog input curve selection	1: three-point curve of AVI1
07-06	Restart after momentary power loss	2: Speed tracking by minimum output frequency
07-11	Number of times of restart after fault	5 (times)
07-33	Auto-restart interval of fault	60 (s)

🕮 Group setting 04: Pump

The following table lists the relevant pump setting application parameters.

Pr.	Explanation	Settings
00-11	Speed control mode	0 (V/F mode)
00-16	Load selection	0: Light load
00-20	Master frequency command source (AUTO) / Source selection of the PID target	2: External analog input
00-21	Operation command source (AUTO)	1: External terminals.
00-23	Control of motor direction	1: Disable reverse
01-00	Maximum operation frequency	Default setting
01-01	Output frequency of motor 1	Default setting
01-02	Output voltage of motor 1	Default setting
01-03	Mid-point frequency 1 of motor 1	Default setting
01-04	Mid-point voltage 1 of motor 1	Default setting
01-05	Mid-point frequency 2 of motor 1	Default setting
01-06	Mid-point voltage 2 of motor 1	Default setting
01-07	Minimum output frequency of motor 1	Default setting
01-08	Minimum output voltage of motor 1	Default setting
01-10	Output frequency upper limit	50 (Hz)
01-11	Output frequency lower limit	35 (Hz)
01-12	Acceleration time 1	15 (s)
01-13	Deceleration time 1	15 (s)
01-43	V/F curve selection	2: 2nd V/F curve
07-06	Restart after momentary power loss	2: Speed tracking by minimum output frequency
07-11	Number of times of restart after fault	5 (times)
07-33	Auto-restart interval of fault	60 (s)

🕮 Group setting 10: Air Handling Unit, AHU

The following table lists the relevant AHU setting application parameters.

Pr.	Explanation	Settings
00-04	Content of multi-function display	2
00-11	Speed control mode	0 (V/F control)
00-16	Load selection	0: Light load
00-20	Master frequency command source (AUTO) / Source selection of the PID target	2 or 0 (External analog input)
00-21	Operation command source (AUTO)	1 or 0 (External terminals)
00-22	Stop method	1: Coast to stop
00-23	Control of motor direction	1: Disable reverse
00-30	Master frequency command (HAND) source	0: Digital keypad
00-31	Operation command (HAND) source	0: Digital keypad

Pr.	Explanation	Settings
01-00	Maximum operation frequency	Default setting
01-01	Output frequency of motor 1	Default setting
01-02	Output voltage of motor 1	Default setting
01-07	Minimum output frequency of motor 1	Default setting
01-10	Output frequency upper limit	50
01-11	Output frequency lower limit	35
01-34	Zero-speed mode	2
01-43	V/F curve selection	2
02-05	Multi-function input command 5 (MI5)	16 or 17
02-13	Multi-function output 1 RLY1	11
02-14	Multi-function output 2 RLY2	1
03-00	Analog input selection (AVI1)	1
03-01	Analog input selection (ACI)	1
03-02	Analog input selection (AVI2)	1
03-28	AVI1 terminal input selection	0
03-29	ACI terminal input selection	1
03-20	Multi-function output 1 (AFM1)	0
03-23	Multi-function output 2（AFM2）	0
03-31	AFM1 current selection	0 or 1
03-34	AFM2 current selection	0 or 1
03-50	Analog input curve selection	4
07-06	Restart after momentary power loss	2 (Speed tracking by minimum output frequency)
07-11	Number of times of restart after fault	5 (times)
07-33	Auto-restart interval of fault	60 (s)

13-01
|
13-99

Application Parameter 1–99

Default: 0.00

Settings 0.00–655.35

14 Extension Card Parameter

✎ This parameter can be set during operation.

✎ **14-00** Extension Card Input Terminal Selection (AI10)

✎ **14-01** Extension Card Input Terminal Selection (AI11)

Default: 0

Settings 0: Disable
1: Frequency command
4: PID target value
5: PID feedback signal
6: Thermistor (PTC) input value
11: PT100 thermistor input value
13: PID compensation amount

🕮 When the setting for Pr.14-00 and Pr.14-01 are the same, the AI10 is selected first.

✎ **14-08** Analog Input Filter Time (AI10)

✎ **14-09** Analog Input Filter Time (AI11)

Default: 0.01

Settings 0.00–20.00 sec.

🕮 The input analog signal of terminal AI1 and AI2 often includes interferences, which will affect the stability of the control. Use these input delays to filter a noisy analog signal.

🕮 When the setting for the time constant is too large, the control is stable but the control response is slow. When the setting for time constant is too small, the control response is faster but the control may be unstable. For optimal setting, adjust the setting according to the control stability or the control response.

14-10 Analog Input 4–20 mA Signal Loss Selection (AI10)

14-11 Analog Input 4–20 mA Signal Loss Selection (AI11)

Default: 0

Settings 0: Disable
1: Continue operation at the last frequency
2: Decelerate to 0 Hz
3: Stop immediately and display ACE

🕮 This parameter determines the treatment when the 4–20 mA signal is lost, when Pr.14-18 = 2, Pr.14-19 = 2.

🕮 When the setting for Pr.14-18 or Pr.14-19 are 0 or 1, the voltage input to AVI and ACI terminal is 0–10 V or 4–20 mA. At this moment, Pr.14-10 and Pr.14-11 are invalid.

🕮 Setting 1 or 2: Displays the warning code "ANL" on the keypad. It continues blinking until the lost ACI signal is recovered.

🕮 When the motor drive stops, the warning condition does not continue to exist, so the warning disappears.

14-12 Extension Card Output Terminal Selection (AO10)

14-13 Extension Card Output Terminal Selection (AO11)

Default: 0

Settings 0–23

🕮 Refer to the function chart below for details setting.

Function Chart

<table>
<tr><th>Settings</th><th>Functions</th><th>Descriptions</th></tr>
<tr><td>0</td><td>Output frequency (Hz)</td><td>Maximum frequency Pr.01-00 is processed as 100%.</td></tr>
<tr><td>1</td><td>Frequency command (Hz)</td><td>Maximum frequency Pr.01-00 is processed as 100%.</td></tr>
<tr><td>2</td><td>Motor speed (Hz)</td><td>Maximum frequency Pr.01-00 is processed as 100%.</td></tr>
<tr><td>3</td><td>Output current (rms)</td><td>(2.5 × rated current) is processed as 100%</td></tr>
<tr><td>4</td><td>Output voltage</td><td>(2 × rated voltage) is processed as 100%</td></tr>
<tr><td>5</td><td>DC bus voltage</td><td>450V (900V)=100%</td></tr>
<tr><td>6</td><td>Power factor</td><td>-1.000–1.000=100%</td></tr>
<tr><td>7</td><td>Power</td><td>(2 × rated power) is processed as 100%</td></tr>
<tr><td>9</td><td>AVI1</td><td>0–10 V = 0–100%</td></tr>
<tr><td>10</td><td>ACI</td><td>4–20 mA = 0–100%</td></tr>
<tr><td>11</td><td>AVI2</td><td>-10–10 V = 0–100%</td></tr>
<tr><td>20</td><td>CANopen analog output</td><td>For CANopen communication analog output
<table>
<tr><th>Terminal</th><th>Corresponding address</th></tr>
<tr><td>AFM1</td><td>2026-A1</td></tr>
<tr><td>AFM2</td><td>2026-A2</td></tr>
<tr><td>AO10</td><td>2026-AB</td></tr>
<tr><td>AO11</td><td>2026-AC</td></tr>
</table></td></tr>
<tr><td>21</td><td>RS-485 analog output</td><td>For RS-485 (InnerCOM / Modbus) analog output
<table>
<tr><th>Terminal</th><th>Corresponding address</th></tr>
<tr><td>AFM1</td><td>26A0H</td></tr>
<tr><td>AFM2</td><td>26A1H</td></tr>
<tr><td>AO10</td><td>26AAH</td></tr>
<tr><td>AO11</td><td>26ABH</td></tr>
</table></td></tr>
<tr><td>22</td><td>Communication card analog output</td><td>For communication analog output (CMC-EIP01, CMC-PN01, CMC-DN01)
<table>
<tr><th>Terminal</th><th>Corresponding address</th></tr>
<tr><td>AFM1</td><td>26A0H</td></tr>
<tr><td>AFM2</td><td>26A1H</td></tr>
<tr><td>AO10</td><td>26AAH</td></tr>
<tr><td>AO11</td><td>26ABH</td></tr>
</table></td></tr>
<tr><td>23</td><td>Constant voltage output</td><td>Pr.14-20 and Pr.14-21 control voltage output level
0–100% of Pr.14-20 corresponds to 0–10 V of AO10.
0–100% of Pr.14-21 corresponds to 0–10 V of AO11.</td></tr>
</table>

✓ **14-14** Analog Output 1 Gain (AO10)

✓ **14-15** Analog Output 1 Gain (AO11)

Default: 100.0

Settings 0.0–500.0%

🕮 Adjusts the voltage level outputted to the analog meter from the analog signal (Pr.14-12, Pr.14-13) output terminal AFM of the drive.

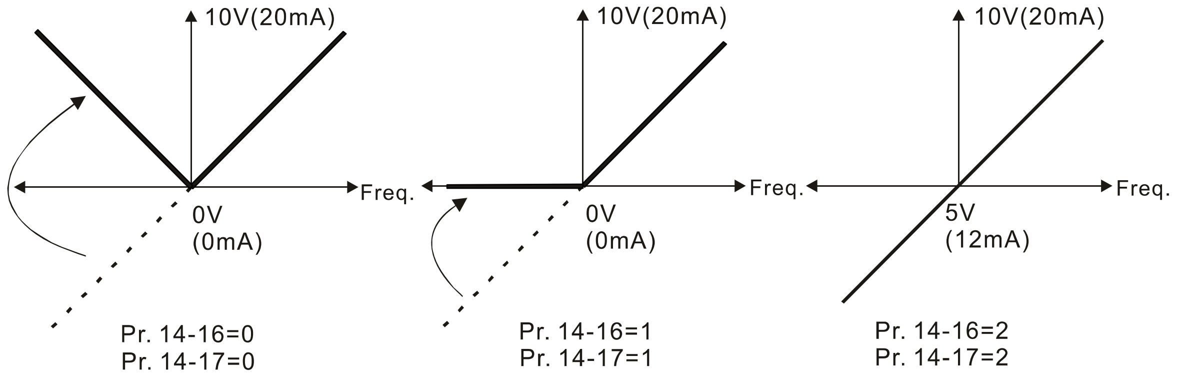
✓ **14-16** Analog Output 1 in REV Direction (AO10)

✓ **14-17** Analog Output 1 in REV Direction (AO11)

Default: 0

Settings 0: Absolute output voltage value
1: Reverse output 0 V; forward output 0–10 V
2: Reverse output 5–0 V; forward output 5–10 V

🕮 Determines the voltage reverse output when AO10 and AO11 are set as 0–10 V (Pr.14-36 = 0, Pr.14-37 = 0).



Analog Output Direction

✓ **14-18** Extension Card Input Selection (AI10)

Default: 0

Settings 0: 0–10 V (AVI10)
1: 0–20 mA (ACI10)
2: 4–20 mA (ACI10)

✓ **14-19** Extension Card Input Selection (AI11)

Default: 0

Settings 0: 0–10 V (AVI11)
1: 0–20 mA (ACI11)
2: 4–20 mA (ACI11)

🕮 When you change the input mode, verify that the switch position of external terminal (AI10, AI11) is correct.

✓ **14-20** AO10 DC Output Setting Level

✓ **14-21** AO11 DC Output Setting Level

Default: 0.00

Settings 0.00–100.00%

ϟ 14-22 AO10 Filter Output Time

ϟ 14-23 AO11 Filter Output Time

Default: 0.01

Settings 0.00–20.00 sec.

ϟ 14-36 AO10 Output Selection

ϟ 14-37 AO11 Output Selection

Default: 0

Settings 0: 0–10 V

1: 0–20 mA

2: 4–20 mA

12-2 Adjustment & Application

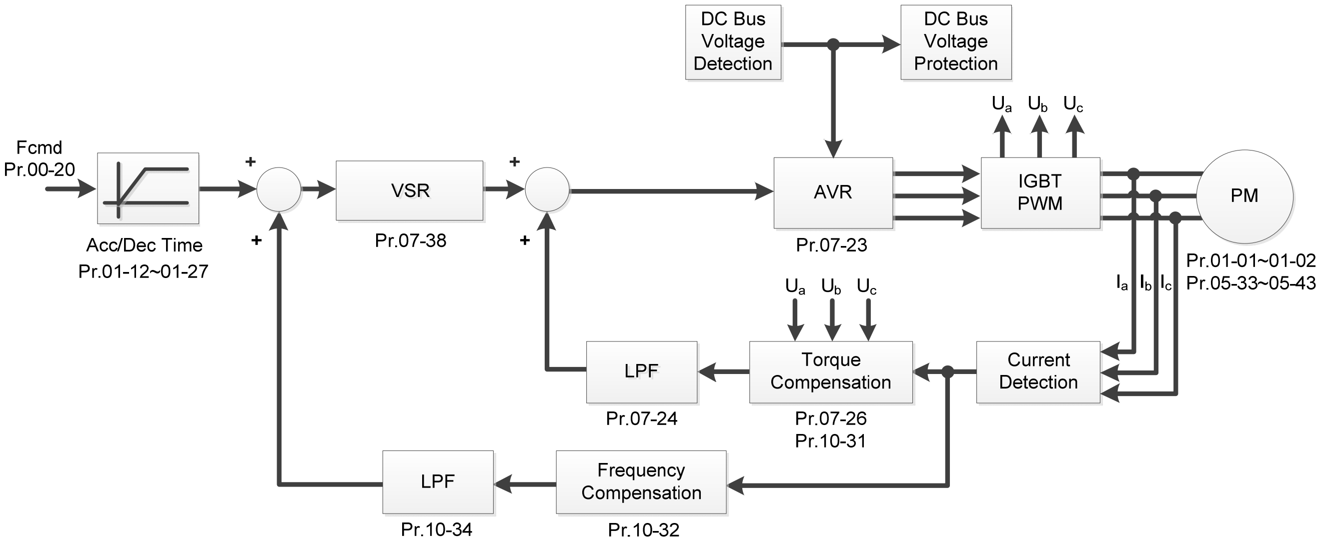
The followings are abbreviations for different types of motors:

- IM: Induction motor
- PM: Permanent magnet synchronous AC motor
- IPM: Interior permanent magnet synchronous AC motor
- SPM: Surface permanent magnet synchronous AC motor
- SynRM: Synchronous reluctance motor

12-2-1 Permanent Magnet Motor Space Vector Control (PM SVC) Pr.00-11 = 2

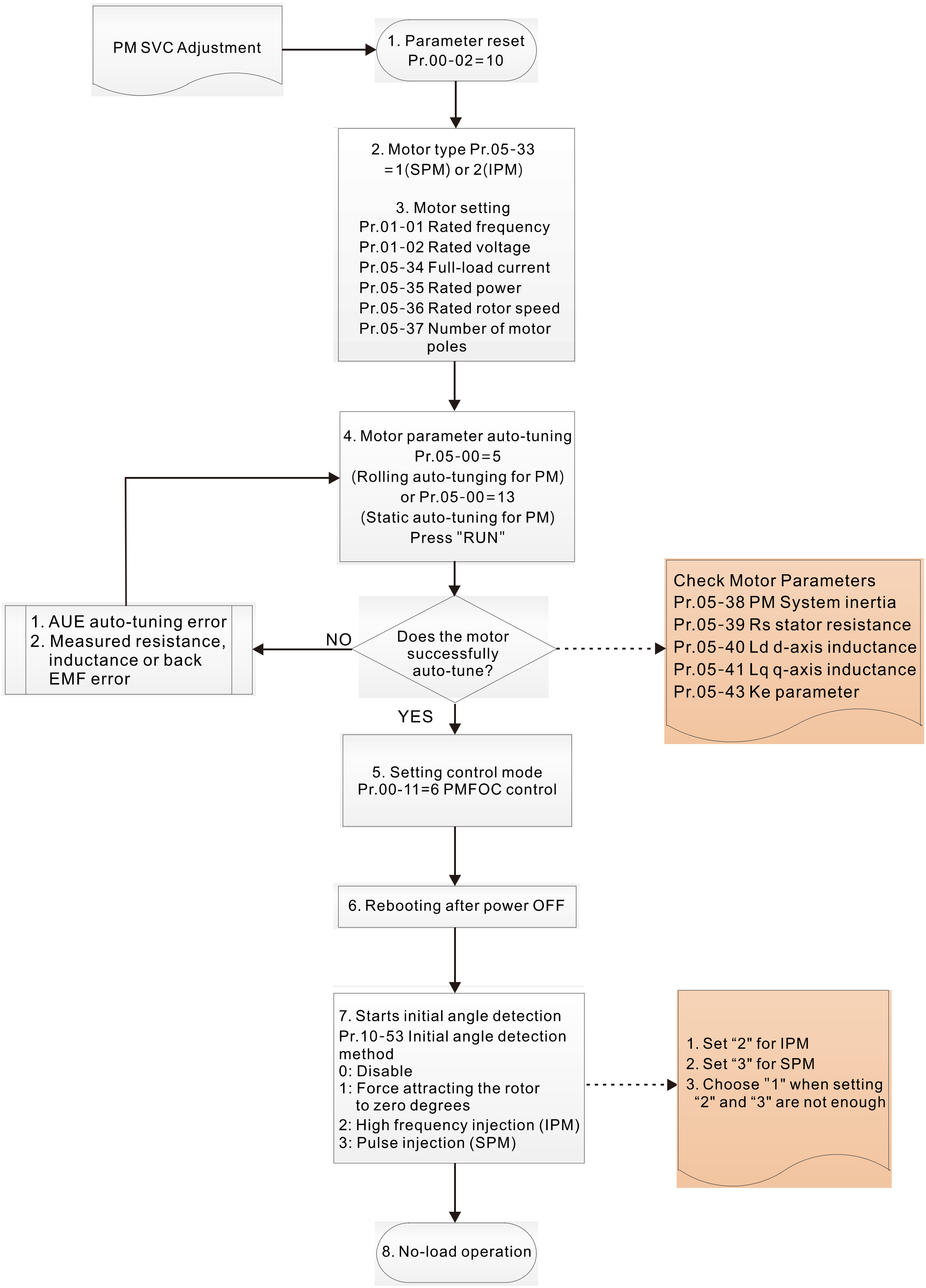
1. Control Diagram

   PM SVC control diagram



2. PM SVC Adjustment Procedure (※ the number marked on the procedure corresponds to the number of following adjustment explanations)

I. PM SVC motor parameters adjustment


PM SVC Adjustment
1. Parameter reset
Pr.00-02=10
2. Motor type Pr.05-33
=1(SPM) or 2(IPM)
3. Motor setting
Pr.01-01 Rated frequency
Pr.01-02 Rated voltage
Pr.05-34 Full-load current
Pr.05-35 Rated power
Pr.05-36 Rated rotor speed
Pr.05-37 Number of motor poles
4. Motor parameter auto-tuning
Pr.05-00=5
(Rolling auto-tunging for PM)
or Pr.05-00=13
(Static auto-tuning for PM)
Press "RUN"
Does the motor successfully auto-tune?
NO
1. AUE auto-tuning error
2. Measured resistance, inductance or back EMF error
Check Motor Parameters
Pr.05-38 PM System inertia
Pr.05-39 Rs stator resistance
Pr.05-40 Ld d-axis inductance
Pr.05-41 Lq q-axis inductance
Pr.05-43 Ke parameter
YES
5. Setting control mode
Pr.00-11=6 PMFOC control
6. Rebooting after power OFF
7. Starts initial angle detection
Pr.10-53 Initial angle detection method
0: Disable
1: Force attracting the rotor to zero degrees
2: High frequency injection (IPM)
3: Pulse injection (SPM)
1. Set “2" for IPM
2. Set “3" for SPM
3. Choose "1" when setting “2" and “3" are not enough
8. No-load operation

📖 Basic Motor Parameters Adjustment

1. Parameter reset:

   Reset Pr.00-02 = 10 (60 Hz) to the default value.

2. Select PM motor type:

   Pr.05-33 = 1 (SPM) or 2 (IPM)

3. Motor nameplate parameter setting:

Parameter	Description
Pr.01-01	Rated frequency (Hz)
Pr.01-02	Rated voltage (V_{AC})
Pr.05-34	Rated current (A)
Pr.05-35	Rated power (kW)
Pr.05-36	Rated rotor speed (rpm)
Pr.05-37	Number of poles for the motor (poles)

4. PM parameter auto-tuning:

5. Set Pr.05-00 = 5 (Rolling auto-tuning for PM) or 13 (Static auto-tuning for PM) and press "RUN" key to finish motor auto-tuning, then you will get the following parameters:

Parameter	Description
Pr.05-39	Stator resistance for a permanent magnet motor (Ω)
Pr.05-40	Permanent magnet motor Ld (mH)
Pr.05-41	Permanent magnet motor Lq (mH)
Pr.05-43	Ke parameter of a permanent magnet motor ($V_{phase \cdot rms}$ / krpm) (When Pr.05-00 = 5, the Ke parameter is measured based on the actual motor rotation.) (When Pr.05-00 = 13, the Ke parameter is automatically calculated based on the motor power, current and rotor speed.)

   If an auto-tuning error (AUE) occurs, refer to Section 14 "Fault Codes and Descriptions" for further treatment.

AUE Error (code)	Description
AUE (40)	Auto-tuning error
AUE1 (142)	Auto-tuning error 1 (No feedback current error)
AUE2 (143)	Auto-tuning error 2 (Motor phase loss error)

6. Set control mode

   Control mode for the motor: Pr.00-11 = 2: PM SVC mode

7. Measure the initial magnetic pole angle of PM

   Set Pr.10-53 PM initial rotor position detection method

   0: Disable

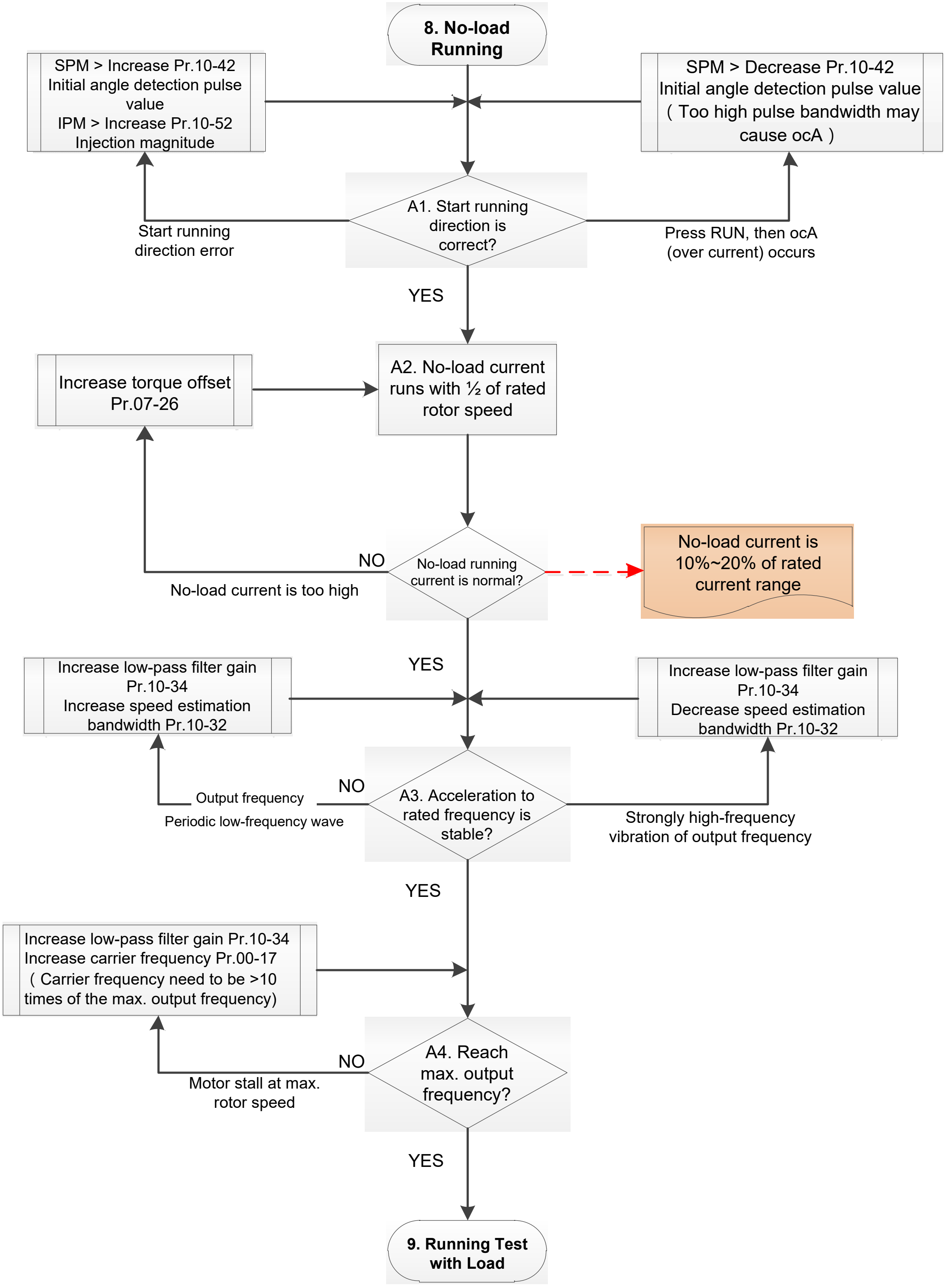
   1: Using I/F current command (Pr.10-31) to attract the rotor to zero degrees

   2: High frequency injection

   3: Pulse injection

   (Set to 2 for IPM; set to 3 for SPM. If these settings cause problems, then set the parameter to 1.)

II. PMSVC Adjustment for Operation without Load / with Light-load


8. No-load Running
SPM > Increase Pr.10-42 Initial angle detection pulse value
IPM > Increase Pr.10-52 Injection magnitude
SPM > Decrease Pr.10-42 Initial angle detection pulse value (Too high pulse bandwidth may cause ocA)
A1. Start running direction is correct?
Start running direction error
Press RUN, then ocA (over current) occurs
YES
Increase torque offset Pr.07-26
A2. No-load current runs with ½ of rated rotor speed
NO
No-load running current is normal?
No-load current is too high
No-load current is 10%~20% of rated current range
YES
Increase low-pass filter gain Pr.10-34
Increase speed estimation bandwidth Pr.10-32
Increase low-pass filter gain Pr.10-34
Decrease speed estimation bandwidth Pr.10-32
NO
Output frequency
Periodic low-frequency wave
A3. Acceleration to rated frequency is stable?
Strongly high-frequency vibration of output frequency
YES
Increase low-pass filter gain Pr.10-34
Increase carrier frequency Pr.00-17
(Carrier frequency need to be >10 times of the max. output frequency)
NO
Motor stall at max. rotor speed
A4. Reach max. output frequency?
YES
9. Running Test with Load

🕮 Adjustment for Operation with Light-load

8. Start the motor with no-load / light-load, and operates to 1/2 of the rated rotor speed

A1. Start operation direction:

a. If the start operation direction is wrong
SPM: increase the current proportion for Pr.10-42 (Initial angle detection pulse value) to improve the accuracy of the angle detection.
IPM: Increase the voltage for Pr.10-52 (Injection magnitude) to improve the accuracy of the angle detection.

b. If an ocA error occurs when pressing RUN to start the motor, decrease the current proportion for Pr.10-42 (Initial angle detection pulse value). An excessive pulse current may cause ocA error easily.

A2. Operates the motor in 1/2 of the rated rotor speed, adjust the no-load operating current
If the no-load operating current exceeds 20% of the rated current, increase Pr.07-26 (Torque compensation gain) and observe the no-load operating current.

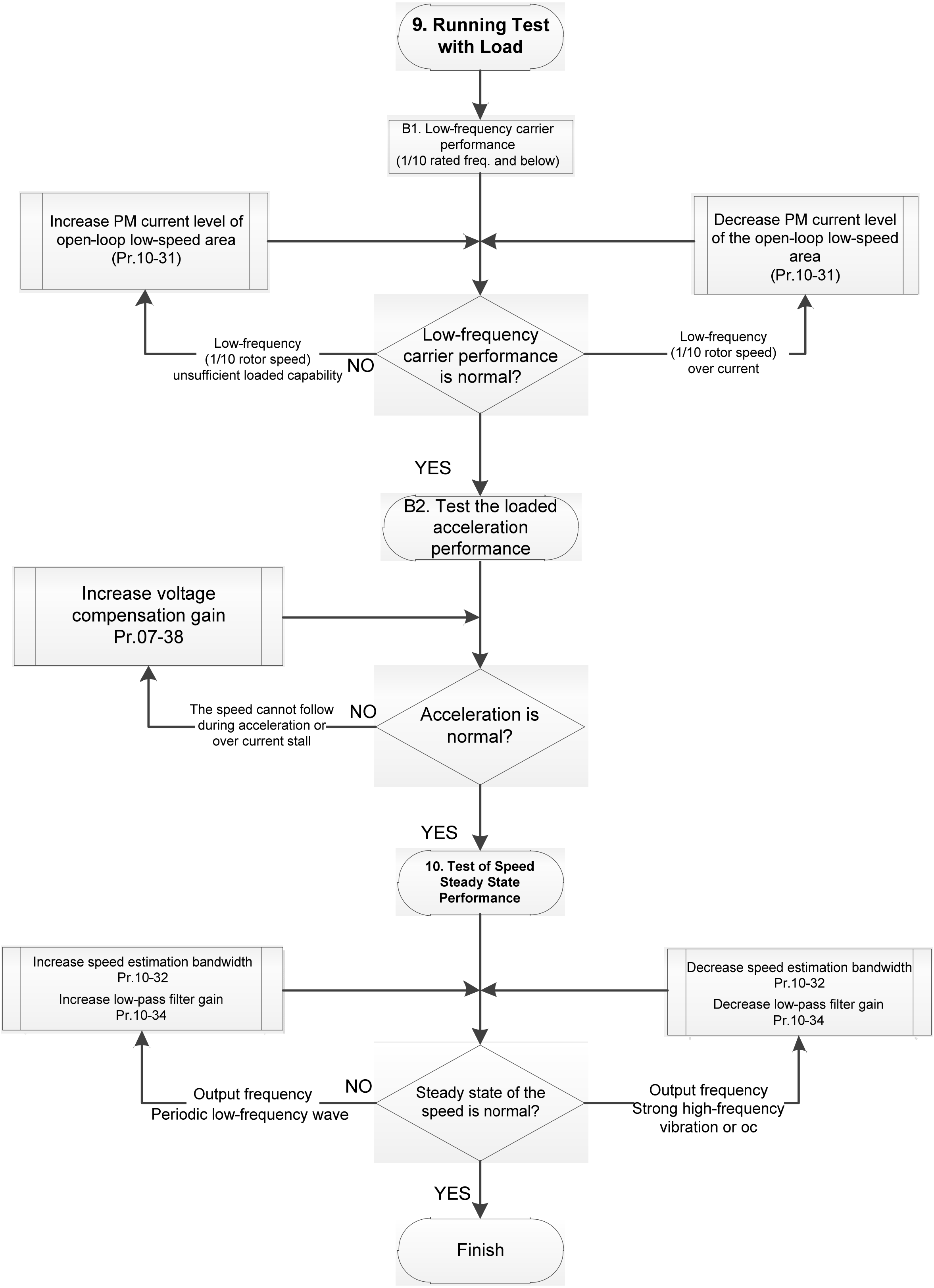
A3. Accelerate to rated frequency and observe if the motor operates stably.

a. If the motor output rotor speed presents periodic low-frequency wave, increase Pr.10-34 (PM sensorless speed estimator low-pass filter gain), or increase Pr.10-32 (PM FOC sensorless speed estimator bandwidth).

b. If the output frequency reflects high frequency vibration, decrease Pr.10-34 or decrease Pr.10-32.

A4. Accelerate the motor to the maximum rotor speed, and observe if it operates stably.
If the motor stalls when accelerating to the maximum rotor speed, then increase Pr.10-34 PM Sensorless Speed Estimator Low-pass Filter Gain, or increase Pr.00-17 Carrier Frequency (you must set the carrier frequency larger than 10 times of the maximum output frequency)

III. PM SVC Carrier Start-up Adjustment


9. Running Test with Load
B1. Low-frequency carrier performance (1/10 rated freq. and below)
Increase PM current level of open-loop low-speed area (Pr.10-31)
Decrease PM current level of the open-loop low-speed area (Pr.10-31)
Low-frequency (1/10 rotor speed) unsufficient loaded capability
NO
Low-frequency carrier performance is normal?
Low-frequency (1/10 rotor speed) over current
YES
B2. Test the loaded acceleration performance
Increase voltage compensation gain Pr.07-38
The speed cannot follow during acceleration or over current stall
NO
Acceleration is normal?
YES
10. Test of Speed Steady State Performance
Increase speed estimation bandwidth Pr.10-32
Increase low-pass filter gain Pr.10-34
Decrease speed estimation bandwidth Pr.10-32
Decrease low-pass filter gain Pr.10-34
Output frequency Periodic low-frequency wave
NO
Steady state of the speed is normal?
Output frequency Strong high-frequency vibration or oc
YES
Finish

🕮 Heavy Load Operation Adjustment

9. Load operating test

B1. Low-frequency loading performance is below 1/10 of rated frequency:

a. If the low-frequency loading performance is insufficient, or the rotor speed is not smooth, increase Pr.10-31 (Current command of I/F mode).

b. If the low-frequency current is large, decrease Pr.10-31 (Current command of I/F mode).

B2. Test the with-load accelerating performance:

When the motor operates in 1/10 of rotor speed and above, if the speed cannot follow the acceleration time during accelerating, or the current stalls, increase Pr.07-38 (PMSVC voltage feedback forward gain).

10. Stability test at constant speed operation: if the motor operates stably at constant speed

a. If the motor output rotor speed presents periodic low-frequency wave, increase Pr.10-34 (PM sensorless speed estimator low-pass filter gain), or increase Pr.10-32 (PM FOC sensorless speed estimator bandwidth).

b. If the output frequency reflects high frequency vibration, decrease Pr.10-34 or decrease Pr.10-32.

12-2-2-1 PMSVC Related Parameters

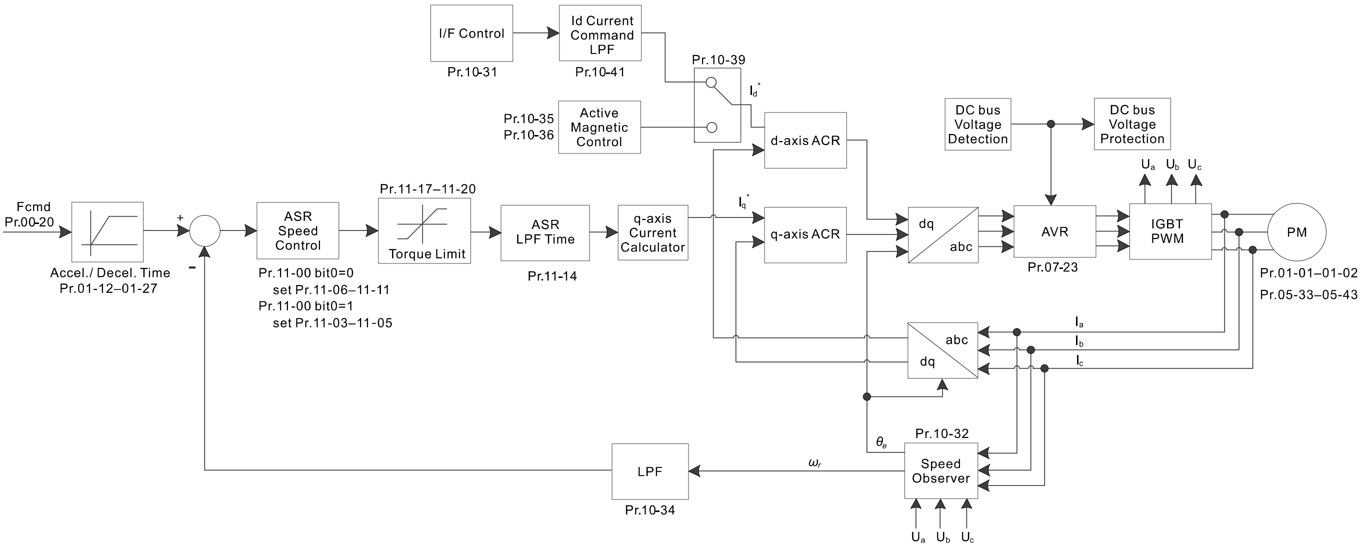
Refer to Section 12-1 Description of Parameter Settings for more details.

Parameter	Description	Unit	Default	Setting Range
Pr.07-24	Torque command filter time	sec.	0.5	0.001–10
Pr.07-26	Torque compensation gain	N/A	0	0–5000
Pr.07-38	PMSVC voltage feedback forward gain	N/A	1.0	0.5–2.0
Pr.10-31	I/F mode, current command	%	40	0–150
Pr.10-32	PM FOC sensorless speed estimator bandwidth	Hz	5.00	0.00–600.00
Pr.10-34	PM sensorless speed estimator low-pass filter gain	N/A	1.00	0.00–655.35
Pr.10-39	Frequency point to switch from I/F mode to PM sensorless mode	Hz	20.00	0.00–599.00
Pr.10-40	Frequency point to switch from PM sensorless mode to V/F mode	Hz	20.00	0.00–599.00
Initial Angle Estimating Parameters				
Pr.10-42	Initial angle detection pulse value	N/A	1.0	0.0–3.0
Pr.10-51	Injection frequency	Hz	500	0–1200
Pr.10-52	Injection magnitude	V	15.0 / 30.0	0.0–200.0
Pr.10-53	PM initial rotor position detection method 0: Disable 1: Using I/F current command (Pr.10-31) to attract the rotor to zero degrees 2: High frequency injection 3: Pulse injection	N/A	0	0–3

12-2-2 PM Sensorless Adjustment (Pr.00-11 = 6)

1. Control Diagram

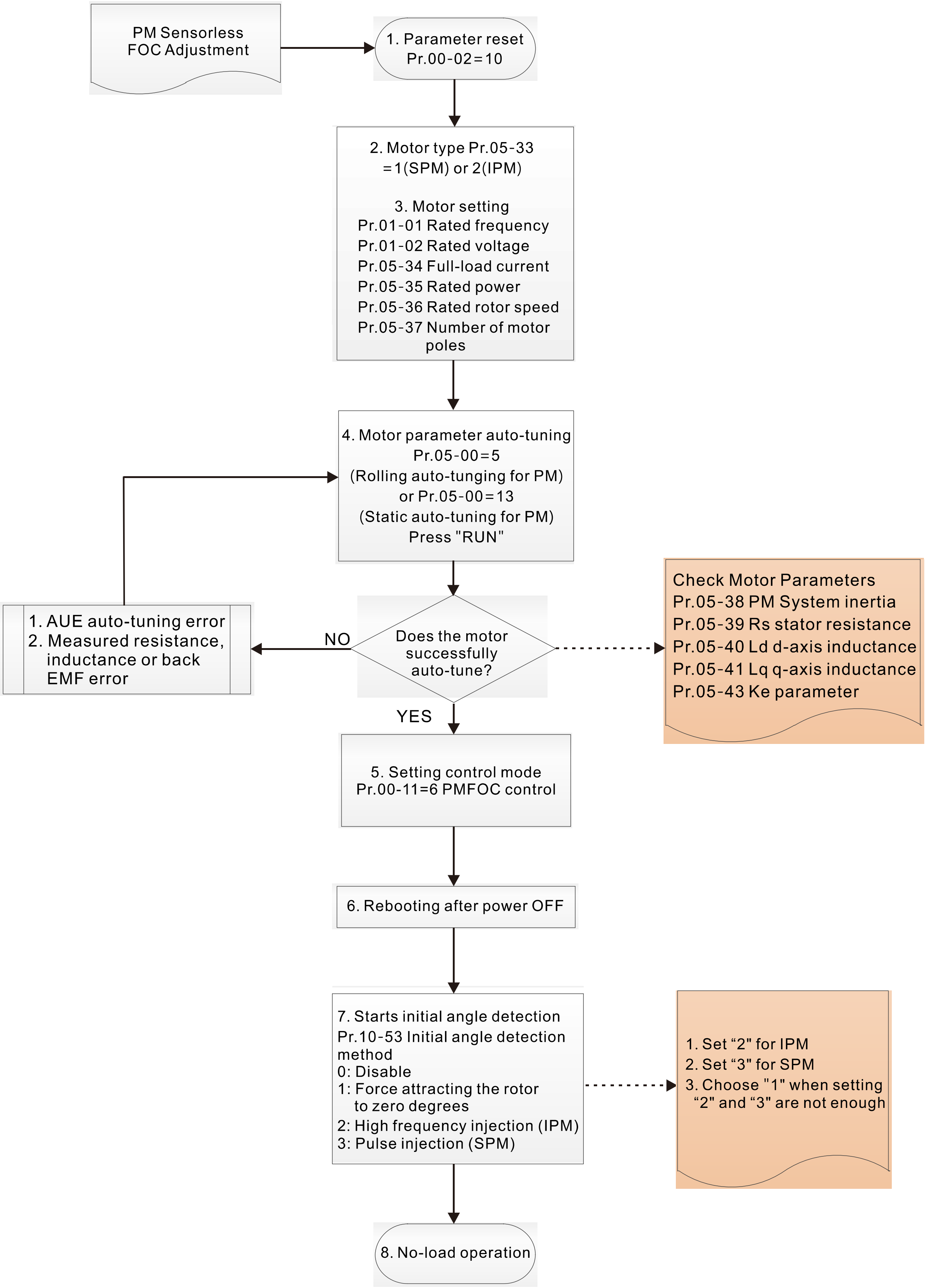
PM Sensorless FOC mode (applicable for CP2000 V2.07 and above)



※ PM Sensorless FOC control is the control method dedicated for PM; it uses the high salient pole characteristic of PM to detect positions of NS magnetic poles. By doing this, it calculates the motor's rotor position at low-speed frequency.

2. PM Sensorless FOC Control Adjustment (* the number marked on the procedure corresponds the number of following explanations)

I. Adjustment for PM Sensorless FOC Mode Motor Parameters


PM Sensorless FOC Adjustment
1. Parameter reset Pr.00-02=10
2. Motor type Pr.05-33 =1(SPM) or 2(IPM)
3. Motor setting
Pr.01-01 Rated frequency
Pr.01-02 Rated voltage
Pr.05-34 Full-load current
Pr.05-35 Rated power
Pr.05-36 Rated rotor speed
Pr.05-37 Number of motor poles
4. Motor parameter auto-tuning Pr.05-00=5 (Rolling auto-tunging for PM) or Pr.05-00=13 (Static auto-tuning for PM) Press "RUN"
Does the motor successfully auto-tune?
NO
1. AUE auto-tuning error
2. Measured resistance, inductance or back EMF error
Check Motor Parameters
Pr.05-38 PM System inertia
Pr.05-39 Rs stator resistance
Pr.05-40 Ld d-axis inductance
Pr.05-41 Lq q-axis inductance
Pr.05-43 Ke parameter
YES
5. Setting control mode Pr.00-11=6 PMFOC control
6. Rebooting after power OFF
7. Starts initial angle detection
Pr.10-53 Initial angle detection method
0: Disable
1: Force attracting the rotor to zero degrees
2: High frequency injection (IPM)
3: Pulse injection (SPM)
1. Set "2" for IPM
2. Set "3" for SPM
3. Choose "1" when setting "2" and "3" are not enough
8. No-load operation

📖 Motor Parameters Adjustment

1. Parameter reset:

   Pr.00-02 = 10, reset parameter to the default value.

2. Select motor type:

   Pr.05-33 = 1 or 2 (SPM or IPM)

3. Motor nameplate parameter setting:

Parameter	Description
Pr.01-01	Rated frequency (Hz)
Pr.01-02	Rated voltage (V_{AC})
Pr.05-34	Rated current (A)
Pr.05-35	Rated power (kW)
Pr.05-36	Rated rotor speed (rpm)
Pr.05-37	Number of motor poles (poles)
Pr.05-38	System inertia for PM (kg-cm^2)

4. PM parameter auto-tuning:

   Set Pr.05-00 = 5 [Rolling auto-tuning for PM (without load)] or 13 (Static auto-tuning for PM), and press "RUN" key to finish motor auto-tuning, then you get the following parameters:

Parameter	Description
Pr.05-39	Stator resistance for a permanent magnet motor (Ω)
Pr.05-40	Permanent magnet motor Ld (mH)
Pr.05-41	Permanent magnet motor Lq (mH)
Pr.05-43	Ke parameter of a permanent magnet motor ($V_{phase \cdot rms}$ / krpm) (When Pr.05-00 = 5, the Ke parameter is measured based on the actual motor rotation.) (When Pr.05-00 = 13, the Ke parameter is automatically calculated based on the motor power, current and rotor speed.)

   If an auto-tuning error (AUE) occurs, refer to Section 14 "Error Codes and Descriptions" for further treatment.

AUE Fault code	Description
AUE (40)	Auto-tuning error
AUE 1 (142)	Auto-tuning error 1 (no feedback current error)
AUE 2 (143)	Auto-tuning error 2 (motor phase loss error)

5. Set control mode

   Set Pr.00-11 = 6 PM Sensorless FOC control mode

6. After auto-tuning, cycle the power.

7. Measure the initial magnetic pole angle of PM

   Set Pr.10-53 PM initial rotor position detection method:

   0: Disable

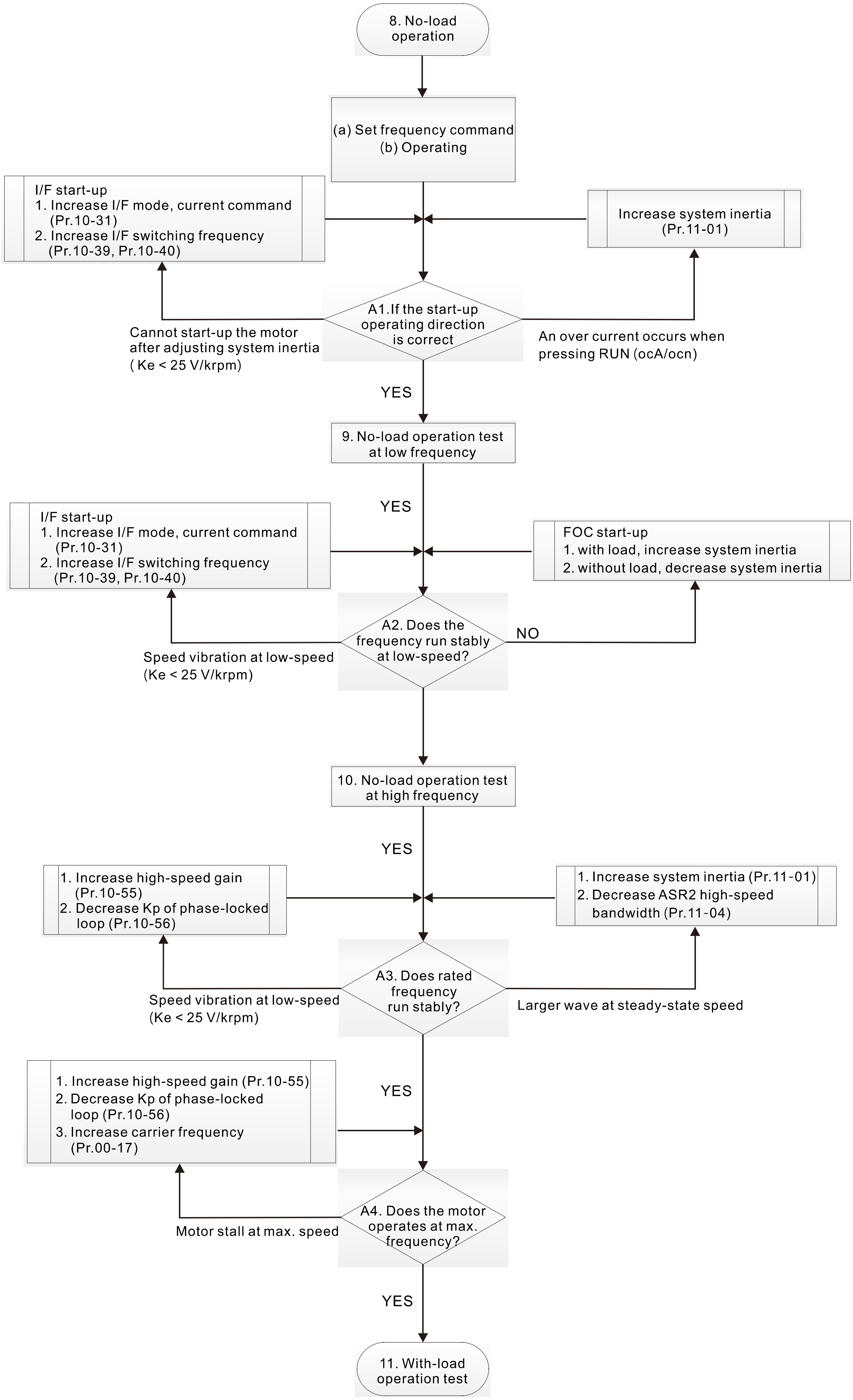
   1: Using I/F current command (Pr.10-31) to attract the rotor to zero degrees

   2: High frequency injection

   3: Pulse injection

   (Set "2" for IPM; set "3" for SPM; set "1" when setting "2" and "3" are not enough)

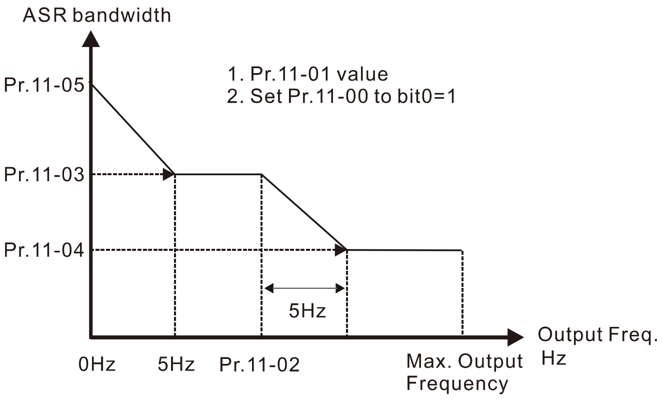
II. PM Sensorless FOC Mode – No load / Light-load Adjustment


8. No-load operation
(a) Set frequency command
(b) Operating
I/F start-up
1. Increase I/F mode, current command (Pr.10-31)
2. Increase I/F switching frequency (Pr.10-39, Pr.10-40)
Increase system inertia (Pr.11-01)
A1.If the start-up operating direction is correct
Cannot start-up the motor after adjusting system inertia (Ke < 25 V/krpm)
An over current occurs when pressing RUN (ocA/ocn)
YES
9. No-load operation test at low frequency
YES
I/F start-up
1. Increase I/F mode, current command (Pr.10-31)
2. Increase I/F switching frequency (Pr.10-39, Pr.10-40)
FOC start-up
1. with load, increase system inertia
2. without load, decrease system inertia
A2. Does the frequency run stably at low-speed?
Speed vibration at low-speed (Ke < 25 V/krpm)
NO
10. No-load operation test at high frequency
YES
1. Increase high-speed gain (Pr.10-55)
2. Decrease Kp of phase-locked loop (Pr.10-56)
1. Increase system inertia (Pr.11-01)
2. Decrease ASR2 high-speed bandwidth (Pr.11-04)
A3. Does rated frequency run stably?
Speed vibration at low-speed (Ke < 25 V/krpm)
Larger wave at steady-state speed
1. Increase high-speed gain (Pr.10-55)
2. Decrease Kp of phase-locked loop (Pr.10-56)
3. Increase carrier frequency (Pr.00-17)
YES
A4. Does the motor operates at max. frequency?
Motor stall at max. speed
YES
11. With-load operation test

📖 No-load / Light-load Operation Adjustment

8. Start the motor without load
   (a) Set Pr.11-00 = 1 Auto-tuning for ASR and APR
   (b) Start the motor without load, and operates the motor to 1/2 of rated rotor speed
   A1. If the start direction is wrong or starting rotation is not smooth (ocA), adjust Pr.11-01 (System inertia). When the Ke parameter (Pr.05-43) is < 25 V, increase Pr.10-31 (I/F mode, current command) or Pr.10-39, Pr.10-40 (Switch the frequency from I/F mode to PM Sensorless mode).
   A2. If the motor starts up with a reverse direction, but operates with a correct direction, adjust Pr.10-52 (Injection magnitude) when using High frequency injection to detect the PM initial rotor position (Pr.10-53 = 2); increase Pr.10-42 (Initial angle detection pulse value) to improve the accuracy of angle detection when using Pulse injection to detect the PM initial rotor position (Pr.10-53 = 3).
9. Acceleration test with no-load / light-load
   A3. Accelerate the motor to the rated frequency, and check if it operates stably.
      a. If the motor output frequency presents steady state speed wave, increase Pr.11-04 (ASR2 high-speed bandwidth) or Pr.11-01 (Per-unit of system inertia).
      b. If the motor output frequency presents large fluctuations or diverges, increase Pr.10-55 (Magnetic flux linkage estimate high-speed gain) or decrease Pr.10-56 (Kp of phase-locked loop).
   A4. Accelerate the motor to the maximum frequency, and check if it operates stably.
   If the motor stalls at the maximum operation speed, increase Pr.10-55 (Magnetic flux linkage estimate high-speed gain) and Pr.00-17 (Carrier frequency), or decrease Pr.10-56 (Kp of phase-locked loop).

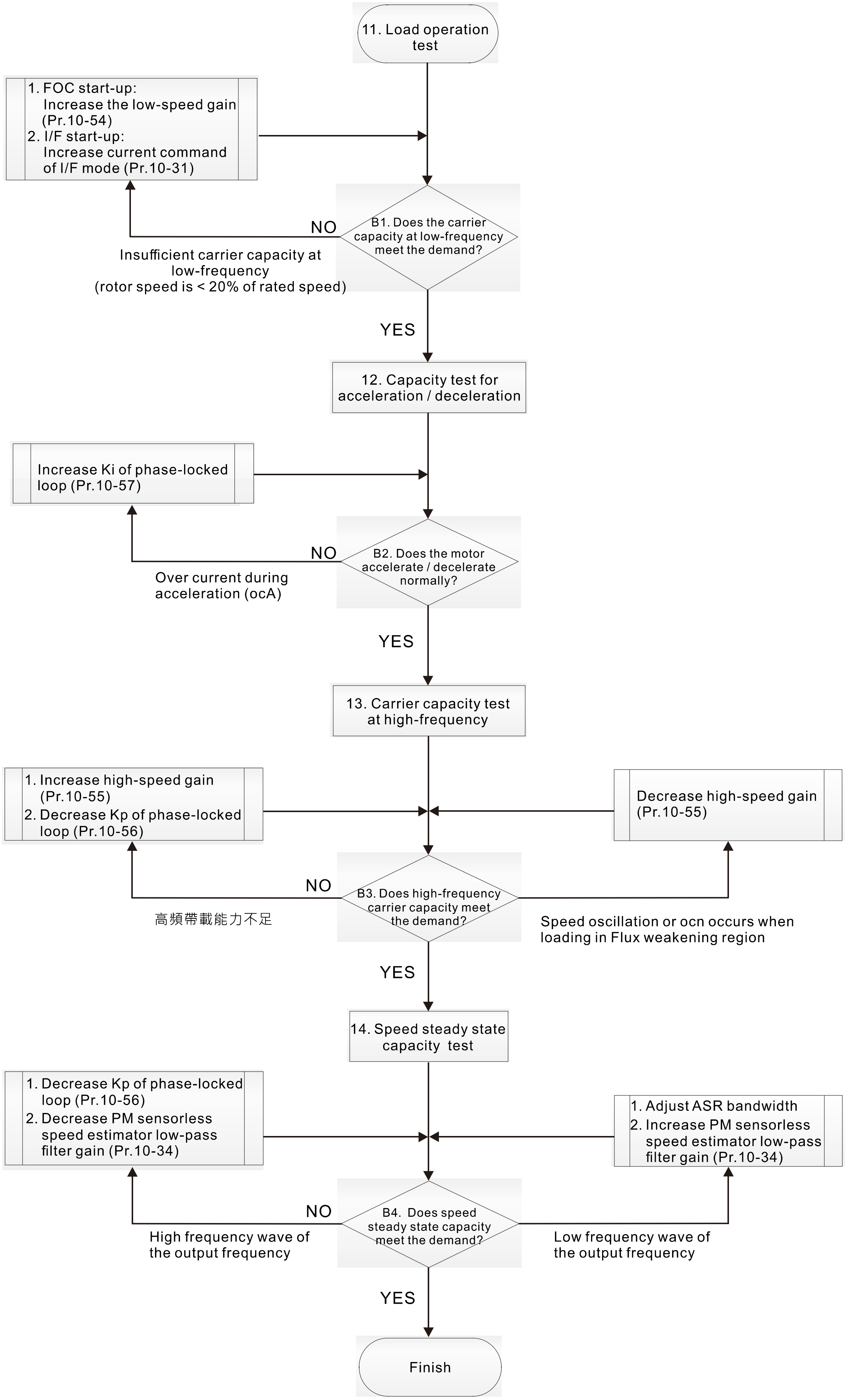
※ Setting curve for speed regulator (ASR) and related parameters:



ASR adjustment- auto gain

Parameter	Description	Default
Pr.11-00	System control	0
Pr.11-01	Per-unit of system inertia	256
Pr.11-02	ASR1 / ASR2 switch frequency (set the switch frequency > Pr.10-39)	7 Hz
Pr.11-03	ASR1 low-speed bandwidth	10 Hz
Pr.11-04	ASR2 high-speed bandwidth	10 Hz
Pr.11-05	Zero-speed bandwidth	10 Hz

III. PM Sensorless FOC Mode – Load Starting Adjustment


11. Load operation test
1. FOC start-up: Increase the low-speed gain (Pr.10-54)
2. I/F start-up: Increase current command of I/F mode (Pr.10-31)
B1. Does the carrier capacity at low-frequency meet the demand?
NO
Insufficient carrier capacity at low-frequency (rotor speed is < 20% of rated speed)
YES
12. Capacity test for acceleration / deceleration
Increase Ki of phase-locked loop (Pr.10-57)
B2. Does the motor accelerate / decelerate normally?
NO
Over current during acceleration (ocA)
YES
13. Carrier capacity test at high-frequency
1. Increase high-speed gain (Pr.10-55)
2. Decrease Kp of phase-locked loop (Pr.10-56)
Decrease high-speed gain (Pr.10-55)
B3. Does high-frequency carrier capacity meet the demand?
NO
高頻帶載能力不足
Speed oscillation or ocn occurs when loading in Flux weakening region
YES
14. Speed steady state capacity test
1. Decrease Kp of phase-locked loop (Pr.10-56)
2. Decrease PM sensorless speed estimator low-pass filter gain (Pr.10-34)
1. Adjust ASR bandwidth
2. Increase PM sensorless speed estimator low-pass filter gain (Pr.10-34)
B4. Does speed steady state capacity meet the demand?
NO
High frequency wave of the output frequency
Low frequency wave of the output frequency
YES
Finish

🕮 Load Operation Adjustment and Steady State Adjustment at Constant Speed

11. Load operation test
    - B1. Low-frequency carrier capacity test (the output frequency is < 20% of rated speed):
        - a. If the frequency switch from I/F mode to PM Sensorless is zero (Pr.10-39 = 0 Hz), increase Pr.10-54 (Magnetic flux linkage estimate low-speed gain).
        - b. If the output frequency is less than Pr.10-39 (Frequency to switch from I/F mode to PM Sensorless), increase Pr.10-31 (I/F mode, current command).
    - B2. Carrier capacity test during acceleration

      In heavy load operation, accelerate the motor to rated speed according to the acceleration time:
        - a. If the motor responds too slowly or an over current occurs during the acceleration, increase Pr.10-57 (Ki phase-locked loop).
12. Steady state test at constant speed, check if the motor operates stably at constant speed.
    - a. If the motor's output frequency presents periodic low-frequency wave, increase Pr.10-34 (PM sensorless speed estimator low-pass filter gain), or adjust the ASR parameters.
    - b. If the motor's output frequency presents extreme vibration, decrease Pr.10-34 (PM sensorless speed estimator low-pass filter gain) or Pr.10-56 (Kp phase-locked loop).

PM Sensorless FOC Mode Adjustment Parameters

Refer to Section 12-1 Description of Parameter Settings for more details.

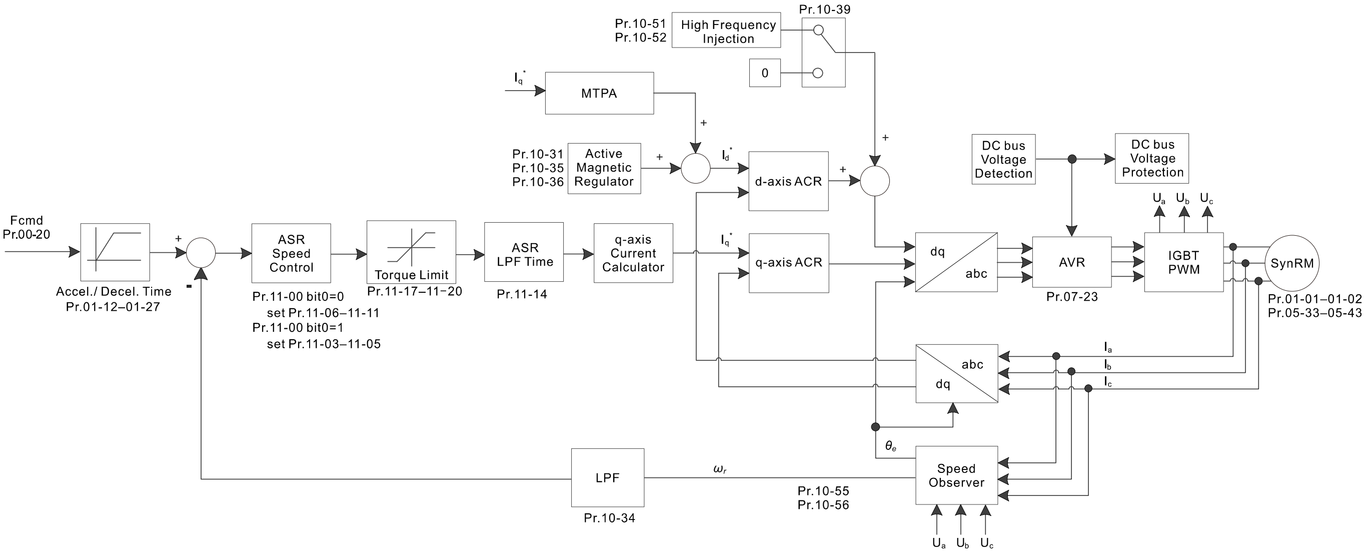
Parameter	Description	Unit	Default	Settings
Pr.10-31	I/F mode, current command	%	40	150
Pr.10-34	PM sensorless speed estimator low-pass filter gain	NA	1.00	0.00–655.35
Pr.10-39	Frequency to switch from I/F mode to PM sensorless mode	Hz	20.0	0.0–599.0
Pr.10-40	Frequency to switch from PM sensorless mode to I/F mode	Hz	20.0	0.0–599.0
Pr.10-54	Magnetic flux linkage estimate low-speed gain (applied to 230V / 460V models)	%	100	10–1000
Pr.10-55	Magnetic flux linkage estimate high-speed gain (applied to 230V / 460V models)	%	100	10–1000
Pr.10-56	Kp of phase-locked loop (applied to 230V / 460V models)	%	100	10–1000
Pr.10-57	Ki of phase-locked loop (applied to 230V / 460V models)	%	100	10–1000
Initial Angle Estimating Parameters				
Pr.10-42	Initial angle detection pulse value	NA	0.5	0.0–3.0
Pr.10-51	Injection frequency (applicable when Pr.10-53 = 2)	Hz	500	0–1200
Pr.10-52	Injection magnitude (applicable when Pr.10-53 = 2)	V	15.0/30.0	0.0–200.0
Pr.10-53	PM initial rotor position detection method 0: Disable 1: Force attracting the rotor to zero degrees 2: High frequency injection 3: Pulse injection	NA	0	0–3
Motor Performance Control Parameters				
Pr.11-00	System control	bit	0	0–8

Parameter	Description	Unit	Default	Settings
Pr.11-02	ASR1 / ASR2 switch frequency	Hz	7.0	5.0–599.0
Pr.11-03	ASR1 low-speed bandwidth	Hz	10	1–100 (PM) 1–40 (IM)
Pr.11-04	ASR2 high-speed bandwidth	Hz	10	1–100 (PM) 1–40 (IM)
Pr.11-05	Zero-speed bandwidth	Hz	10	1–100 (PM) 1–40 (IM)

12-2-3 SynRM FOC Sensorless Vector Control Mode (SynRM Sensorless) Pr.00-11 = 8

1. Control diagram

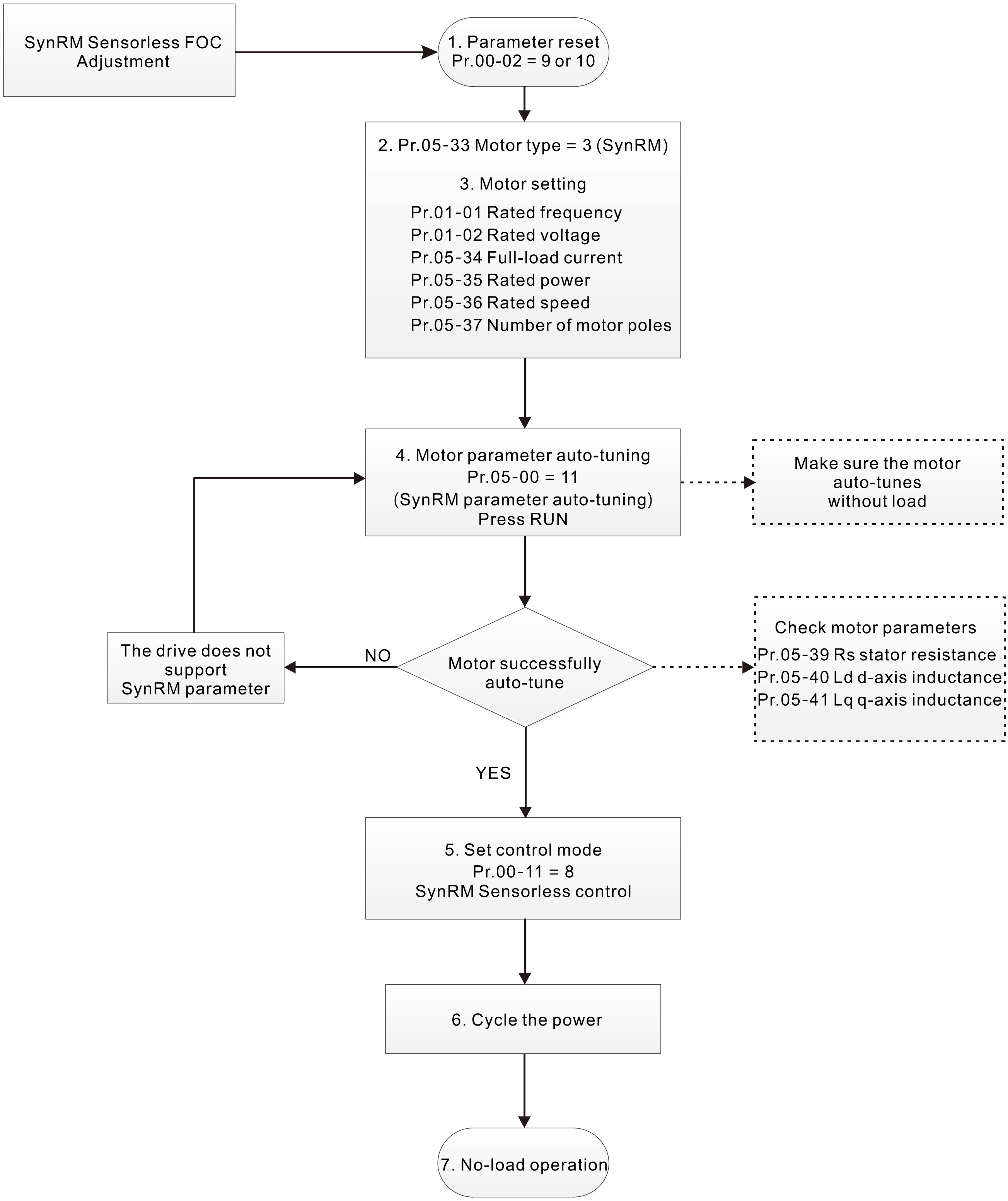
SynRM Sensorless (applied to CP2000 V2.07 and above)



2. SynRM Sensorless Adjustment Procedure

(* the number marked on the procedure corresponds the number of following explanations)

I. Adjustment for SynRM Sensorless Parameters


SynRM Sensorless FOC Adjustment
1. Parameter reset Pr.00-02 = 9 or 10
2. Pr.05-33 Motor type = 3 (SynRM)
3. Motor setting
Pr.01-01 Rated frequency
Pr.01-02 Rated voltage
Pr.05-34 Full-load current
Pr.05-35 Rated power
Pr.05-36 Rated speed
Pr.05-37 Number of motor poles
4. Motor parameter auto-tuning Pr.05-00 = 11 (SynRM parameter auto-tuning) Press RUN
Make sure the motor auto-tunes without load
Motor successfully auto-tune
NO
The drive does not support SynRM parameter
Check motor parameters
Pr.05-39 Rs stator resistance
Pr.05-40 Ld d-axis inductance
Pr.05-41 Lq q-axis inductance
YES
5. Set control mode Pr.00-11 = 8 SynRM Sensorless control
6. Cycle the power
7. No-load operation

📖 Motor Parameters Adjustment

1. Parameter reset:

   Pr.00-02 = 9 (50 Hz) or 10 (60 Hz), reset parameter to the default value

2. Select motor type:

   Pr.05-33 = 3 (SynRM)

3. Motor nameplate parameter setting:

Parameter	Description
Pr.01-01	Rated frequency (Hz)
Pr.01-02	Rated voltage (V_{AC})
Pr.05-34	Rated current (A)
Pr.05-35	Rated power (kW)
Pr.05-36	Rated rotor speed (rpm)
Pr.05-37	Number of motor poles (poles)

4. Motor parameter auto-tuning:

   Set Pr.05-00 = 11 [SynRM parameter auto-tuning (without load)] and press "RUN" key to finish motor auto-tuning, then you get the following parameters:

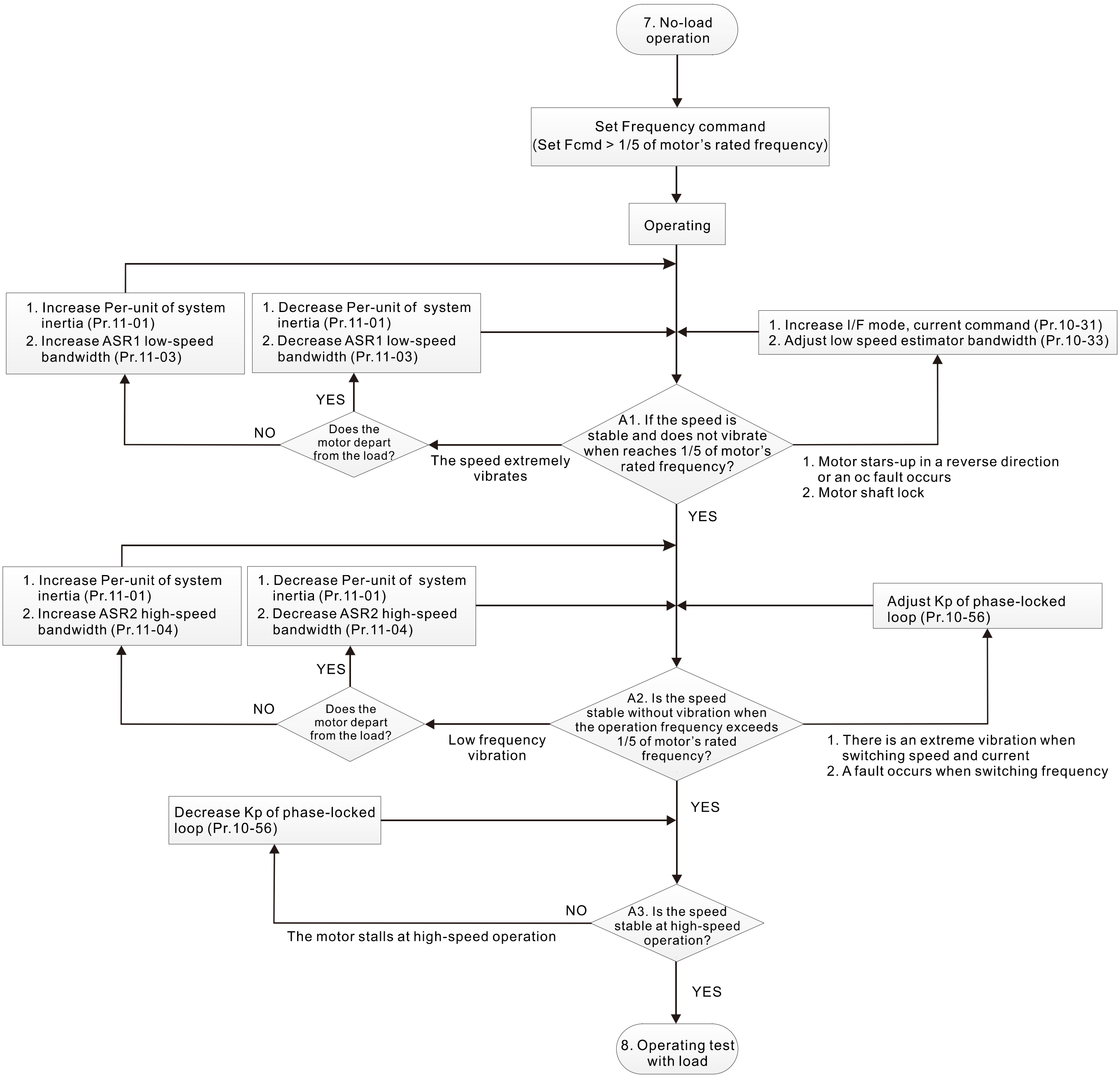
Parameter	Description
Pr.05-39	Stator resistance for a permanent magnet motor (Ω)
Pr.05-40	Permanent magnet motor Ld (mH)
Pr.05-41	Permanent magnet motor Lq (mH)

5. Set control mode:

   Set Pr.00-11 = 8 (SynRM Sensorless)

6. After auto-tuning, cycle the power.

II. SynRM Sensorless No-load Adjustment Procedure


7. No-load operation
Set Frequency command (Set Fcmd > 1/5 of motor's rated frequency)
Operating
1. Increase Per-unit of system inertia (Pr.11-01)
2. Increase ASR1 low-speed bandwidth (Pr.11-03)
1. Decrease Per-unit of system inertia (Pr.11-01)
2. Decrease ASR1 low-speed bandwidth (Pr.11-03)
1. Increase I/F mode, current command (Pr.10-31)
2. Adjust low speed estimator bandwidth (Pr.10-33)
YES
NO
Does the motor depart from the load?
The speed extremely vibrates
A1. If the speed is stable and does not vibrate when reaches 1/5 of motor's rated frequency?
1. Motor stars-up in a reverse direction or an oc fault occurs
2. Motor shaft lock
YES
1. Increase Per-unit of system inertia (Pr.11-01)
2. Increase ASR2 high-speed bandwidth (Pr.11-04)
1. Decrease Per-unit of system inertia (Pr.11-01)
2. Decrease ASR2 high-speed bandwidth (Pr.11-04)
Adjust Kp of phase-locked loop (Pr.10-56)
YES
NO
Does the motor depart from the load?
Low frequency vibration
A2. Is the speed stable without vibration when the operation frequency exceeds 1/5 of motor's rated frequency?
1. There is an extreme vibration when switching speed and current
2. A fault occurs when switching frequency
Decrease Kp of phase-locked loop (Pr.10-56)
YES
NO
The motor stalls at high-speed operation
A3. Is the speed stable at high-speed operation?
YES
8. Operating test with load

📖 No-load Operation Adjustment

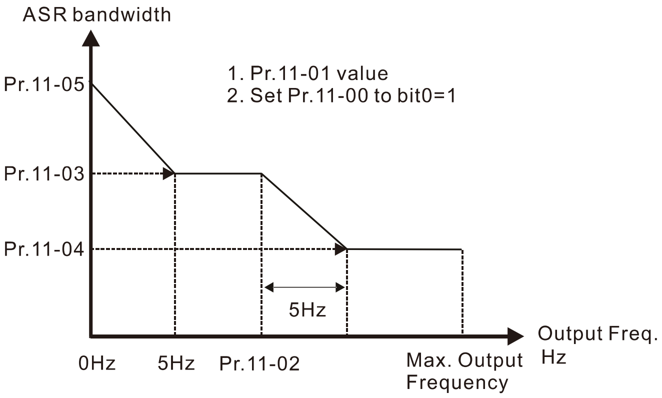
7. Start the motor without load

A1. Start the motor without load, refer to the following adjustment before the operation frequency reaches 1/5 or motor's rated frequency:

a. If the motor starts in a wrong direction, the starting rotation is not smooth (ocA) or there is motor shaft lock, adjust Pr.10-31 (I/F mode, current command) and Pr.10-33 (PM FOC sensorless low-speed estimator bandwidth).

b. When there is an extreme vibration of the motor speed, adjust Pr.11-01 (Per-unit of system inertia) and Pr.11-03 (ASR1 low-speed bandwidth) depending on whether the motor departs from the load.

※ Setting curve for speed regulator (ASR) and related parameters:



ASR adjustment- auto gain

Parameter	Description	Default
Pr.11-00	System control	0
Pr.11-01	Per-unit of system inertia	256
Pr.11-02	ASR1 / ASR2 switch frequency (set the switch frequency > 1/5 of motor's rated frequency)	7 Hz
Pr.11-03	ASR1 low-speed bandwidth	10 Hz
Pr.11-04	ASR2 high-speed bandwidth	10 Hz
Pr.11-05	Zero-speed bandwidth	10 Hz

A2. The operation frequency exceeds the switch frequency for Pr.10-39

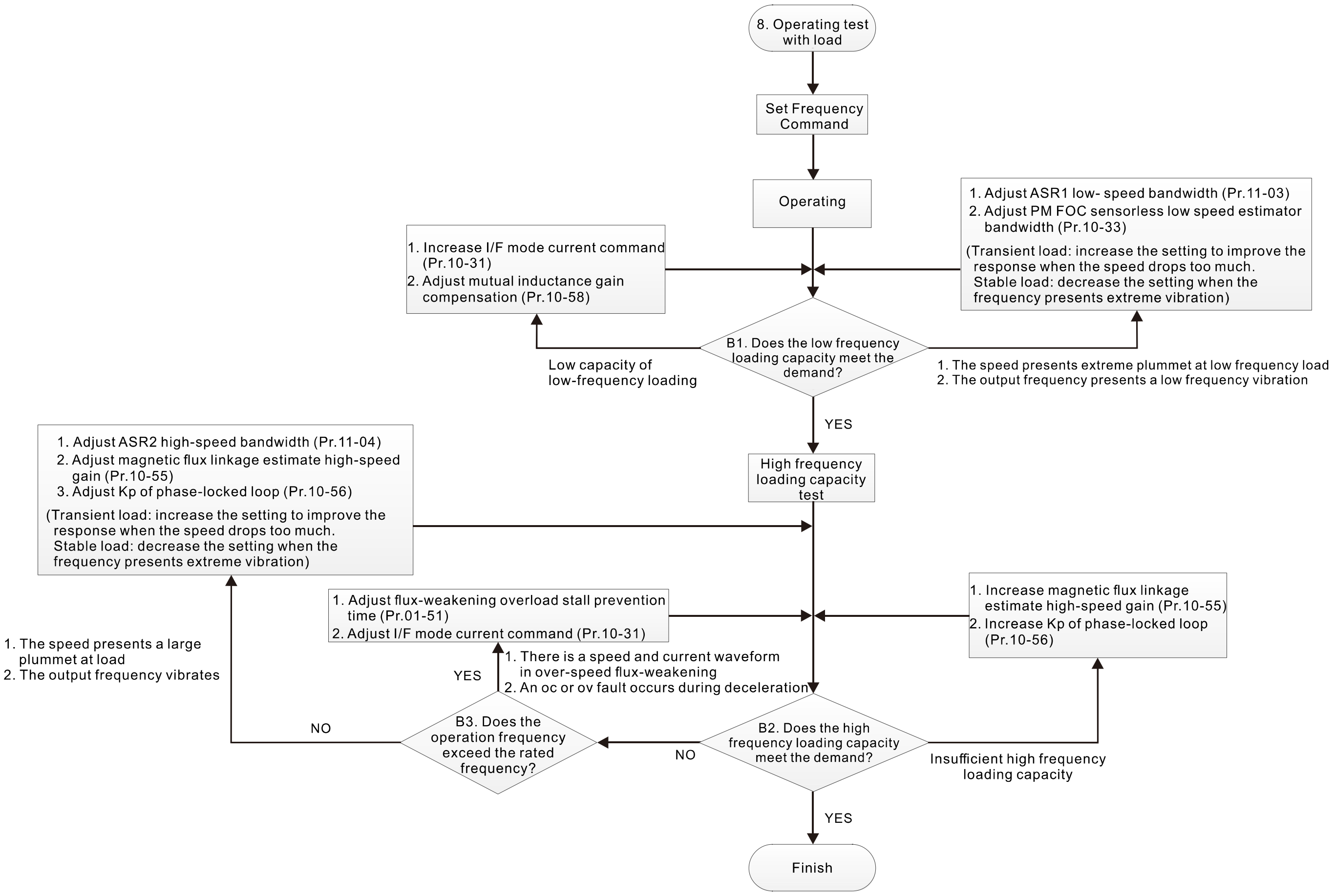
a. If there is an extreme vibration of speed and current when switching frequency, or a fault occurs during the switching process, adjust Pr.10-56 (Kp of phase-locked loop).

b. Both of adjustments for Pr.10-55 (Magnetic flux linkage estimate high-speed gain) and Pr.10-56 (Kp of phase-locked loop) affect the performance of the speed estimator. Adjust only Pr.10-56 in no-load operation.

c. When there is a low-frequency vibration of speed during motor's operation, adjust Pr.11-01 (Per-unit of system inertia) and Pr.11-04 (ASR2 high-speed bandwidth) depending on whether the motor departs from the load.

A3. Observe whether the motor operates stably when accelerates to the maximum frequency If the motor stalls at the maximum operation speed, decrease Pr.10-56 (Kp phase-locked loop)

III. SynRM Sensorless Start-up with Load Adjustment


8. Operating test with load
Set Frequency Command
Operating
1. Increase I/F mode current command (Pr.10-31)
2. Adjust mutual inductance gain compensation (Pr.10-58)
1. Adjust ASR1 low- speed bandwidth (Pr.11-03)
2. Adjust PM FOC sensorless low speed estimator bandwidth (Pr.10-33)
(Transient load: increase the setting to improve the response when the speed drops too much.
Stable load: decrease the setting when the frequency presents extreme vibration)
B1. Does the low frequency loading capacity meet the demand?
Low capacity of low-frequency loading
1. The speed presents extreme plummet at low frequency load
2. The output frequency presents a low frequency vibration
YES
High frequency loading capacity test
1. Adjust ASR2 high-speed bandwidth (Pr.11-04)
2. Adjust magnetic flux linkage estimate high-speed gain (Pr.10-55)
3. Adjust Kp of phase-locked loop (Pr.10-56)
(Transient load: increase the setting to improve the response when the speed drops too much.
Stable load: decrease the setting when the frequency presents extreme vibration)
1. Adjust flux-weakening overload stall prevention time (Pr.01-51)
2. Adjust I/F mode current command (Pr.10-31)
1. Increase magnetic flux linkage estimate high-speed gain (Pr.10-55)
2. Increase Kp of phase-locked loop (Pr.10-56)
1. The speed presents a large plummet at load
2. The output frequency vibrates
YES
1. There is a speed and current waveform in over-speed flux-weakening
2. An oc or ov fault occurs during deceleration
NO
B3. Does the operation frequency exceed the rated frequency?
NO
B2. Does the high frequency loading capacity meet the demand?
Insufficient high frequency loading capacity
YES
Finish

🕮 Load Operation Adjustment

8. Operation test with load

B1. Low-frequency loading capacity test

a. If the low-frequency loading performance is low, increase Pr.10-31 (I/F mode, current command) and Pr.10-58 (mutual inductance compensation gain).

b. If the low-frequency loading speed presents large plummet, or the output frequency presents low-frequency vibration, adjust Pr.11-03 (ASR1 low-speed bandwidth) and Pr.10-33 (PM FOC sensorless speed estimator bandwidth). Increase the setting to improve the response when the speed drops too much at transient load. Decrease the setting if the frequency presents an extreme vibration at stable load.

B2. High frequency loading capacity test

a. If the high frequency loading performance is insufficient, increase Pr.10-55 (Magnetic flux linkage estimate high-speed gain) and Pr.10-56 (Kp of phase-locked loop).

b. If there is large plummet of loading speed, or the output frequency vibrates, adjust Pr.11-04 (ASR2 high-speed bandwidth), Pr.10-55 (Magnetic flux linkage estimate high-speed gain) and Pr.10-56 (Kp of phase-locked loop). Increase the setting to improve the response when the speed drops too much at transient load. Decrease the setting if the frequency presents an extreme vibration at stable load.

B3. Operation frequency exceeds the rated frequency

a. When there is a waveform of speed and current in the flux-weakening zone, and an oc or ov fault occurs during the deceleration, adjust Pr.01-51 (Flux-weakening overload stall prevention time) and Pr.10-31 (I/F mode current command).

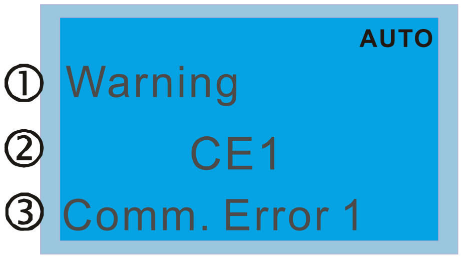
SynRM Sensorless Mode Adjustment Parameters

Refer to Section 12-1 Description of Parameter Settings for more details.

Parameter	Description	Unit	Default	Settings
00-11	Speed control mode		0	0–8
00-17	Carrier frequency	kHz	4	4–8
01-51	Flux-weakening overload stall prevention time	sec.	1.00	0.00–600.00
05-00	Motor parameter auto-tuning		0	0–13
05-33	Induction motor or permanent magnet synchronous AC motor selection		3	0–3
05-34	Full-load current for a permanent magnet synchronous AC motor / reluctance motor	Amps	NA	NA
05-35	Rated power for a permanent magnet synchronous AC motor / reluctance motor	kW	NA	0–655.35
05-36	Rated speed for a permanent magnet synchronous AC motor / reluctance motor	rpm	NA	0–65535
05-37	Number of poles for a permanent magnet synchronous AC motor / reluctance motor		NA	0–65535
05-38	System inertia for a permanent magnet synchronous AC motor / reluctance motor	kg-cm^2	NA	0.0–6553.5
05-39	Stator resistance for a permanent magnet synchronous AC motor / reluctance motor	ohm	0.000	0.000–65.535
05-40	Permanent magnet synchronous AC motor / reluctance motor Ld	mH	0.00	0.00–655.35

Parameter	Description	Unit	Default	Settings
05-41	Permanent magnet synchronous AC motor / reluctance motor Lq	mH	0.00	0.00–655.35
07-12	Speed tracking during start-up		0	0–3
10-08	Treatment for speed observer feedback fault		2	0–2
10-09	Detection time of speed observer feedback fault	sec.	1.0	0.0–10.0
10-10	Speed observer stall level	%	115	0–120
10-11	Detection time of speed observer stall	sec.	0.1	0.0–2.0
10-12	Speed observer stall action		2	0–2
10-13	Speed observer slip range	%	50	0–0
10-14	Detection time of speed observer slip	sec.	0.5	0.0–10.0
10-15	Speed observer stall and slip error action		2	0–2
10-31	I/F mode, current command	%	15	0–150
10-33	PM FOC sensorless speed estimator bandwidth (low speed)		1.00	0.01–3.00
10-34	PM sensorless speed estimator low-pass filter gain		1.00	0.00–10.00
10-35	AMR (Kp) gain		0.4	0.00–3.00
10-36	AMR (Ki) gain		2.00	0.00–3.00
10-39	Frequency to switch from I/F mode to PM sensorless mode	Hz	10.00	0.0–599.00
10-51	Injection frequency	Hz	400	0–1200
10-52	Injection magnitude	%	30	10–50
10-55	PM initial rotor position detection method		1.0	0.1–3.0
10-56	Kp of phase-locked loop	Hz	10	5–50
10-58	Mutual inductance gain compensation		1.00	0.00–655.35
11-00	System control		0x201h	0–65535
11-01	Per-unit of system inertia	pu	256	0–65535
11-02	ASR1 / ASR2 switch frequency	Hz	10.00	5.00–599.00
11-03	ASR1 low-speed bandwidth	Hz	5	1–30
11-04	ASR2 high-speed bandwidth	Hz	5	1–30
11-05	Zero-speed bandwidth	Hz	5	1–30
11-17	Forward motor torque limit Quadrant I	%	200	0–500
11-18	Forward regenerative torque limit Quadrant II	%	200	0–500
11-19	Reverse motor torque limit Quadrant III	%	200	0–500
11-20	Reverse regenerative torque limit Quadrant IV	%	200	0–500

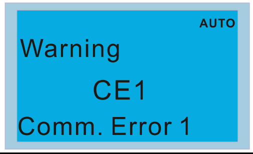
Chapter 13 Warning Codes

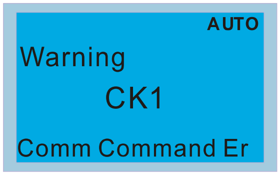


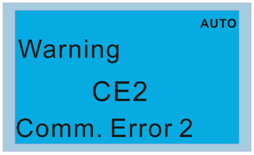
① Display error signal

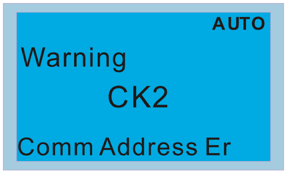
② Abbreviate error code

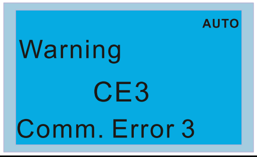
③ Display error description

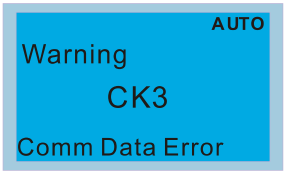
<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>1</td><td> </td><td>Communication error 1 (CE1)</td><td>RS-485 Modbus illegal function code</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When the function code is not 03, 06, 10 and 63</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">“Warning” occurs when Pr.09-02 = 0 and the motor drive keeps running. The drive resets automatically when receiving the correct function code.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect communication command from upper unit</td><td colspan="2">Check if the communication command is correct.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td colspan="2">Different communication setting from the upper unit</td><td colspan="2">Check if the setting for Pr.09-02 is the same as the setting for the upper unit.</td></tr>
<tr><td colspan="2">Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

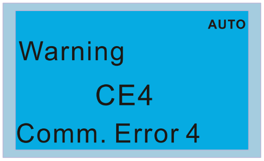
<table>
<tr><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td> </td><td>Communication command error 1 (CK1)</td><td>Keypad communication data, illegal function code
(Keypad auto-detects this error and displays it.)</td></tr>
<tr><th colspan="3">Action and Reset</th></tr>
<tr><td>Action condition</td><td colspan="2">When the function code is not 03, 06, 10 and 63</td></tr>
<tr><td>Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td>Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td>Reset method</td><td colspan="2">Remove the keypad and then reconnect it to the motor drive.</td></tr>
<tr><td>Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td>Record</td><td colspan="2">N/A</td></tr>
<tr><th>Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td>Incorrect communication command from keypad</td><td colspan="2">Keypad and the motor drive don’t communicate properly. It is recommended to remove the keypad and then reconnect it to the motor drive.</td></tr>
<tr><td>Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td>Different communication setting from keypad</td><td colspan="2">Check if the Baud rate = 19200 bps. Format = RTU8, N, 2.</td></tr>
<tr><td>Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>2</td><td>
AUTO
Warning
CE2
Comm. Error 2</td><td>Communication error 2 (CE2)</td><td>RS-485 Modbus illegal data address</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When the input data address is incorrect</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">“Warning” occurs when Pr.09-02 = 0 and the motor drive keeps running. The drive resets automatically when receiving the correct data address.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect communication command from upper unit</td><td colspan="2">Check if the communication command is correct.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td colspan="2">Different communication setting from the upper unit</td><td colspan="2">Check if the setting for Pr.09-02 is the same as the setting for the upper unit.</td></tr>
<tr><td colspan="2">Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

<table>
<tr><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>
AUTO
Warning
CK2
Comm Address Er</td><td>Communication address error (CK2)</td><td>Keypad communication data, illegal data address
(Keypad auto-detects this error and displays it.)</td></tr>
<tr><th colspan="3">Action and Reset</th></tr>
<tr><td>Action condition</td><td colspan="2">When the input data address is incorrect</td></tr>
<tr><td>Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td>Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td>Reset method</td><td colspan="2">Remove the keypad and then reconnect it to the motor drive.</td></tr>
<tr><td>Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td>Record</td><td colspan="2">N/A</td></tr>
<tr><th>Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td>Incorrect communication command from keypad</td><td colspan="2">Keypad and the motor drive don’t communicate properly. It is recommended to remove the keypad and then reconnect it to the motor drive.</td></tr>
<tr><td>Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td>Different communication setting from keypad</td><td colspan="2">Check if the Baud rate = 19200 bps. Format = RTU8, N, 2.</td></tr>
<tr><td>Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

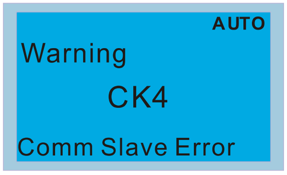
<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>3</td><td>AUTO
Warning
CE3
Comm. Error 3</td><td>Communication error 3 (CE3)</td><td>RS-485 Modbus illegal data value</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When the length of communication data is too long</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">“Warning” occurs when Pr.09-02 = 0 and the motor drive keeps running. The drive resets automatically when receiving the correct communication data value.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect communication command from upper unit</td><td colspan="2">Check if the communication command is correct.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td colspan="2">Different communication setting from upper unit</td><td colspan="2">Check if the setting for Pr.09-02 is the same as the setting for the upper unit.</td></tr>
<tr><td colspan="2">Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

<table>
<tr><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>AUTO
Warning
CK3
Comm Data Error</td><td>Communication data error (CK3)</td><td>Keypad communication data, illegal data value
(Keypad auto-detects this error and displays it.)</td></tr>
<tr><th colspan="3">Action and Reset</th></tr>
<tr><td>Action condition</td><td colspan="2">When the length of communication data is too long</td></tr>
<tr><td>Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td>Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td>Reset method</td><td colspan="2">Remove the keypad and then reconnect it to the motor drive.</td></tr>
<tr><td>Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td>Record</td><td colspan="2">N/A</td></tr>
<tr><th>Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td>Incorrect communication command from keypad</td><td colspan="2">Keypad and the motor drive don’t communicate properly. It is recommended to remove the keypad and then reconnect it to the motor drive.</td></tr>
<tr><td>Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td>Different communication setting from keypad</td><td colspan="2">Check if the Baud rate = 19200 bps. Format = RTU8, N, 2.</td></tr>
<tr><td>Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

ID No.	Display on LCD Keypad	Warning Name	Description
4		Communication error 4 (CE4)	RS-485 Modbus data is written to read-only address

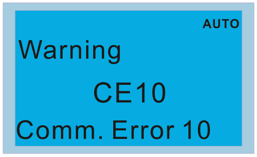
Action and Reset	
Action condition	When the data is written to read-only address
Action time	Immediately act
Warning setting parameter	N/A
Reset method	"Warning" occurs when Pr.09-02 = 0 and the motor drive keeps running. The drive resets automatically when receiving the correct written address of communication data.
Reset condition	Immediately reset
Record	N/A

Cause	Corrective Actions
Incorrect communication command from upper unit	Check if the communication command is correct.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from the upper unit	Check if the setting for Pr.09-02 is the same as the setting for the upper unit.
Disconnection or bad connection of the cable	Check the cable and replace it if is necessary.

Display on LCD Keypad	Warning Name	Description
	Communication slave error (CK4)	Keypad communication data is written to read-only address. (Keypad auto-detects this error and displays it.)

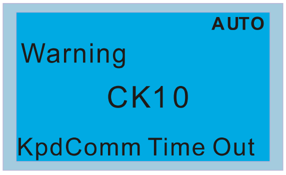
Action and Reset	
Action condition	When the data is written to read-only address
Action time	Immediately act
Warning setting parameter	N/A
Reset method	Remove the keypad and then reconnect it to the motor drive.
Reset condition	Immediately reset
Record	N/A

Cause	Corrective Actions
Incorrect communication command from keypad	Keypad and the motor drive don't communicate properly. It is recommended to remove the keypad and then reconnect it to the motor drive. If the problem persists after reconnecting the keypad, pay attention to the motor drive status. For example: Motor drive might reset to default setting during operation or while enabling PLC function.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from keypad	Check if the Baud rate = 19200 bps. Format = RTU8, N, 2.
Disconnection or bad connection of the cable	Check the cable and replace it if is necessary.

ID No.	Display on LCD Keypad	Warning Name	Description
5	 AUTO Warning CE10 Comm. Error 10	Communication error 10 (CE10)	RS-485 Modbus transmission time-out

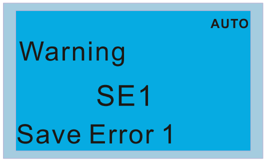
Action and Reset	
Action condition	When the communication time exceeds the detection time of Pr.09-03 communication time-out
Action time	Setting for Pr.09-03
Warning setting parameter	N/A
Reset method	"Warning" occurs when Pr.09-02 = 0 and the motor drive keeps running. The drive resets automatically when receiving the next communication packet.
Reset condition	Immediately reset
Record	N/A

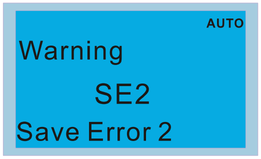
Cause	Corrective Actions
The upper unit does not transmit the communication command within Pr.09-03 setting time	Check if the upper unit transmits the communication command within the setting time for Pr.09-03.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from the upper unit	Check if the setting for Pr.09-02 is the same as the setting for the upper unit.
Disconnection or bad connection of the cable	Check the cable and replace it if necessary.

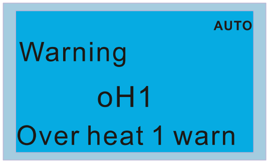
Display on LCD Keypad	Warning Name	Description
 AUTO Warning CK10 KpdComm Time Out	Keypad communication time out (CK10)	Keypad communication data, transmission time-out (Keypad auto-detects this error and displays it.)

Action and Reset	
Action condition	When the communication time exceeds the detection time of Pr.09-03 communication time-out
Action time	Setting for Pr.09-03
Warning setting parameter	N/A
Reset method	Remove the keypad and then reconnect it to the motor drive.
Reset condition	Immediately reset
Record	N/A

Cause	Corrective Actions
Incorrect communication command from keypad	Keypad and the motor drive don't communicate properly. It is recommended to remove the keypad and then reconnect it to the motor drive.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from keypad	Check if the Baud rate = 19200 bps. Format = RTU8, N, 2.
Disconnection or bad connection of the cable	Check the cable and replace it if necessary.

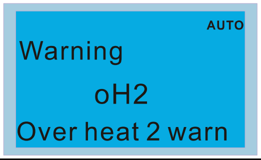
<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>7</td><td>AUTO
Warning
SE1
Save Error 1</td><td>Save error 1
(SE1)</td><td>Keypad COPY error 1: Keypad copy time-out</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">“SE1” warning occurs when the keypad does not transmit the COPY command to the drive, and does not transmit any data to the drive again in 10 ms at the time you copy the parameters to the drive.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">10 ms</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Communication connection error</td><td colspan="2" rowspan="3">SE1: The causes of error are mostly communication problems between the keypad and control board. Potential causes include communication signal interference and the unacceptable communication command to the Slave.
Check if the error occurs randomly, or only occurs when copying certain parameters (the error displays on the upper right corner of the copy page). If you cannot clear the error, please contact Delta.</td></tr>
<tr><td colspan="2">Keypad error</td></tr>
<tr><td colspan="2">Control board error</td></tr>
</table>

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>8</td><td>AUTO
Warning
SE2
Save Error 2</td><td>Save error 2
(SE2)</td><td>Keypad COPY error 2: parameter writing error</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">“SE2” warning occurs when writing the parameters incorrectly at the time you copy parameters to the drive. For example, you copy the new firmware version with added parameters to the drive with old firmware version.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Add new parameters to the new firmware version.</td><td colspan="2">SE2: In this stage, the copied data has been transmitted to the Slave.
The Slave compares and processes the copied data, and then saves the data to the Data ROM. During the process, the data error (should be attribution error) may occur, or the data cannot be saved to EEPROM. At this time, the warning occurs.
It is suggested to check the status of Data ROM and remove the error causes first.
If you cannot clear the error, please contact Delta.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the main circuit, control circuit and the encoder for effective anti-interference performance.</td></tr>
</table>

ID No.	Display on LCD Keypad	Warning Name	Description
9	 AUTO Warning oH1 Over heat 1 warn	IGBT over-heating warning (oH1)	The AC motor drive detects over-heating of IGBT, and over the protection level of oH1 warning. (When Pr.06-15 is higher than the IGBT over-heating level, the drive shows oH1 error without displaying oH1 warning.)

Action and Reset	
Action condition	Pr.06-15
Action time	"oH1" warning occurs when IGBT temperature is higher than Pr.06-15 setting value.
Warning setting parameter	N/A
Reset method	Auto-reset
Reset condition	The drive auto-resets when IGBT temperature is lower than oH1 warning level minus (–) 5°C
Record	N/A

Cause	Corrective Actions
Check if the ambient temperature or temperature inside the cabinet is too high, or if there is obstruction in the ventilation hole of the control cabinet.	1. Check the ambient temperature. 2. Regularly inspect the ventilation hole of the control cabinet. 3. Change the installed place if there are heating objects, such as braking resistors, in the surroundings. 4. Install/ add cooling fan or air conditioner to lower the temperature inside the cabinet.
Check if there is any obstruction on the heat sink or if the fan is running	Remove the obstruction or replace the cooling fan.
Insufficient ventilation space	Increase ventilation space of the drive.
Check if the drive matches the corresponded loading	1. Decrease loading. 2. Decrease the carrier. 3. Replace with a drive with larger capacity.
The drive has run 100% or more of the rated output for a long time	Replace with a drive with larger capacity.

ID No.	Display on LCD Keypad	Warning Name	Description
10	 AUTO Warning oH2 Over heat 2 warn	Board-level component overheating warning (oH2)	The drive has detected over heat of the board-level component

Action and Reset	
Action condition	oH2 error level minus (–) 5°C
Action time	The oH2 warning occurs when the board-level component temperature is higher than oH2 warning level
Warning setting parameter	N/A
Reset method	Auto-reset
Reset condition	The drive auto-resets when the board-level component temperature is lower than oH2 error level minus (–) 10°C
Record	N/A

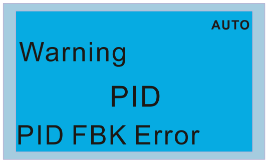
Cause	Corrective Actions
Check if the ambient temperature or temperature inside the cabinet is too high, or if there is obstruction in the ventilation hole of the control cabinet.	1. Check the ambient temperature. 2. Regularly inspect the ventilation hole of the control cabinet. 3. Change the installed place if there are heating objects, such as braking resistors, in the surroundings. 4. Install/ add cooling fan or air conditioner to lower the temperature inside the cabinet.
Check if there is any obstruction on the heat sink or if the fan is running	Remove the obstruction or replace the cooling fan.
Insufficient ventilation space	Increase ventilation space of the drive.
Check if the drive matches the corresponded loading	1. Decrease loading. 2. Decrease the carrier. 3. Replace with a drive with larger capacity.

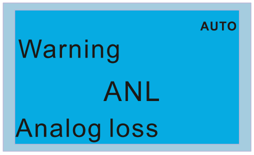
The drive has run 100% or more of the rated output for a long time	Replace with a drive with larger capacity.
Unstable power	Install reactor(s).
The load changes frequently	Reduce the changes of the load.

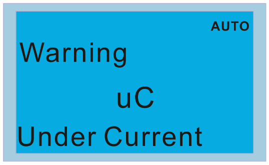
oH1/ oH2 warning level

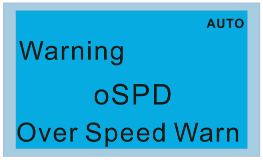
Model	oH1	oH2	oH warning oH1 warning = (Pr. 06-15)
VFD007CP23A-21	110	110	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD015CP23A-21			
VFD022CP23A-21			
VFD037CP23A-21			
VFD055CP23A-21			
VFD075CP23A-21			
VFD110CP23A-21			
VFD150CP23A-21			
VFD185CP23A-21			
VFD220CP23A-21			
VFD300CP23A-21			
VFD370CP23A-00/-21		90	
VFD450CP23A-00/-21			
VFD550CP23A-00/-21			
VFD750CP23A-00/-21			
VFD900CP23A-00/-21			
VFD007CP43A/4EA-21	110	110	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD015CP43B/4EB-21			
VFD022CP43B/4EB-21			
VFD037CP43B/4EB-21			
VFD040CP43A/4EA-21	110	110	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD055CP43B/4EB-21			
VFD075CP43B/4EB-21			
VFD110CP43B/4EB-21			
VFD150CP43B/4EB-21			
VFD185CP43B/4EB-21			
VFD220CP43A/4EA-21			
VFD370CP43B/4EB-21			
VFD450CP43S-00/-21		90	
VFD550CP43S-00/-21			
VFD750CP43B-00/-21			
VFD900CP43A-00/-21			
VFD1100CP43A-00/-21			
VFD1320CP43B-00/-21			
VFD1600CP43A-00/-21			
VFD1850CP43B-00/-21			
VFD2000CP43A-00/-21			
VFD2200CP43A-00/-21			
VFD2500CP43A-00/-21			
VFD2800CP43A-00/-21			
VFD3150CP43A-00 VFD3150CP43C-00/-21			
VFD3550CP43A-00 VFD3550CP43C-00/-21			
VFD4000CP43A-00 VFD4000CP43C-00/-21			
VFD5000CP43A-00 VFD5000CP43C-00/-21		85	
VFD5600CP43A-00 VFD5600CP43C-21	Contact Delta for more information		
VFD6300CP43A-00 VFD6300CP43C-21	Contact Delta for more information		
VFD015CP53A-21	100	85	oH1 Warning = oH1 – 5

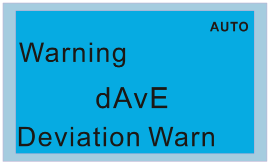
Model	oH1	oH2	oH warning
VFD022CP53A-21			oH1 warning = (Pr. 06-15) oH2 Warning = oH2 – 5
VFD037CP53A-21			
VFD055CP53A-21		70	
VFD075CP53A-21			
VFD110CP53A-21			
VFD150CP53A-21			
VFD185CP63A-21	90	85	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD220CP63A-21			
VFD300CP63A-21			
VFD370CP63A-21			
VFD450CP63A-00/-21	100	65	
VFD550CP63A-00/-21			
VFD750CP63A-00/-21	110		
VFD900CP63A-00/-21			
VFD1100CP63A-00/-21			
VFD1320CP63A-00/-21			
VFD1600CP63A-00/-21			
VFD2000CP63A-00/-21		70	
VFD2500CP63A-00/-21			
VFD3150CP63A-00/-21			
VFD4000CP63A-00/-21			
VFD4500CP63A-00/-21			
VFD5600CP63A-00/-21			
VFD6300CP63A-00/-21			

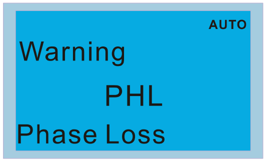
ID No.	Display on LCD Keypad	Warning Name	Description
11	 AUTO Warning PID PID FBK Error	PID feedback error (PID)	PID feedback loss (warning for analog feedback signal; works only when PID enables)
Action and Reset			
Action condition	When the analog input is lower than 4 mA (only detects analog input of 4–20 mA)		
Action time	Pr.08-08		
Warning setting parameter	Pr.08-09 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: Warn and operate at last frequency		
Reset method	Auto	"Warning" occurs when Pr.08-09 = 0 or 3. The "Warning" automatically clears when the feedback signal is larger than 4mA.	
	Manual	"Error" occurs when Pr.08-09 = 1 or 2. You must reset manually.	
Reset condition	Immediately reset		
Record	Records when Pr.08-09 = 1 or 2 ("Error"). Does not record when Pr.08-09 = 3 ("Warning").		
Cause	Corrective Actions		
Loose or broken PID feedback wiring	Tighten the terminals again. Replace with a new cable.		
Feedback device malfunction	Replace with a new feedback device.		
Hardware error	If the PID error still occurs after checking all the wiring, return to the factory for repair.		

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th colspan="2">Warning Name</th><th>Description</th></tr>
<tr><td>12</td><td>
AUTO
Warning
ANL
Analog loss</td><td colspan="2">ACI analog signal loss (AnL)</td><td>Analog input current loss (including all analog 4–20 mA signals)</td></tr>
<tr><td colspan="5">Action and Reset</td></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">When the analog input is lower than 4 mA (only detects analog input 4–20 mA)</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Immediately act</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="3">Pr.03-19
0: Disable
1: Continue operation at the last frequency (warning, keypad displays ANL)
2: Decelerate to 0 Hz (warning, keypad displays ANL)
3: Stop immediately and display ACE</td></tr>
<tr><td colspan="2" rowspan="2">Reset method</td><td>Auto</td><td colspan="2">“Warning” occurs when Pr.03-19 = 1 or 2. The “Warning automatically clears when the analog input signal is larger than 4mA.</td></tr>
<tr><td>Manual</td><td colspan="2">“Error” occurs when Pr.03-19 = 3. You must reset manually.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Does not record when Pr.03-19 = 1 or 2 (“Warning”).</td></tr>
<tr><td colspan="2">Cause</td><td colspan="3">Corrective Actions</td></tr>
<tr><td colspan="2">Loose or broken ACI wiring</td><td colspan="3">Tighten the terminals again.
Replace with a new cable.</td></tr>
<tr><td colspan="2">External device error</td><td colspan="3">Replace new device.</td></tr>
<tr><td colspan="2">Hardware error</td><td colspan="3">If the AnL error still occurs after checking all the wiring, return to the factory for repair.</td></tr>
</table>

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th colspan="2">Warning Name</th><th>Description</th></tr>
<tr><td>13</td><td>
AUTO
Warning
uC
Under Current</td><td colspan="2">Under current (uC)</td><td>Low current</td></tr>
<tr><td colspan="5">Action and Reset</td></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">Pr.06-71</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Pr.06-72</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="3">Pr.06-73
0: No function
1: Fault and coast to stop
2: Fault and ramp to stop by 2nd deceleration time
3: Warn and operation continue</td></tr>
<tr><td colspan="2" rowspan="2">Reset method</td><td>Auto</td><td colspan="2">“Warning” occurs when Pr.06-73 = 3. The “Warning” automatically clears when the output current is > (Pr.06-71 + 0.1 A).</td></tr>
<tr><td>Manual</td><td colspan="2">“Error” occurs when Pr.06-73 = 1 and 2. You must reset manually.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Does not record when Pr.06-73 = 3 and uC displays “Warning”.</td></tr>
<tr><td colspan="2">Cause</td><td colspan="3">Corrective Actions</td></tr>
<tr><td colspan="2">Broken motor cable</td><td colspan="3">Exclude the connection issue of the motor and its load.</td></tr>
<tr><td colspan="2">Improper setting for the low current protection</td><td colspan="3">Set the proper settings for Pr.06-71, Pr.06-72 and Pr.06-73.</td></tr>
<tr><td colspan="2">Low load</td><td colspan="3">Check the loading status.
Make sure the loading matches the motor capacity.</td></tr>
</table>

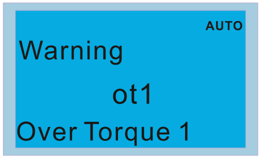
ID No.	Display on LCD Keypad	Warning Name	Description
17	 AUTO Warning oSPD Over Speed Warn	Over speed warning (oSPd)	Over speed warning
Action and Reset			
Action condition		The encoder feedback speed > Pr.10-10	
Action time		Pr.10-11	
Warning setting parameter		Pr.10-12 = 0 0: Warn and keep operation	
Reset method		“Warning” automatically clears when the drive stops	
Reset condition		“Warning” automatically clears when the drive stops	
Record		N/A	
Cause		Corrective Actions	
Improper setting for Pr.10-25 FOC bandwidth of speed observer		Decrease setting value for Pr.10-25.	
Improper bandwidth setting for ASR speed controller		Increase the bandwidth setting for ASR speed controller.	
Incorrect motor parameter setting		Reset motor parameter and run parameter tuning.	
Malfunction caused by interference		Verify wiring of the control circuit, and wiring/grounding of the main circuit to prevent interference.	

ID No.	Display on LCD Keypad	Warning Name	Description
18	 AUTO Warning dAvE Deviation Warn	Deviation Warning (dAvE)	Over speed deviation warning
Action and Reset			
Action condition		Pr.10-13	
Action time		Pr.10-14	
Warning setting parameter		Pr.10-15 = 0 0: Warn and keep operation	
Reset method		“Warning” automatically clears when the drive stops	
Reset condition		After the drive stops	
Record		N/A	
Cause		Corrective Actions	
Improper parameter setting for the slip error		Reset proper value for Pr.10-13 and Pr.10-14.	
Improper setting for ASR parameter and acceleration/ deceleration		Reset ASR parameters. Set proper accel./ decel. time.	
Accel./ Decel. time is too short		Reset proper accel./ decel. time.	
Motor locked		Remove the causes of motor locked.	
Mechanical brake is not released		Check the active timing of the system.	
Incorrect parameter setting of torque limit (Pr.06-12, Pr.11-17–20)		Adjust to proper setting value.	
Malfunction caused by interference		Verify wiring of the control circuit, and wiring/grounding of the main circuit to prevent interference.	

ID No.	Display on LCD Keypad	Warning Name	Description
19	 Warning PHL Phase Loss	Phase loss (PHL)	Input phase loss warning

Action and Reset	
Action condition	One of the phases outputs less than Pr.06-47
Action time	Pr.06-46
Warning setting parameter	Pr.06-45 = 0 0: Warn and keep operation
Reset method	"Warning" automatically clears when the drive stops
Reset condition	After the drive stops
Record	N/A

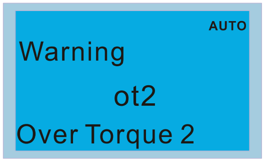
Cause	Corrective Actions
Phase loss of the input power	Verify wiring of the main circuit.
Single phase power input on a three-phase model	Use the model with voltage that matches the power.
The power voltage has changed	If the power of main circuit works well, check if the MC of the main circuit is broken. Cycle the power after verifying the power is normal. If PHL still occurs, return to the factory for repair.
Loose wiring terminal of input power	Tighten the terminal screws with the torque listed in the user manual.
Check if the input cable of 3-phase power is broken	Make sure the wiring is correct. Replace the broken part of the cable.
The voltage of input power has changed	Check setting for Pr.06-50 (Time for Input Phase Loss Detection) and Pr.06-52 (Ripple of Input Phase Loss).
Unbalance three-phase of the input power	Check the status of three-phase power.

ID No.	Display on LCD Keypad	Warning Name	Description
20	 Warning ot1 Over Torque 1	Over-torque 1 (ot1)	Over-torque 1 warning

Action and Reset	
Action condition	Pr.06-07
Action time	Pr.06-08
Warning setting parameter	Pr.06-06 = 1 or 3 0: No function 1: Continue operation after over-torque detection during constant speed operation 2: Stop after over-torque detection during constant speed operation 3: Continue operation after over-torque detection during RUN 4: Stop after over-torque detection during RUN
Reset method	When input current < (Pr.06-07 – 5%), the Ot1 warning automatically clears
Reset condition	When input current < (Pr.06-07 – 5%), the Ot1 warning automatically clears
Record	N/A

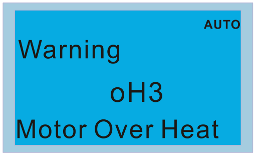
Cause	Corrective Actions
Incorrect parameter setting	Configure the settings for Pr.06-07 and Pr.06-08 again.
Mechanical error (e.g. mechanical lock due to over-torque)	Remove the causes of malfunction.
The load is too large	Decrease the loading. Replace with a motor with larger capacity.
Accel./ Decel. time and working cycle is too short	Increase the setting values for Pr.01-12–01-19 (accel./ decel. time)
V/F voltage is too high	Adjust the settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too small, the load capacity decreases at low-speed).

The motor capacity is too small	Replace with a motor with larger capacity.
Over-load during low-speed operation	Decrease the loading during low-speed operation. Increase the motor capacity.
The torque compensation is too large	Adjust the torque compensation value (Pr.07-26 torque compensation gain) until the output current decreases and the motor does not stall.
Improper parameter settings for the speed tracking function (including restart after momentary power loss and restart after fault)	Correct the parameter settings for speed tracking. Start the speed tracking function. Adjust the maximum current for Pr.07-09 speed tracking.

ID No.	Display on LCD Keypad	Warning Name	Description
21	 AUTO Warning ot2 Over Torque 2	Over-torque (ot2)	Over-torque 2 warning

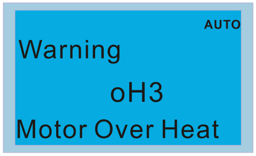
Action and Reset	
Action condition	Pr.06-10
Action time	Pr.06-11
Warning setting parameter	Pr.06-09 = 1 or 3 0: No function 1: Continue operation after over-torque detection during constant speed operation 2: Stop after over-torque detection during constant speed operation 3: Continue operation after over-torque detection during RUN 4: Stop after over-torque detection during RUN
Reset method	When output current < (Pr.06-10 – 5%), the Ot2 warning automatically clears
Reset condition	When output current < (Pr.06-10 – 5%), the Ot2 warning automatically clears
Record	N/A

Cause	Corrective Actions
Incorrect parameter setting	Configure the settings for Pr.06-10 and Pr.06-11
Mechanical error (e.g. mechanical lock due to over-torque)	Remove the causes of malfunction.
The load is too large	Decrease the loading. Replace with a motor with larger capacity.
Accel./ Decel. time and working cycle is too short	Increase the setting values for Pr.01-12–01-19 (accel./ decel. time)
V/F voltage is too high	Adjust the V/F curve (Motor 2, Pr.01-35–01-42), especially the setting value for the mid-point voltage (if the mid-point voltage is set too small, the load capacity decreases at low-speed).
The motor capacity is too small	Replace with a motor with larger capacity.
Over-load during low-speed operation	Decrease the loading during low-speed operation. Increase the motor capacity.
The torque compensation is too large	Adjust the torque compensation value (Pr.07-26 torque compensation gain) until the output current decreases and the motor does not stall.
Improper parameter settings for the speed tracking function (including restart after momentary power loss and restart after fault)	Correct the parameter settings for speed tracking. Start speed tracking function. Adjust the maximum current for Pr.07-09 speed tracking.

ID No.	Display on LCD Keypad	Warning Name	Description
22_1	AUTO Warning oH3 Motor Over Heat	Motor over-heating (oH3) PTC	Motor over-heating warning. The AC motor drive detects the temperature inside the motor is too high

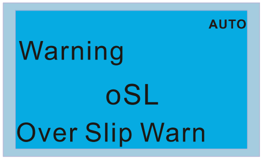
Action and Reset	
Action condition	Pr.03-00 = 6 (PTC), PTC input level > Pr.06-30 (default = 50%)
Action time	Immediately act
Warning setting parameter	Error treatment: Pr.06-29 0: Warn and keep operating 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning When Pr.06-29 = 0 and when the temperature is ≤ Pr.06-30 level, the oH3 warning automatically clears. When Pr.06-29 = 0 ("Warning"), it automatically resets.
Reset method	When Pr.06-29 = 0, oH3 displays "Warning". When the temperature is ≤ Pr.06-30 level, the oH3 warning automatically clears.
Reset condition	When the temperature is ≤ Pr.06-30 level, the oH3 warning automatically clears.
Record	N/A

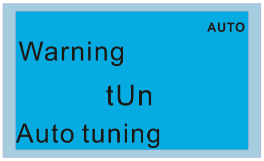
Cause	Corrective Actions
Motor locked	Clear the motor lock status.
The load is too large	Decrease the loading. Replace with a motor with larger capacity.
Ambien temperature is too high	Change the installed place if there are heating devices in the surroundings. Install/ add cooling fan or air conditioner to lower the ambient temperature.
Motor cooling system error	Check the cooling system to make it work normally.
Motor fan error	Replace the fan.
Operates at low-speed too long	Decrease low-speed operation time. Change to dedicated motor for the drive. Increase the motor capacity.
Accel./ Decel. time and working cycle is too short	Increase setting values for Pr.01-12–01-19 (accel./ decel. time).
V/F voltage is too high	Adjust settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too small, the load capacity decreases at low-speed).
Check if the motor rated current matches the motor nameplate	Configure the correct rated current value of the motor again.
Check if the PTC is properly set and wired	Check the connection between PTC thermistor resistor and the heat protection.
Check if the setting for stall prevention is correct	Set the stall prevention to the proper value.
Unbalance three-phase impedance of the motor	Replace the motor.
Harmonics is too high	Use remedies to reduce harmonics.

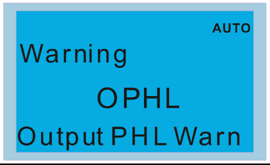
ID No.	Display on LCD Keypad	Warning Name	Description
22_2	 AUTO Warning oH3 Motor Over Heat	Motor over-heating (oH3) PT100	Motor over-heating warning. The AC motor drive detects the temperature inside the motor is too high.

Action and Reset	
Action condition	Pr.03-00 = 11 (PT100), PT100 input level > Pr.06-57 (default = 7 V)
Action time	Immediately act
Warning setting parameter	Error treatment: Pr.06-29 0: Warn and keep operating 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning When Pr.06-29 = 0 and when the temperature is < Pr.06-56 level, the oH3 warning automatically clears. If the temperature is between Pr.06-56 and Pr.06-57, the frequency outputs according to the operating frequency setting for Pr.06-58.
Reset method	When Pr.06-29 = 0, oH3 displays “Warning”. When the temperature is < Pr.06-56 level, the oH3 warning automatically clears.
Reset condition	When the temperature is < Pr.06-56 level, the oH3 warning automatically clears.
Record	N/A

Cause	Corrective Actions
Motor locked	Clear the motor lock status.
The load is too large	Decrease loading. Replace with a motor with larger capacity.
Ambien temperature is too high	Change the installed place if there are heating devices in the surroundings. Install/ add cooling fan or air conditioner to lower the ambient temperature.
Motor cooling system error	Check the cooling system to make it work normally.
Motor fan error	Replace the fan.
Operates at low-speed too long	Decrease low-speed operation time. Change to dedicated motor for the drive. Increase the motor capacity.
Accel./ Decel. time and working cycle is too short	Increase the setting values for Pr.01-12–01-19 (accel./ decel. time).
V/F voltage is too high	Adjust the settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too small, the load capacity decreases at low-speed).
Check if the motor rated current matches the motor nameplate	Configure the correct rated current value of the motor again.
Check if the PT100 is properly set and wired	Check the connection between PT100 thermistor resistor and the heat protection.
Check if the setting for stall prevention is correct	Set the stall prevention to the proper value.
Unbalance three-phase impedance of the motor	Replace the motor.
Harmonics is too high	Use remedies to reduce harmonics.

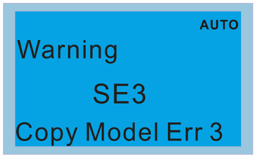
ID No.	Display on LCD Keypad	Warning Name	Description
24	 AUTO Warning oSL Over Slip Warn	Over slip warning (oSL)	Over slip warning. By using the maximum slip (Pr.10-29) as the base, when the drive outputs at constant speed, and the F>H or F<H exceeds Pr.07-29 level and Pr.07-30 setting time, 100% Pr.07-29 = Pr.10-29.
Action and Reset			
Action condition		When the drive outputs at constant speed, and F > H or F < H exceeds the Pr.07-29 level	
Action time		Pr.07-30	
Warning setting parameter		Pr.07-31 = 0 Warning 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning	
Reset method		When Pr.07-31 = 0 and when the drive outputs at constant speed, and F > H or F < H no longer exceeds the Pr.07-29 level, the oSL warning automatically clears.	
Reset condition		N/A	
Record		N/A	
Cause		Corrective Actions	
Check if the motor parameter is correct		Check the motor parameter.	
The load is too large		Decrease the loading.	
Check if the settings for Pr.07-29, Pr.07-30 and Pr.10-29 are properly set		Check the parameter settings for oSL protection.	

ID No.	Display on LCD Keypad	Warning Name	Description
25	 AUTO Warning tUn Auto tuning	Auto tuning (tUn)	Parameter auto-tuning is processing. When running auto-tuning, the keypad displays “tUn”.
Action and Reset			
Action condition		When running Pr.05-00 motor parameter auto-tuning, the keypad displays “tUn”.	
Action time		N/A	
Warning setting parameter		N/A	
Reset method		When auto-tuning is finished and no error occurs, the warning automatically clears.	
Reset condition		When auto-tuning is finished and no error occurs.	
Record		N/A	
Cause		Corrective Actions	
The motor parameter is running auto-tuning		When the auto-tuning is finished, the warning automatically clears.	

ID No.	Display on LCD Keypad	Warning Name	Description
28	 AUTO Warning OPHL Output PHL Warn	Output phase loss (OPHL)	Output phase loss

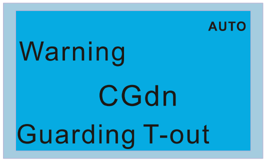
Action and Reset	
Action condition	Pr.06-47
Action time	N/A
Warning setting parameter	Pr.06-45 0: Warn and keep operating 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning
Reset method	If Pr.06-45 is set to 0, the OPHL warning automatically clears after the drive stops.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Unbalanced three-phase impedance of the motor	Replace the motor.
Check if the wiring is incorrect	Check the cable. Replace the cable.
Check if the motor is a single-phase motor	Choose a three-phase motor.
Check if the current sensor is broken	Check if the control board cable is loose. If yes, reconnect the cable and run the drive to test. If the error still occurs, return to the factory for repair. Check if the three-phase current is balanced with a current clamp meter. If the current is balanced and the OPHL error still shows on the display, return to the factory for repair.
If capacity of the drive is larger than the motor	Choose the matches capacity of the drive and motor.

ID No.	Display on LCD Keypad	Warning Name	Description
30	 AUTO Warning SE3 Copy Model Err 3	Copy model error 3 (SE3)	Keypad COPY error 3: copy model error

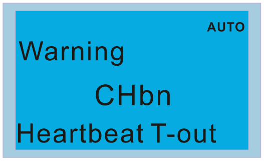
Action and Reset	
Action condition	“SE3” warning occurs when different drive identity codes are found during copying parameters.
Action time	Immediately act when the error is detected
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Keypad copy between different power range drives	It is mainly to prevent parameter copies between different HP/models.

ID No.	Display on LCD Keypad	Warning Name	Description
36	 AUTO Warning CGdn Guarding T-out	CANopen guarding time-out (CGdn)	CANopen guarding time-out 1

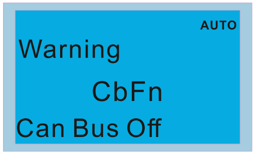
Action and Reset	
Action condition	When CANopen Node Guarding detects that one of the slaves does not response, the CGdn error displays. The upper unit sets factor and time during configuration.
Action time	The time that upper unit sets during configuration
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	The upper unit sends a reset package to clear this fault.
Record	N/A

Cause	Corrective Actions
The guarding time is too short, or less detection times	Increase the guarding time (Index 100C) and detection times.
Malfunction caused by interference	1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.

ID No.	Display on LCD Keypad	Warning Name	Description
37	 AUTO Warning CHbn Heartbeat T-out	CANopen heartbeat error (CHbn)	CANopen heartbeat error

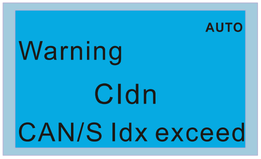
Action and Reset	
Action condition	When CANopen Heartbeat detects that one of the slaves does not response, the CHbn error shows. The upper unit sets the confirming time of producer and consumer during configuration.
Action time	The upper unit sets the confirming time of producer and consumer during configuration.
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	The upper unit sends a reset package to clear this fault
Record	When Pr.00-21 ≠ 3, CHbn is a “Warning”, and the warning is not recorded

Cause	Corrective Actions
The heartbeat time is too short	Increase heartbeat time (Index 1016)
Malfunction caused by interference	1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
Communication cable is broken or bad connected	Check or replace the communication cable.

ID No.	Display on LCD Keypad	Warning Name	Description
39	 AUTO Warning CbFn Can Bus Off	CANopen bus off error (CbFn)	CANopen BUS off error

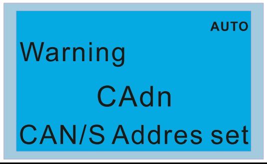
Action and Reset		
Action condition	Hardware	When CANopen card is not installed, CbFn fault will occur.
	Software	When the master received wrong communication package, CbFn fault will occur. Too much interference on BUS When the CAN_H and CAN_L communication cable is short, the master receives wrong package, and CbFn fault occurs.
Action time	Immediately act when the fault is detected	
Warning setting parameter	N/A	
Reset method	Manual Reset	
Reset condition	Cycle the power	
Record	When Pr.00-21≠3, CbFn is a “Warning”, and the warning is not recorded	

Cause	Corrective Actions
Check if the CANopen card is installed	Make sure the CANopen card is installed.
Check if the CANopen speed is correct	Reset CANopen speed (Pr.09-37)
Malfunction caused by interference	1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
Communication cable is broken or bad connected	Check or replace the communication cable.

ID No.	Display on LCD Keypad	Warning Name	Description
40	 AUTO Warning CIdn CAN/S Idx exceed	CANopen index error (CIdn)	CANopen Index error

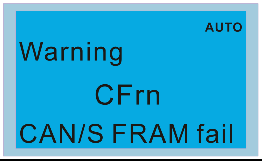
Action and Reset	
Action condition	CANopen communication Index error
Action time	Immediately act when the fault is detected
Warning setting parameter	N/A
Reset method	Manual Reset
Reset condition	Upper unit sends a reset package to clear this fault
Record	When Pr.00-21 ≠ 3, CIdn is a “Warning”, and the warning is not recorded

Cause	Corrective Actions
Incorrect setting of CANopen index	Reset CANopen Index (Pr.00-02 = 7)

ID No.	Display on LCD Keypad	Warning Name	Description
41	 AUTO Warning CAdn CAN/S Addres set	CANopen station address error (CAdn)	CANopen station address error (only supports 1–127)

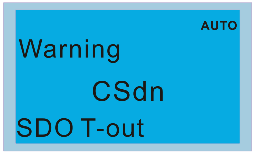
Action and Reset	
Action condition	CANopen station address error
Action time	Immediately act when the fault is detected
Warning setting parameter	N/A
Reset method	Manual Reset
Reset condition	Pr.00-02 = 7
Record	When Pr.00-21 ≠ 3, CAdn is a “Warning”, and the warning is not recorded

Cause	Corrective Actions
Incorrect setting of CANopen station address	1. Disable CANopen (Pr.09-36 = 0) 2. Reset CANopen (Pr.00-02 = 7) 3. Reset CANopen station address (Pr.09-36)

ID No.	Display on LCD Keypad	Warning Name	Description
42	 AUTO Warning CFrn CAN/S FRAM fail	CANopen memory error (CFrn)	CANopen memory error

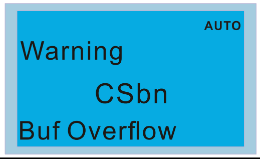
Action and Reset	
Action condition	When the user update firmware version of the control board, the FRAM internal data will not be changed, then CFrn fault will occur.
Action time	Immediately act when the fault is detected
Warning setting parameter	N/A
Reset method	Manual Reset
Reset condition	Pr.00-02 = 7
Record	When Pr.00-21 ≠ 3, CFrn is a “Warning”, and the warning is not recorded

Cause	Corrective Actions
CANopen internal memory error	1. Disable CANopen (Pr.09-36 = 0) 2. Reset CANopen (Pr.00-20 = 7) 3. Reset CANopen station address (Pr.09-36)

ID No.	Display on LCD Keypad	Warning Name	Description
43	 AUTO Warning CSdn SDO T-out	CANopen SDO time-out (CSdn)	SDO transmission time-out (only shows on master station)

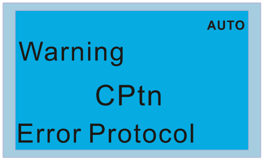
Action and Reset	
Action condition	When the CANopen master transmits SDO command, and the Slave response “time-out”, CSdn warning will occur.
Action time	Immediately act when the fault is detected
Warning setting parameter	N/A
Reset method	When the master resends a SDO command and receives the response, the warning automatically clears.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Slave is not connected	Connect slave and CANopen BUS.
The synchronize cycle is set too short	Increase the synchronization time (Index 1006)
Malfunction caused by interference	1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
Disconnection or bad connection of the communication cable	Check the status of the cable, or replace the cable.

ID No.	Display on LCD Keypad	Warning Name	Description
44	 AUTO Warning CSbn Buf Overflow	CANopen SDO receives register overflow (CSbn)	CANopen SDO receives register overflow

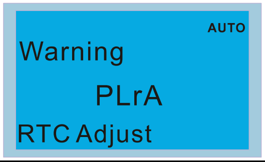
Action and Reset	
Action condition	The upper unit sends too much SDO and causes buffer overflow
Action time	Immediately act when the fault is detected
Warning setting parameter	N/A
Reset method	The upper unit sends a reset package to clear the warning.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Too much SDO from the upper unit	Check if the master sends too much SDO command. Make sure the master sends SDO command according to the command format.

ID No.	Display on LCD Keypad	Warning Name	Description
46	 AUTO Warning CPtn Error Protocol	CANopen format error (CPtn)	CANopen protocol format error

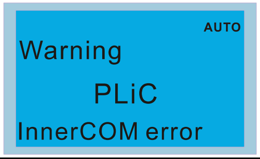
Action and Reset	
Action condition	The slave detects that data from the upper unit cannot be recognized, and then shows CPtn warning
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	The upper unit sends a reset packet to clear the warning
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The upper unit sends incorrect communication packet	Make sure the master sends the packet based on CANopen DS301 standard command format.

ID No.	Display on LCD Keypad	Warning Name	Description
47	 AUTO Warning PLrA RTC Adjust	RTC adjust (PLrA)	PLC (RTC) is not adjusted

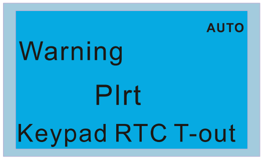
Action and Reset		
Action condition	When using RTC function for PLC program, and PLC detects unreasonable RTC time, PLrA warning displays.	
Action time	Immediately displays when the fault is detected	
Warning setting parameter	N/A	
Reset method	Auto	Stops the PLC and runs again, the warning automatically clears
	Manual	Manual reset to clear this warning
Reset condition	Cycle the power	
Record	N/A	

Cause	Corrective Actions
When using RTC function for PLC program, and the drive is power off over 7 days or KPC-CC01 does not connect to the drive for a long time, the RTC time is different with the internal calculated time when re-connect the keypad to the drive.	1. Stop the PLC program and restart it. 2. Adjust the RTC time and cycle the power.
KPC-CC01 does not adjust the RTC time	Adjust the RTC time and cycle the power.
PLC detects unreasonable RTC time	1. Stop the PLC program and restart it. 2. Cycle the power.
Replace with a new KPC-CC01	1. Stop the PLC program and restart it. 2. Cycle the power.

ID No.	Display on LCD Keypad	Warning Name	Description
48	 AUTO Warning PLiC InnerCOM error	InnerCOM error (PLiC)	InnerCOM error

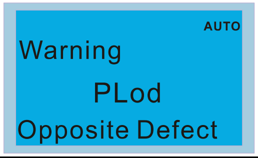
Action and Reset	
Action condition	N/A
Action time	N/A
Warning setting parameter	N/A
Reset method	N/A
Reset condition	When InnerCOM is back to normal condition, the warning automatically clears
Record	N/A

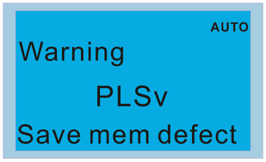
Cause	Corrective Actions
Communication cable is loose	Check the connection of the communication cable
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. It recommended to install terminal resistor(s) on the first and the last unit of the communication circuit.

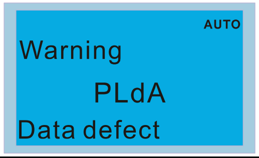
ID No.	Display on LCD Keypad	Warning Name	Description
49	 AUTO Warning PLrt Keypad RTC T-out	Keypad RTC time-out (PLrt)	PLC (RTC) error

Action and Reset	
Action condition	N/A
Action time	N/A
Warning setting parameter	N/A
Reset method	N/A
Reset condition	Cycle the power
Record	N/A

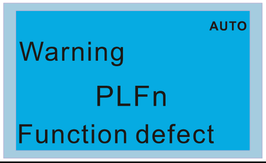
Cause	Corrective Actions
KPC-CC01 is not connected to the control board while using the RTC function	Do not remove the KPC-CC01 keypad while using RTC function.

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>50</td><td>
AUTO
Warning
PLod
Opposite Defect</td><td>PLC opposite defect (PLod)</td><td>PLC download error warning</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">During PLC downloading, the program source code detects incorrect address (e.g. the address exceeds the range), then the PLod warning shows.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately displays when the fault is detected</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect component number is found when downloading the PLC program</td><td colspan="2">Use the correct component number.</td></tr>
</table>

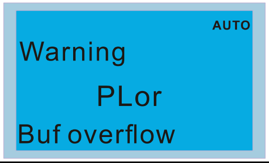
<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>51</td><td>
AUTO
Warning
PLSv
Save mem defect</td><td>PLC save memory error (PLSv)</td><td>Data error during PLC operation</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">The program detects incorrect written address (e.g. the address has exceeded the range) during PLC operation, then the PLSv warning shows.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately displays when the fault is detected</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">An incorrect written address is detected during PLC operation</td><td colspan="2">Make sure the write-in address is correct and re-download the program.</td></tr>
</table>

ID No.	Display on LCD Keypad	Warning Name	Description
52	 AUTO Warning PLdA Data defect	Data defect (PLdA)	Data error during PLC operation

Action and Reset	
Action condition	T. The program detects incorrect write-in address when decoding the program source code and downloading the PLC program (e.g. the address has exceeded the range), then PLdA warning acts.
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A
Cause	**Corrective Actions**
During PLC operation, the external Modbus has written/read incorrect data to internal PLC program	Check if the upper unit transmits the correct command

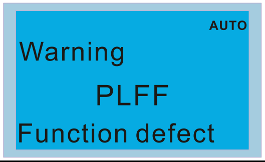
ID No.	Display on LCD Keypad	Warning Name	Description
53	 AUTO Warning PLFn Function defect	Function defect (PLFn)	PLC download function code error

Action and Reset	
Action condition	The program detects incorrect command (unsupported command) during PLC downloading, then PLFn warning acts.
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A
Cause	**Corrective Actions**
Unsupported command has used while downloading the program	Check if the firmware of the drive is the old version. If yes, contact Delta.

ID No.	Display on LCD Keypad	Warning Name	Description
54	 AUTO Warning PLor Buf overflow	PLC buffer overflow (PLor)	PLC register overflow

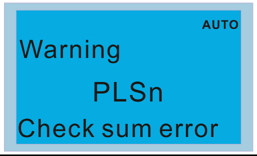
Action and Reset	
Action condition	When PLC runs the last command and the command exceeds the maximum capacity of the program, the PLor warning shows.
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The program detects source code error during PLC operation	1. Disable PLC 2. Delete PLC program (Pr.00-02 = 6) 3. Enable PLC 4. Re-download PLC program

ID No.	Display on LCD Keypad	Warning Name	Description
55	 AUTO Warning PLFF Function defect	Function defect (PLFF)	Function code error during PLC operation

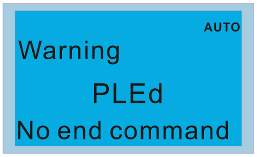
Action and Reset	
Action condition	The program detects incorrect command (unsupported command) during PLC operation, then PLFF warning shows.
Action time	Immediately displays when the fault is detected
Warning setting parameter	NA
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The PLC runs an incorrect command during operation	When starting the PLC function and there is no program in the PLC, the PLFF warning shows. This is a normal warning, please download the program.

ID No.	Display on LCD Keypad	Warning Name	Description
56	 AUTO Warning PLSn Check sum error	Checksum error (PLSn)	PLC checksum error

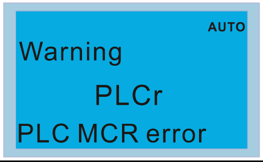
Action and Reset	
Action condition	PLC checksum error is detected after power on, then PLSn warning shows
Action time	Immediately displays when the fault is detected
Warning setting parameter	NA
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The program detects checksum error during PLC operation	1. Disable PLC 2. Remove PLC program (Pr.00-02 = 6) 3. Enable PLC 4. Re-download PLC program

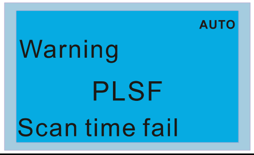
ID No.	Display on LCD Keypad	Warning Name	Description
57	 AUTO Warning PLEd No end command	No end command (PLEd)	PLC end command is missing

Action and Reset	
Action condition	The “End” command is missing until the last command is executed, the PLEd warning shows
Action time	Immediately displays when the fault is detected
Warning setting parameter	NA
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
There is no “END” command during PLC operation	1. Disable PLC 2. Remove PLC program (Pr.00-02 = 6) 3. Enable PLC 4. Re-download PLC program

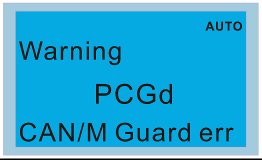
ID No.	Display on LCD Keypad	Warning Name	Description
58	 AUTO Warning PLCr PLC MCR error	PLC MCR error (PLCr)	PLC MCR command error
Action and Reset			
Action condition	The MC command is detected during PLC operation, but there is no corresponded MCR command, then the PLCr warning shows.		
Action time	Immediately displays when the fault is detected		
Warning setting parameter	NA		
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.		
Reset condition	N/A		
Record	N/A		
Cause	Corrective Actions		
The MC command is continuously used for more than 9 times	The MC command cannot be used continuously for 9 times. Check and reset the program, then re-download the program.		

ID No.	Display on LCD Keypad	Warning Name	Description
59	 AUTO Warning PLdF Download fail	PLC download fail (PLdF)	PLC download fail
Action and Reset			
Action condition	PLC download fail due to momentary power loss during the downloading, when power is ON again, PLdF warning shows.		
Action time	Immediately displays when the fault is detected		
Warning setting parameter	NA		
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.		
Reset condition	N/A		
Record	N/A		
Cause	Corrective Actions		
PLC download is forced to stop, so the program write-in is incompleted	Check if there is any error in the program and re-download the PLC program		

ID No.	Display on LCD Keypad	Warning Name	Description
60	 AUTO Warning PLSF Scan time fail	PLC scan time fail (PLSF)	PLC scan time exceeds the maximum allowable time

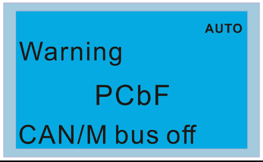
Action and Reset	
Action condition	When the PLC scan time exceeds the maximum allowable time (400 ms), PLSF warning shows.
Action time	Immediately displays when the fault is detected
Warning setting parameter	NA
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The PLC scan time exceeds the maximum allowable time (400ms)	Check if the source code is correct and re-download the program

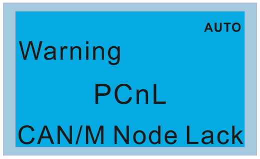
ID No.	Display on LCD Keypad	Warning Name	Description
61	 AUTO Warning PCGd CAN/M Guard err	CAN/M guarding error (PCGd)	CANopen Master guarding error

Action and Reset	
Action condition	When CANopen Master Node Guarding detects that one of the Slaves does not response, the PCGd warning will display
Action time	Immediately displays when the fault is detected
Warning setting parameter	NA
Reset method	Check if the program is correct and re-download the program. If the fault does not exist, the warning automatically clears.
Reset condition	N/A
Record	N/A

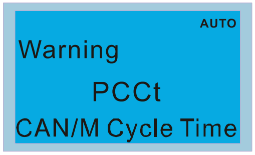
Cause	Corrective Actions
Slave is not connected or CANopen BUS cable is not connected	Connect the Slave and CANopen BUS
Malfunction caused by interference	1. Verify wiring/grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
Communication cable is broken or bad connected	Check or replace the communication cable.

ID No.	Display on LCD Keypad	Warning Name	Description
62	 AUTO Warning PCbF CAN/M bus off	CAN/M BUS off (PCbF)	CANopen Master BUS off

Action and Reset	
Action condition	When the CANopen master detects error packets more than 255 during the BUS off detection, or when the CANopen card is not installed, the PCbF warning displays. If the BUS cable is not connected, the drive will not receive issues packet, and the PCbF warning will not display.
Action time	Immediately displays when the fault is detected
Warning setting parameter	NA
Reset method	Cycle the power
Reset condition	N/A
Record	N/A
Cause	**Corrective Actions**
Malfunction caused by interference	1. Verify wiring/grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
Communication cable is broken or bad connected	Check or replace the communication cable.

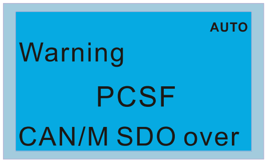
ID No.	Display on LCD Keypad	Warning Name	Description
63	 AUTO Warning PCnL CAN/M Node Lack	CAN/M node lack (PCnL)	CANopen Master node error

Action and Reset	
Action condition	When the CANopen master configures different setting nodes from the actual nodes, the PCnL warning displays.
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	When connect BUS to the original slave, or change the configured node numbers to meet the actual node quantity, the warning automatically clears.
Reset condition	N/A
Record	N/A
Cause	**Corrective Actions**
The configured node quantity is different from the actual nodes	Connect BUS to the original slave, or change the configured node numbers to meet the actual node quantity
Communication cable is broken or bad connected	Check or replace the communication cable.

ID No.	Display on LCD Keypad	Warning Name	Description
64	 AUTO Warning PCCt CAN/M Cycle Time	CAN/M cycle time-out (PCCt)	CANopen Master cycle time-out

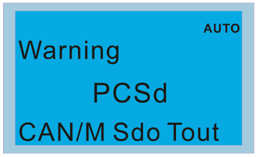
Action and Reset	
Action condition	When the transmitted packet from CANopen master exceeds the maximum allowable quantity in a certain time, the PCCt warning displays.
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	The warning automatically clears when changing the configuration and re-executing the program.
Reset condition	N/A
Record	N/A

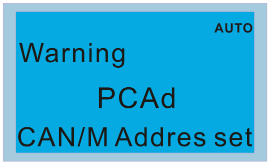
Cause	Corrective Actions
When the transmitted packet from CANopen master exceeds the maximum allowable quantity in a certain time	Increase the time setting of D1090 synchronization cycle

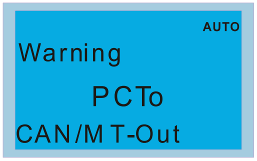
ID No.	Display on LCD Keypad	Warning Name	Description
65	 AUTO Warning PCSF CAN/M SDO over	CAN/M SDO over (PCSF)	CANopen Master SDO overflow

Action and Reset	
Action condition	When the CANopen master transmits too much SDO that causes buffer overflow, the PCSF warning displays
Action time	Immediately displays when the fault is detected
Warning setting parameter	N/A
Reset method	Cycle the power, or stop the PLC and run the PLC again
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Internal PLC transmits too much SDO at once	The PLC program needs to confirm receiving the SDO feedback data before sending another SDO command.

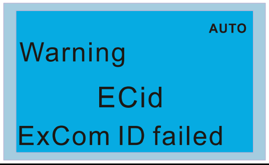
ID No.	Display on LCD Keypad	Warning Name	Description
66	 AUTO Warning PCSd CAN/M Sdo Tout	CAN/M SDO time-out (PCSd)	CANopen Master SDO time-out
Action and Reset			
Action condition	When the CANopen master sends a SDO command, and the BUS is too busy to transmit the command, PCSd warning displays.		
Action time	Immediately displays when the fault is detected		
Warning setting parameter	N/A		
Reset method	The warning automatically clears when the SDO transmits normally.		
Reset condition	N/A		
Record	N/A		
Cause	Corrective Actions		
When the CANopen master transmits a SDO command, and does not receive feedback from the Slave within 1 sec.	Check if the Slave responds within 1 second.		

ID No.	Display on LCD Keypad	Warning Name	Description
67	 AUTO Warning PCAd CAN/M Addres set	CAN/M address error (PCAd)	CANopen Master station address error
Action and Reset			
Action condition	When the CANopen master detects an incorrect or repeated station address from the Slave, the PCAd warning displays.		
Action time	Immediately displays when the fault is detected		
Warning setting parameter	N/A		
Reset method	The warning automatically clears when reset the station address and run the program again.		
Reset condition	N/A		
Record	N/A		
Cause	Corrective Actions		
When the CANopen master detects an incorrect or repeated station address from the Slave	Set the correct slave station address.		

ID No.	Display on LCD Keypad	Warning Name	Description
68		CAN/M time-out (PCTo)	When the drive receives an incorrect packet, it means that there is interference or the command from the upper unit does not meet the CANopen command format.

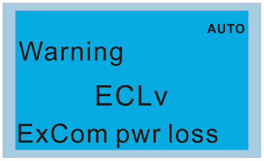
Action and Reset	
Action condition	N/A
Action time	Immediately acts when receiving the command
Warning setting parameter	N/A
Reset method	The warning automatically clears after receives another normal packet
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Malfunction caused by interference	1. Verify wiring/grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
The command from the upper unit does not meet the CANopen format	Contact Delta for further confirmation.

ID No.	Display on LCD Keypad	Warning Name	Description
70		ExCom ID fail (ECid)	Duplicate MAC ID error Node address setting error

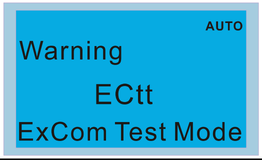
Action and Reset	
Action condition	Duplicate setting of MAC ID Node address setting error
Action time	N/A
Warning setting parameter	N/A
Reset method	Correct the setting and cycle the power
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The setting address exceeds the range (0–63)	Check the address setting of the communication card (Pr.09-70)
The speed setting exceeds the range	Standard: 0–2, non-standard: 0–7
The address is duplicated with other nodes on the BUS	Reset the address

ID No.	Display on LCD Keypad	Warning Name	Description
71	 AUTO Warning ECLv ExCom pwr loss	ExCom power loss (ECLv)	Low voltage of communication card

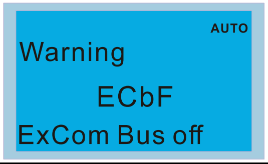
Action and Reset	
Action condition	The 5V power that drive provides to communication card is to low
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Re-power
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The 5V power that drive provides to communication card is to low	1. Switch the communication card to other CP2000 drives and observe if there is ECLv warning shown. If yes, replace with a new communication card; if not, replace the drive. 2. Use another communication card to test if the ECLv warning has shown as well. If not, replace the card; if yes, replace the drive.
The card is loose	Make sure the communication card is well inserted.

ID No.	Display on LCD Keypad	Warning Name	Description
72	 AUTO Warning ECtt ExCom Test Mode	ExCom test mode (ECtt)	Communication card is in the test mode

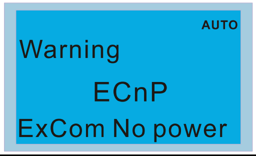
Action and Reset	
Action condition	Communication card is in the test mode
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Cycle the power and enter the normal mode
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Communication command error	Cycle the power

ID No.	Display on LCD Keypad	Warning Name	Description
73	 AUTO Warning ECbF ExCom Bus off	ExCom Bus off (ECbF)	The communication card detects too much errors in the BUS, then enters the BUS-OFF status and stop communicating

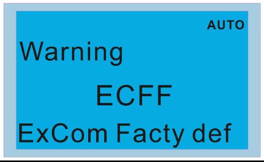
Action and Reset	
Action condition	When the drive detects BUS-off (for DeviceNet)
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Cycle the power
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Poor connection of the cable	Re-connect the cable
Bad quality of the cable	Replace the cable

ID No.	Display on LCD Keypad	Warning Name	Description
74	 AUTO Warning ECnP ExCom No power	ExCom no power (ECnP)	There is no power supply on the DeviceNet

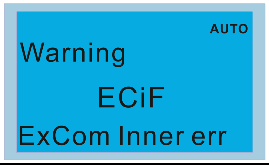
Action and Reset	
Action condition	There is no power supply on the DeviceNet
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Re-power
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
The drive detects that DeviceNet has no power	Check if the cable and power is normal. If yes, return to the factory for repair.

ID No.	Display on LCD Keypad	Warning Name	Description
75	 AUTO Warning ECFF ExCom Facty def	ExCom factory defect (ECFF)	Factory default setting error

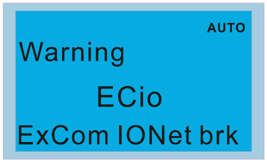
Action and Reset	
Action condition	Factory default setting error
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Cycle the power
Reset condition	N/A
Record	N/A

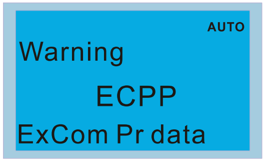
Cause	Corrective Actions
Factory default setting error	Use DCISoft to reset to the default value.

ID No.	Display on LCD Keypad	Warning Name	Description
76	 AUTO Warning ECiF ExCom Inner err	ExCom inner error (ECiF)	Serious internal error

Action and Reset	
Action condition	Internal memory saving error
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Cycle the power
Reset condition	N/A
Record	N/A

Cause	Corrective Actions
Noise interference	Verify wiring of the control circuit, and wiring/grounding of the main circuit to prevent interference. Cycle the power.
The memory is broken	Reset to the default value and check if the error still exists. If yes, replace the communication card.

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>77</td><td>AUTO
Warning
ECio
ExCom IONet brk</td><td>ExCom IO Net break
(ECio)</td><td>IO connection break off</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">IO connection between the communication card and the master is broken off</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately acts</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">The cable is loose</td><td colspan="2">Re-install the cable</td></tr>
<tr><td colspan="2">Incorrect parameter setting for master communication</td><td colspan="2">Check the setting for master communication parameter</td></tr>
</table>

<table>
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>78</td><td>AUTO
Warning
ECPP
ExCom Pr data</td><td>ExCom Parameter data error
(ECPP)</td><td>Profibus parameter data error</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">The GSD file is incorrect</td><td colspan="2">Get the correct GSD file from the software</td></tr>
</table>

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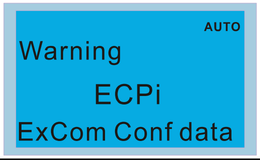
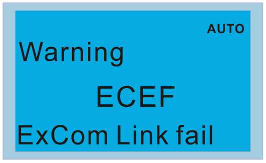
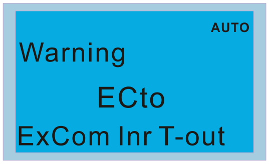
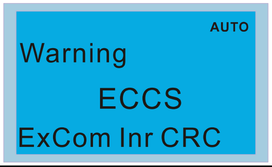
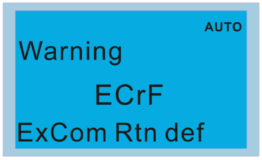
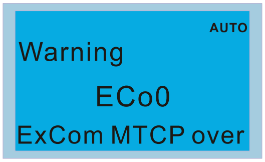
<tr><th>ID No.</th><th>Display on LCD Keypad</th><th>Warning Name</th><th>Description</th></tr>
<tr><td>79</td><td>AUTO
Warning
ECPi
ExCom Conf data</td><td>ExCom configuration data error
(ECPi)</td><td>Profibus configuration data error</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Warning setting parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">N/A</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">The GSD file is incorrect</td><td colspan="2">Get the correct GSD file from the software</td></tr>
</table>

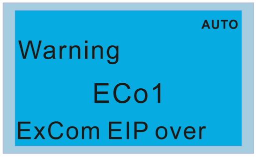
ID No.	Display on LCD Keypad	Warning Name	Description
80	 AUTO Warning ECEF ExCom Link fail	Ethernet link fail (ECEF)	Ethernet cable is not connected
Action and Reset			
Action condition		Hardware detection	
Action time		Immediately acts	
Warning setting parameter		N/A	
Reset method		Manual reset	
Reset condition		N/A	
Record		N/A	
Cause		Corrective Actions	
Ethernet cable is loose		Re-connect the cable	
Bad quality of Ethernet cable		Replace the cable	

ID No.	Display on LCD Keypad	Warning Name	Description
81	 AUTO Warning ECto ExCom Inr T-out	Communication time-out (ECto)	Communication time-out for communication card and the upper unit
Action and Reset			
Action condition		N/A	
Action time		N/A	
Warning setting parameter		N/A	
Reset method		N/A	
Reset condition		CMC-EC01: auto resets when the communication with the upper unit is back to normal	
Record		N/A	
Cause		Corrective Actions	
Communication card is not connected with the upper unit		Check if the connection of the communication cable is correct	
Communication error of the upper unit		Check if the communication of the upper unit is normal	

ID No.	Display on LCD Keypad	Warning Name	Description
82	 AUTO Warning ECCS ExCom Inr CRC	Checksum error (ECCS)	Checksum error for communication card and the drive
Action and Reset			
Action condition		Software detection	
Action time		N/A	
Warning setting parameter		N/A	
Reset method		Manual reset	
Reset condition		Immediately resets	
Record		N/A	
Cause		Corrective Actions	
Noise interference		Verify wiring of the control circuit, and wiring/grounding of the main circuit to prevent interference.	

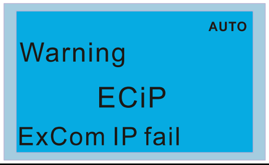
ID No.	Display on LCD Keypad	Warning Name	Description
83	 AUTO Warning ECrF ExCom Rtn def	Return defect (ECrF)	Communication card returns to the default setting
Action and Reset			
Action condition		Communication card returns to the default setting	
Action time		N/A	
Warning setting parameter		N/A	
Reset method		Manual reset	
Reset condition		Immediately resets	
Record		N/A	
Cause		Corrective Actions	
Communication card is returning to default setting		No actions.	

ID No.	Display on LCD Keypad	Warning Name	Description
84	 AUTO Warning ECo0 ExCom MTCP over	Modbus TCP over (Eco0)	Modbus TCP exceeds maximum communication value
Action and Reset			
Action condition		Hardware detection	
Action time		Immediately acts	
Warning setting parameter		N/A	
Reset method		Manual reset	
Reset condition		Immediately resets	
Record		N/A	
Cause		Corrective Actions	
The Master communication value is more than the allowable quantity of the communication card		Reduce Master communication value	
The upper unit is online without communicating, and does not break off the Modbus TCP link, causes occupy connection		Revise program of upper unit, the communication should be break off when it is not used for a long time	
A new Modbus TCP connection is built every time when the upper unit is connected to the communication card, which caused occupy connection		Revise program of upper unit: use the same Modbus TCP connection when connected to the same communication card	

ID No.	Display on LCD Keypad	Warning Name	Description
85	 AUTO Warning ECo1 ExCom EIP over	EtherNet/IP over (ECo1)	Ethernet/IP exceeds maximum communication value

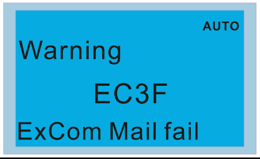
Action and Reset	
Action condition	Hardware detection
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Immediately resets
Record	N/A

Cause	Corrective Actions
The Master communication value is more than the allowable quantity of the communication card	Reduce Master communication value
The upper unit is online without communicating, and does not break off the Modbus TCP link, causes occupy connection	Revise program of upper unit, the communication should be break off when it is not used for a long time
A new Modbus TCP connection is built every time when the upper unit is connected to the communication card, which caused occupy connection	Revise program of upper unit: use the same Modbus TCP connection when connected to the same communication card

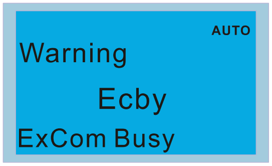
ID No.	Display on LCD Keypad	Warning Name	Description
86	 AUTO Warning ECiP ExCom IP fail	IP fail (ECiP)	IP setting error

Action and Reset	
Action condition	Software detection
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Immediate reset
Record	N/A

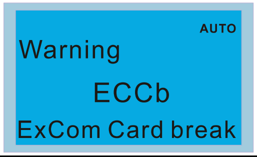
Cause	Corrective Actions
IP conflict	Reset IP
DHCP IP configuration error	MIS check if DHCP Server works normally

ID No.	Display on LCD Keypad	Warning Name	Description
87	 AUTO Warning EC3F ExCom Mail fail	Mail fail (EC3F)	Mail warning: Alarm mail will be sent when the communication card establishes alarm conditions

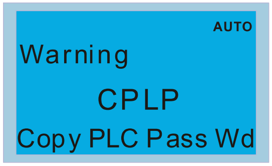
Action and Reset	
Action condition	Communication card establishes alarm conditions
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Immediately resets
Record	N/A
Cause	**Corrective Actions**
Communication card establishes alarm conditions	No actions

ID No.	Display on LCD Keypad	Warning Name	Description
88	 AUTO Warning Ecby ExCom Busy	ExCom busy (ECbY)	Communication card busy: too much packets are received

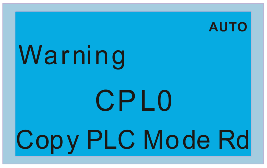
Action and Reset	
Action condition	Software detection
Action time	N/A
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	N/A
Record	N/A
Cause	**Corrective Actions**
Communication packets are too much for the communication card to process	Reduce communication packets

ID No.	Display on LCD Keypad	Warning Name	Description
89	 AUTO Warning ECCb ExCom Card break	ExCom card break (ECCb)	Communication card break off warning

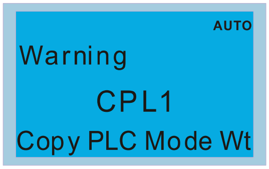
Action and Reset	
Action condition	Communication card break off
Action time	The time between communication card break off and ECCb displays: 1. EtherNet/IP: 3 sec. 2. Modbus TCP: 3 sec. 3. DeviceNet: 1 sec. 4. PROFIBUS: 1 sec. 5. EtherCAT: 0.1 sec.
Warning setting parameter	N/A
Reset method	Auto resets after communication card is re-installed
Reset condition	Immediately resets
Record	N/A
Cause	**Corrective Actions**
Communication card break off	Re-install communication card

ID No.	Display on LCD Keypad	Warning Name	Description
90	 AUTO Warning CPLP Copy PLC Pass Wd	Copy PLC: password error (CPLP)	Copy PLC password error. When KPC-CC01 is processing PLC copy and the PLC password is incorrect, the CPLP warning shows.

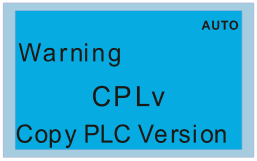
Action and Reset	
Action condition	PLC password is incorrect
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Directly resets
Record	N/A
Cause	**Corrective Actions**
PLC password is incorrect	Reset and enter correct PLC password

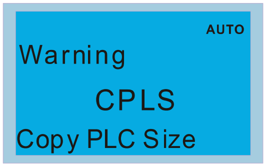
ID No.	Display on LCD Keypad	Warning Name	Description
91	 AUTO Warning CPL0 Copy PLC Mode Rd	Copy PLC: Read mode error (CPL0)	Copy PLC Read mode error

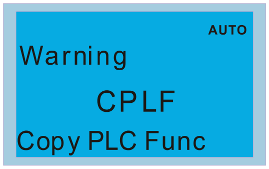
Action and Reset	
Action condition	When copy PLC read mode with incorrect process
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Directly resets
Record	N/A
Cause	**Corrective Actions**
When copy PLC read mode and the process is incorrect	Cycle the power and copy PLC read mode again

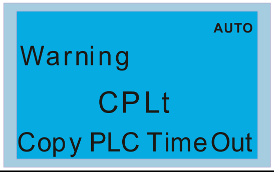
ID No.	Display on LCD Keypad	Warning Name	Description
92	 AUTO Warning CPL1 Copy PLC Mode Wt	Copy PLC: Write mode (CPL1)	Copy PLC write mode error

Action and Reset	
Action condition	Copy PLC write mode with incorrect process
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Directly resets
Record	N/A
Cause	**Corrective Actions**
When copy PLC write mode and the process is incorrect	Cycle the power and copy PLC read mode again

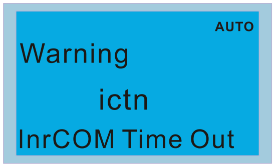
ID No.	Display on LCD Keypad	Warning Name	Description
93	 AUTO Warning CPLv Copy PLC Version	Copy PLC: version error (CPLv)	Copy PLC version error. When non-CP2000 built-in PLC is copied to CP2000 drive, the CPLv warning shows
Action and Reset			
Action condition	Software detection		
Action time	Immediately acts		
Warning setting parameter	N/A		
Reset method	Manual reset		
Reset condition	Directly resets		
Record	N/A		
Cause	Corrective Actions		
Non-CP2000 PLC program is copied to CP2000	Check if the copied PLC program is for CP2000. Use the correct CP2000 PLC program.		

ID No.	Display on LCD Keypad	Warning Name	Description
94	 AUTO Warning CPLS Copy PLC Size	Copy PLC: size error (CPLS)	Copy PLC Capacity size error
Action and Reset			
Action condition	Software detection		
Action time	Immediately acts		
Warning setting parameter	N/A		
Reset method	Manual reset		
Reset condition	Directly resets		
Record	N/A		
Cause	Corrective Actions		
The PLC copied to CP2000 exceeds the allowable capacity	Check if the copied PLC program is for CP2000 Use CP2000 PLC program with correct capacity		

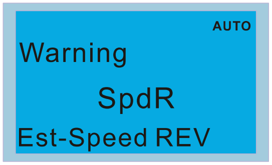
ID No.	Display on LCD Keypad	Warning Name	Description
95	 AUTO Warning CPLF Copy PLC Func	Copy PLC: PLC function (CPLF)	KPC-CC01 Copy PLC function should be executed when PLC is off
Action and Reset			
Action condition	Software detection		
Action time	Immediately acts		
Warning setting parameter	N/A		
Reset method	Manual reset		
Reset condition	Directly resets		
Record	N/A		
Cause	Corrective Actions		
PLC function is enabled when KPC-CC01 is running copy PLC	Disable PLC function first, then run the PLC copy function again		

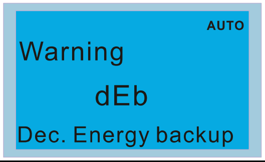
ID No.	Display on LCD Keypad	Warning Name	Description
96	 AUTO Warning CPLt Copy PLC Time Out	Copy PLC: time-out (CPLt)	Copy PLC time out

Action and Reset	
Action condition	Software detection
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Manual reset
Reset condition	Directly resets
Record	N/A
Cause	**Corrective Actions**
KPC-CC01 is removed while copying PLC program	The KPC-CC01 cannot be removed during the PLC copy process

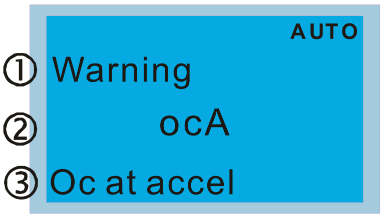
ID No.	Display on LCD Keypad	Warning Name	Description
101	 AUTO Warning ictn InrCOM Time Out	InrCOM time-out (ictn)	Internal communication time-out

Action and Reset	
Action condition	When Pr.09-31= (-1) – (-10) (no -9) and the internal communication between Master and Slave is abnormal, the ictn warning shows.
Action time	Immediately acts
Warning setting parameter	N/A
Reset method	Auto-reset
Reset condition	The warning automatically clears when the communication is back to normal condition
Record	N/A
Cause	**Corrective Actions**
Malfunction caused by interference	Verify wiring/grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication conditions with the upper unit	Check if the setting for Pr.09-02 is the same as the setting for upper unit
Communication cable break off or not connected well	Check the cable status or replace the cable

ID No.	Display on LCD Keypad	Warning Name	Description
105	 AUTO Warning SpdR Est-Speed REV	Estimated speed reverse (SpdR)	Estimated speed is in a reverse direction with motor actual running direction
Action and Reset			
Action condition		Software detection	
Action time		Pr.10-09	
Warning setting parameter		Pr.10-08 0: Warn and keep operation 1: Fault and coast to stop 2: Fault and ramp to stop	
Reset method		Manual reset	
Reset condition		Immediately resets	
Record		N/A	
Cause		Corrective Actions	
The motor runs in reverse direction at start		Check if the motor is hold when started, or start the motor with speed source.	
The difference between motor parameter measured Rr and Rs value is too large		Normally the Rr value of IM is Rs × 0.7. If there is much difference of the measured value (e.g. Rr = Rs × 0.3), proceed the motor parameter auto-tuning again.	
Insufficient output torque is dragged to the reverse direction by the load.		Increase the current limit of Pr.06-12, so as to increase the output torque.	

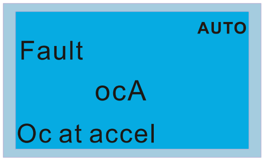
ID No.	Display on LCD Keypad	Warning Name	Description
123	 AUTO Warning dEb Dec. Energy backup	Deceleration energy backup (dEb)	Deceleration energy backup
Action and Reset			
Action condition		Software detection	
Action time		N/A	
Warning setting parameter		0: Disable 1: dEb with auto accel./decel., the output frequency will note return after power reply. 2: dEb with auto accel./decel., the output frequency will return after power reply. 3: dEb low-voltage control, then increase to 350 V_{DC} / 700 V_{DC} and decelerate to stop. 4: dEb high-voltage control of 350 V_{DC} / 700 V_{DC} and decelerate to stop	
Reset method		Manual reset	
Reset condition		Immediately resets	
Record		N/A	
Cause		Corrective Actions	
Instantaneous power off or low voltage and unstable/ sudden heavy load of the power that cause the voltage drop		Check the power consumption	
Unexpected power off		Check the power consumption	

Chapter 14 Fault Codes and Descriptions



Warning
ocA
Oc at accel

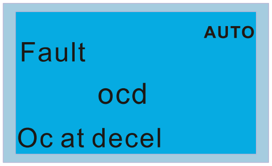
① Display error signal
② Abbreviate error code
③ Display error description

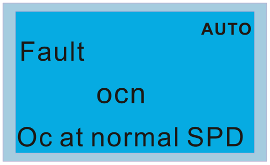
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
1	 AUTO Fault ocA Oc at accel	Over-current during acceleration (ocA)	Output current exceeds 2.4 times of rated current during acceleration. When ocA occurs, the drive closes the gate of the output immediately, the motor runs freely, and the display shows an ocA error.

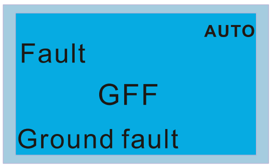
Action and Reset	
Action condition	240% of rated current
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset in 5 sec. after the fault is cleared
Record	Yes

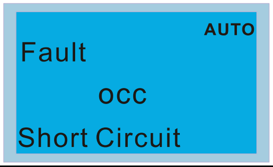
Cause	Corrective Actions
Acceleration time is too short	1. Increase the acceleration time 2. Increase the acceleration time of S curve 3. Set auto-acceleration and auto-deceleration parameter (Pr.01-44) 4. Set over-current stall prevention function (Pr.06-03) 5. Replace the drive with a larger capacity model.
Short circuit at motor output due to poor insulation wiring	Check the motor cable and remove causes of the short circuits, or replace the cable before turning on the power.
Check for possible burnout or aging insulation of the motor	Check the motor insulation value with megger. Replace the motor if the insulation is poor.
The load is too large.	Check if the output current during the whole working process exceeds the AC motor drive's rated current. If yes, replace the AC motor drive with a larger capacity model.
Impulsive change of the load	Reduce the load or increase the capacity of AC motor drive.
Use special motor or motor with larger capacity than the drive	Check the motor capacity (the rated current on the motor's nameplate should ≦ the rated current of the drive)
Use ON/OFF controller of an electromagnetic contactor at the output (U/V/W) of the drive	Check the action timing of the contactor and make sure it is not turned ON/OFF when the drive outputs the voltage.
V/F curve setting error	Adjust V/F curve setting and frequency/voltage. When the fault occurs, and the frequency voltage is too high, reduce the voltage.
Torque compensation is too large	Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the output current reduces and the motor does not stall.
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.
The motor starts when in free run	Enable the speed tracking during start-up of Pr.07-12.
Improper parameter settings for the speed tracking function (including restart after momentary power loss and restart after fault)	Correct the parameter settings for speed tracking. 1. Start the speed tracking function. 2. Adjust the maximum current for Pr.07-09 speed tracking.
Incorrect combination of control mode and used motor	Check the settings for Pr.00-11 control mode: 1. For IM, Pr.00-11 = 0, 1, 2, 3, 5 2. For PM, Pr.00-11 = 4, 6, or 7
The length of motor cable is too long	Increase AC motor drive's capacity. Install AC reactor(s) on the output side (U/V/W).

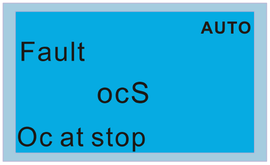
Hardware failure	The ocA occurs due to short circuit or ground fault at the output side of the drive. Check for possible short circuits between terminals with the electric meter: B1 corresponds to U, V and W; DC- corresponds to U, V and W; ⏚ corresponds to U, V and W. If short circuit occur, return to the factory for repair.
Check if the setting for stall prevention is correct	Set the stall prevention to the proper value.

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>2</td><td>AUTO
Fault
ocd
Oc at decel</td><td>Over-current during deceleration (ocd)</td><td>Output current exceeds 2.4 times of rated current during deceleration.
When ocd occurs, the drive closes the gate of the output immediately, the motor runs freely, and the display shows an ocd error.</td></tr>
<tr><td colspan="4">Action and Reset</td></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">240% of rated current</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Reset in 5 sec. after the fault is cleared</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><td colspan="2">Cause</td><td colspan="2">Corrective Actions</td></tr>
<tr><td colspan="2">Deceleration time too short</td><td colspan="2">1. Increase the deceleration time
2. Increase the deceleration time of S-curve
3. Set auto-acceleration and auto-deceleration parameter (Pr.01-44)
4. Set over-current stall prevention function (Pr.06-03)
5. Replace the drive with a larger capacity model</td></tr>
<tr><td colspan="2">Check if the mechanical brake of the motor activates too early</td><td colspan="2">Check the action timing of the mechanical brake</td></tr>
<tr><td colspan="2">Short-circuit at motor output due to poor insulation wiring</td><td colspan="2">Check the motor cable and remove causes of the short circuits, or replace the cable before turning on the power.</td></tr>
<tr><td colspan="2">Check for possible burnout or aging insulation of the motor</td><td colspan="2">Check the motor insulation value with megger. Replace the motor if the insulation is poor.</td></tr>
<tr><td colspan="2">The load is too large</td><td colspan="2">Check if the output current during the whole working process exceeds the AC motor drive’s rated current. If yes, replace the AC motor drive with a larger capacity model.</td></tr>
<tr><td colspan="2">Impulsive change of the load</td><td colspan="2">Reduce the load or increase the capacity of AC motor drive.</td></tr>
<tr><td colspan="2">Use special motor or motor with larger capacity than the drive</td><td colspan="2">Check the motor capacity (the rated current on the motor’s nameplate should ≤ the rated current of the drive)</td></tr>
<tr><td colspan="2">Use ON/OFF controller of an electromagnetic contactor at the output (U/V/W) of the drive</td><td colspan="2">Check the action timing of the contactor and make sure it is not turned ON/OFF when the drive outputs the voltage.</td></tr>
<tr><td colspan="2">V/F curve setting error</td><td colspan="2">Adjust V/F curve settings and frequency/voltage. When the fault occurs, and the frequency voltage is too high, reduce the voltage.</td></tr>
<tr><td colspan="2">Torque compensation is too large</td><td colspan="2">Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the output current reduces and the motor does not stall.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.</td></tr>
<tr><td colspan="2">The length of motor cable is too long</td><td colspan="2">Increase AC motor drive’s capacity
Install AC reactor(s) on the output side (U/V/W)</td></tr>
<tr><td colspan="2">Hardware error</td><td colspan="2">The ocd occurs due to short circuit or ground fault at the output side of the drive.
Check for possible short circuits between terminals with the electric meter:
B1 corresponds to U, V and W; DC- corresponds to U, V and W; ⏚ corresponds to U, V and W.
If short circuits occur, return to the factory for repair.</td></tr>
<tr><td colspan="2">Check if the setting of stall prevention is correct</td><td colspan="2">Set the stall prevention to the proper value.</td></tr>
</table>

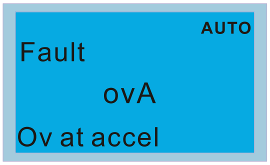
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>3</td><td>AUTO
Fault
ocn
Oc at normal SPD</td><td>Over-current during steady operation (ocn)</td><td>Output current exceeds 2.4 times of the rated current during constant speed.
When ocn occurs, the drive closes the gate of the output immediately, the motor runs freely, and the display shows an ocn error.</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">240% of rated current</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Reset in 5 sec. after the fault is cleared</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Short-circuit at motor output due to poor insulation wiring</td><td colspan="2">Check the motor cable and remove causes of the short circuits, or replace the cable before turning on the power.</td></tr>
<tr><td colspan="2">Check for possible shaft lock, burnout or aging insulation of the motor</td><td colspan="2">Troubleshoot the motor shaft lock.
Check the motor insulation value with megger. Replace the motor if the insulation is poor.</td></tr>
<tr><td colspan="2">Impulsive change of the load</td><td colspan="2">Reduce the load or increase the capacity of AC motor drive.</td></tr>
<tr><td colspan="2">Use special motor or motor with larger capacity than the drive</td><td colspan="2">Check motor capacity (the rated current on the motor's nameplate should ≤ the rated current of the drive)</td></tr>
<tr><td colspan="2">Use ON/OFF controller of an electromagnetic contactor at the output (U/V/W) of the drive</td><td colspan="2">Check the action timing of the contactor and make sure it is not turned ON/OFF when the drive outputs the voltage.</td></tr>
<tr><td colspan="2">V/F curve setting error</td><td colspan="2">Adjust V/F curve settings and frequency/voltage. When the fault occurs, and the frequency voltage is too high, reduce the voltage.</td></tr>
<tr><td colspan="2">Over-torque offset value too high</td><td colspan="2">Adjust over-torque offset value (Refer to Pr.07-26 torque compensation gain), until the output current is reduced and not motor stall.</td></tr>
<tr><td colspan="2">Torque compensation is too large.</td><td colspan="2">Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the output current reduces and the motor does not stall.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.</td></tr>
<tr><td colspan="2">The length of motor cable is too long</td><td colspan="2">Increase the AC motor drive's capacity.
Install AC reactor(s) on the output side (U/V/W).</td></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="2">The ocn occurs due to short circuit or ground fault at the output side of the drive.
Check for possible short circuit between terminals with the electric meter:
B1 corresponds to U, V and W; DC- corresponds to U, V, and W; ⏚ corresponds to U, V, and W.
If short circuits occur, return to the factory for repair.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>4</td><td>AUTO
Fault
GFF
Ground fault</td><td>Ground fault (GFF)</td><td>When (one of) the output terminal(s) is grounded, short circuit current is larger than Pr.06-60 setting value, and the detection time is longer than Pr.06-61 time setting, GFF occurs.
NOTE: the short circuit protection is provided for AC motor drive protection, not to protect the user.</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Pr.06-60 (Default = 60%)</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Pr.06-61 (Default = 0.10 sec.)</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Reset in 5 sec. after the fault is cleared</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Motor burnout or aging insulation occurred</td><td colspan="2">Check the motor insulation value with megger. Replace the motor if the insulation is poor.</td></tr>
<tr><td colspan="2">Short circuit due to broken cable</td><td colspan="2">Troubleshoot the short circuit.
Replace the cable.</td></tr>
<tr><td colspan="2">Larger stray capacitance of the cable and terminal ⏚</td><td colspan="2">If the motor cable length exceeds 100 m, decrease the setting value for carrier frequency.
Take remedies to reduce stray capacitance.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the grounding and wiring of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective sufficient anti-interference performance.</td></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="2">Cycle the power after checking the status of motor, cable and cable length. If GFF still exists, return to the factory for repair.</td></tr>
</table>

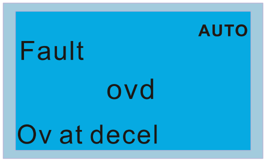
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>5</td><td>AUTO
Fault
occ
Short Circuit</td><td>IGBT short circuit between upper bridge and lower bridge (occ)</td><td>Short-circuit is detected between upper bridge and lower bridge of the IGBT module</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Hardware protection</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Reset in 5 sec. after the fault is cleared</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">IGBT error</td><td colspan="2" rowspan="2">Check the motor wiring.
Cycle the power, if occ still exists, return to the factory for repair.</td></tr>
<tr><td colspan="2">Short-circuit detecting circuit error</td></tr>
</table>

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
6	 AUTO Fault ocS Oc at stop	Over-current at stop (ocS)	Over-current or hardware failure in current detection at stop. Cycle the power after ocS occurs. If the hardware failure occurs, the display shows cd1, cd2 or cd3.

Action and Reset	
Action condition	240% of rated current
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset in 5 sec. after the fault is cleared
Record	Yes
Cause	**Corrective Actions**
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.
Hardware failure	Check if other error code such as cd1–cd3 occur after cycling the power. If yes, return to the factory for repair.

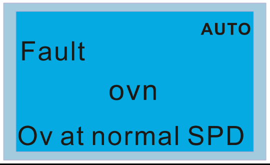
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
7	 AUTO Fault ovA Ov at accel	Over-voltage during acceleration (ovA)	DC bus over-voltage during acceleration. When ovA occurs, the drive closes the gate of the output, the motor runs freely, and the display shows an ovA error.

Action and Reset	
Action condition	230V models: 410 V_{DC} 460V models: 820 V_{DC} 575V models: 1116 V_{DC} 690V models: 1318 V_{DC}
Action time	Immediately act when DC bus voltage is higher than the level
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset only when DC bus voltage is lower than 90% of the over-voltage level
Record	Yes
Cause	**Corrective Actions**
Acceleration is too slow (e.g. hen lifting load decreases acceleration time)	Decrease the acceleration time Use brake unit or DC bus Replace the drive with a larger capacity model.
The setting for stall prevention level is smaller than no-load current	The setting for stall prevention level should be larger than no-load current
Power voltage is too high	Check if the input voltage is within the rated AC motor drive input voltage range, and check for possible voltage spikes.
ON/OFF switch action of phase-in capacitor in the same power system	If the phase-in capacitor or active power supply unit acts in the same power system, the input voltage may surge abnormally in a short time. In this case, install an AC reactor.
Regenerative voltage of motor inertia	Use over-voltage stall prevention function (Pr.06-01) Use auto-acceleration and auto-deceleration setting (Pr.01-44) Use a brake unit or DC bus
Acceleration time is too short	Check if the over-voltage warning occurs after acceleration stops. When the warning occurs, do the following: 1. Increase the acceleration time 2. Set Pr.06-01 over-voltage stall prevention 3. Increase setting value for Pr.01-25 S-curve acceleration arrival time 2
Motor ground fault	The ground short circuit current charges the capacitor in the main circuit through the power. Check if there is ground fault on the motor cable, wiring box and its internal terminals. Troubleshoot the ground fault.
Incorrect wiring of brake resistor or brake unit	Check the wiring of brake resistor and brake unit.
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
8	 AUTO Fault ovd Ov at decel	Over-voltage during deceleration (ovd)	DC bus over-voltage during deceleration. When ovd occurs, the drive closes the gate of the output immediately, the motor runs freely, and the display shows an ovd error.

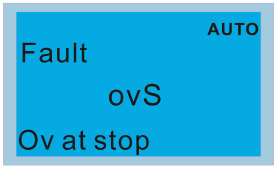
Action and Reset	
Action condition	230V models: 410 V_{DC} 460V models: 820 V_{DC} 575V models: 1116 V_{DC} 690V models: 1318 V_{DC}
Action time	Immediately act when DC bus voltage is higher than the level
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset only when DC bus voltage is lower than 90% of the over-voltage level
Record	Yes

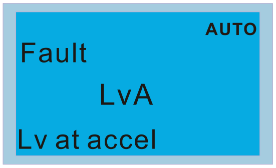
Cause	Corrective Actions
Deceleration time is too short, causing too large regenerative energy of the load	1. Increase the setting value of Pr.01-13, Pr.01-15, Pr.01-17 and Pr.01-19 (deceleration time) 2. Connect brake resistor, brake unit or DC bus on the drive. 3. Reduce the brake frequency. 4. Replace the drive with a larger capacity model. 5. Use S-curve acceleration/deceleration. 6. Use over-voltage stall prevention (Pr.06-01). 7. Use auto-acceleration and auto-deceleration (Pr.01-44). 8. Adjust braking level (Pr.07-01 or the bolt position of the brake unit).
The setting for stall prevention level is smaller than no-load current	The setting for stall prevention level should be larger than no-load current
Power voltage is too high	Check if the input voltage is within the rated AC motor drive input voltage range, and check for possible voltage spikes.
ON/OFF switch action of phase-in capacitor in the same power system	If the phase-in capacitor or active power supply unit acts in the same power system, the input voltage may surge abnormally in a short time. In this case, install an AC reactor.
Motor ground fault	The ground short circuit current charges the capacitor in the main circuit through the power. Check if there is ground fault on the motor cable, wiring box and its internal terminals. Troubleshoot the ground fault.
Incorrect wiring of brake resistor or brake unit	Check the wiring of brake resistor or brake unit.
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

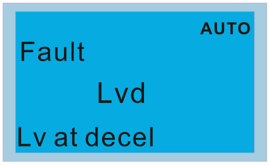
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
9	 AUTO Fault ovn Ov at normal SPD	Over-voltage at constant speed (ovn)	DC bus over-voltage at constant speed. When ovn occurs, the drive closes the gate of the output immediately, the motor runs freely, and the display shows an ovn error.

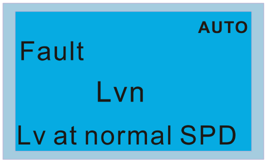
Action and Reset	
Action condition	230V models: 410 V_{DC} 460V models: 820 V_{DC} 575V models: 1116 V_{DC} 690V models: 1318 V_{DC}
Action time	Immediately act when DC bus voltage is higher than the level
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset only when DC bus voltage is lower than 90% of over-voltage level
Record	Yes

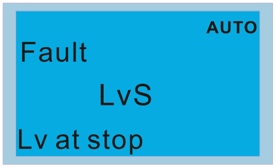
Cause	Corrective Actions
Impulsive change of the load	1. Connect brake resistor, brake unit or DC bus to the drive. 2. Reduce the load. 3. Replace to drive with a larger capacity model. 4. Adjust braking level (Pr.07-01 or bolt position of the brake unit).
The setting for stall prevention level is smaller than no-load current	The setting of stall prevention level should be larger than no-load current
Regenerative voltage of motor inertia	Use over-voltage stall prevention function (Pr.06-01) Use a brake unit or DC bus
Power voltage is too high	Check if the input voltage is within the rated AC motor drive input voltage range, and check for possible voltage spikes.
ON/OFF switch action of phase-in capacitor in the same power system	If the phase-in capacitor or active power supply unit acts in the same power system, the input voltage may surge abnormally in a short time. In this case, install an AC reactor.
Motor ground fault	The ground short-circuit current charges the capacitor in the main circuit through the power. Check if there is ground fault on the motor cable, wiring box and its internal terminals. Troubleshoot the ground fault.
Incorrect wiring of brake resistor or brake unit	Check the wiring of brake resistor or brake unit.
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>10</td><td>
AUTO
Fault
ovS
Ov at stop</td><td>Over-voltage at stop (ovS)</td><td>Over-voltage at stop</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">230V models: 410 V_{DC}
460V models: 820 V_{DC}
575V models: 1116 V_{DC}
690V models: 1318 V_{DC}</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act when DC bus voltage is higher than the level</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Reset only when DC bus voltage is lower than 90% of over-voltage level</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Power voltage is too high</td><td colspan="2">Check if the input voltage is within the rated AC motor drive input voltage range, and check for possible voltage spikes.</td></tr>
<tr><td colspan="2">ON/OFF switch action of phase-in capacitor in the same power system</td><td colspan="2">If the phase-in capacitor or active power supply unit activates in the same power system, the input voltage may surge abnormally in a short time. In this case, install an AC reactor.</td></tr>
<tr><td colspan="2">Incorrect wiring of brake resistor or brake unit</td><td colspan="2">Check the wiring of brake resistor or brake unit.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.</td></tr>
<tr><td colspan="2">Hardware failure in voltage detection</td><td colspan="2">Check if other error code such as cd1–cd3 occur after cycling the power. If yes, return to the factory for repair.</td></tr>
<tr><td colspan="2">Motor ground fault</td><td colspan="2">The ground short circuit current charges the capacitor in the main circuit through the power. Check if there is ground fault on the motor cable, wiring box and its internal terminals.
Troubleshoot the ground fault.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>11</td><td>
AUTO
Fault
LvA
Lv at accel</td><td>Low-voltage during acceleration (LvA)</td><td>DC bus voltage is lower than Pr.06-00 setting value during acceleration</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Pr.06-00 (Default = depending on the model)</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act when DC bus voltage is lower than Pr.06-00</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Reset when DC bus voltage is higher than Pr.06-00 + 30 V (Frame A–D) / 40 V (Frame E and below)</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Power-off</td><td colspan="2">Improve power supply condition.</td></tr>
<tr><td colspan="2">Power voltage changes</td><td colspan="2">Adjust voltage to the power range of the drive</td></tr>
<tr><td colspan="2">Start up the motor with large capacity</td><td colspan="2">Check the power system.
Increase the capacity of power equipment.</td></tr>
<tr><td colspan="2">The load is too large</td><td colspan="2">Reduce the load.
Increase the drive capacity.
Increase the acceleration time.</td></tr>
<tr><td colspan="2">DC bus</td><td colspan="2">Install DC reactor(s).</td></tr>
<tr><td colspan="2">Check if there is short-circuit plate or any DC reactor installed between terminal +1 and +2</td><td colspan="2">Connect short circuit plate or DC reactor between terminal +1 and +2.
If the error still exists, return to the factory for repair.</td></tr>
</table>

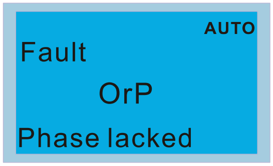
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
12	 AUTO Fault Lvd Lv at decel	Low-voltage during deceleration (Lvd)	DC bus voltage is lower than Pr.06-00 setting value during deceleration
Action and Reset			
Action condition		Pr.06-00 (Default = depending on the model)	
Action time		Immediately act when DC bus voltage is lower than Pr.06-00	
Fault treatment parameter		NA	
Reset method		Manual reset	
Reset condition		Reset when DC bus voltage is higher than Pr.06-00 + 30 V (Frame A–D) / 40 V (Frame E and above)	
Record		Yes	
Cause		Corrective Actions	
Power-off		Improve power supply condition.	
Power voltage changes		Adjust voltage to the power range of the drive.	
Start up the motor with large capacity		Check the power system. Increase the capacity of power equipment.	
Sudden load		Reduce the load. Increase the drive capacity.	
DC bus		Install DC reactor(s).	

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
13	 AUTO Fault Lvn Lv at normal SPD	Low-voltage at constant speed (Lvn)	DC bus voltage is lower than Pr.06-00 setting value at constant speed
Action and Reset			
Action condition		Pr.06-00 (Default = depending on the model)	
Action time		Immediately act when DC bus voltage is lower than Pr.06-00	
Fault treatment parameter		NA	
Reset method		Manual reset	
Reset condition		Reset when DC bus voltage is higher than Pr.06-00 + 30 V (Frame A–D) / 40 V (Frame E and above)	
Record		Yes	
Cause		Corrective Actions	
Power-off		Improve power supply condition.	
Power voltage changes		Adjust voltage to the power range of the drive	
Start up the motor with large capacity		Check the power system. Increase the capacity of power equipment.	
Sudden load		Reduce the load. Increase the drive capacity.	
DC bus		Install DC reactor(s).	

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
14	 AUTO Fault LvS Lv at stop	Low-voltage at stop (LvS)	1. DC bus voltage is lower than Pr.06-00 setting value at stop 2. Hardware failure in voltage detection

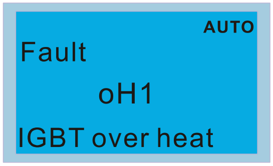
Action and Reset	
Action condition	Pr.06-00 (Default = depending on the model)
Action time	Immediately act when DC bus voltage is lower than Pr.06-00
Fault treatment parameter	N/A
Reset method	Manual / auto: 230V models: Frame A–D = Lv level + 30 V_{DC} + 500 ms Frame E and above = Lv level + 40 V_{DC} + 500 ms 460V models: Frame A–D = Lv level + 60 V_{DC} + 500 ms Frame E and above = Lv level + 80 V_{DC} + 500 ms 575V models: Frame A–D = Pr.06-00 + 100.0 V_{DC} Frame E and above = Pr.06-00 + 120 V_{DC} 690V models: Frame A–D = Pr.06-00 + 100.0 V_{DC} Frame E and above = Pr.06-00 + 100.0 V_{DC}
Reset condition	500 ms
Record	Yes

Cause	Corrective Actions
Power-off	Improve power supply condition.
Incorrect drive models	Check if the power specification matches the drive.
Power voltage changes	Adjust voltage to the power range of the drive. Cycle the power after checking the power. If LvS error still exists, return to the factory for repair.
Start up the motor with large capacity	Check the power system. Increase the capacity of power equipment.
DC bus	Install DC reactor(s).

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
15	 AUTO Fault OrP Phase lacked	Phase loss protection (OrP)	Phase loss of power input

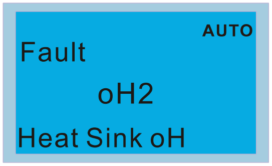
Action and Reset	
Action condition	DC bus is lower than Pr.07-00, and DC bus ripple is higher than Pr.06-52
Action time	N/A
Fault treatment parameter	Pr.06-53
Reset method	Manual reset
Reset condition	Immediately reset when DC bus is higher than Pr.07-00
Record	Yes

Cause	Corrective Actions
Phase loss of input power	Correctly install the wiring of the main circuit power.
Single phase power input to three-phase model	Choose the model whose power matches the voltage.
Power voltage changes	If the main circuit power works normally, verify the main circuit. Cycle the power after checking the power, if OrP error still exists, return to the factory for repair.
Loose wiring terminal of input power	Tighten the terminal screws according to the torque described in the user manual.
The input cable of three-phase power is cut off	Wire correctly. Replace the cut off cable.
Input power voltage changes too much	Verify the setting value for Pr.06-50 Time for Input Phase Loss Detection and Pr.06-52 Ripple of Input Phase Loss
Unbalanced three-phase of input power	Check the power three-phase status.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
16	 AUTO Fault oH1 IGBT over heat	IGBT overheating (oH1)	IGBT temperature exceeds the protection level

Action and Reset	
Action condition	When Pr.06-15 is higher than the IGBT overheating protection level, oH1 error occurs instead of oH1 warning.
Action time	IGBT temperature exceeds the protection level for more than 100ms, oH1 error occurs.
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset only when IGBT temperature is lower than oH1 error level minus (-) 10°C
Record	Yes

Cause	Corrective Actions
Check if the ambient temperature or temperature inside the control cabinet is too high, or if there is obstruction in the ventilation hole of the control cabinet.	1. Check ambient temperature. 2. Regularly inspect the ventilation hole of the control cabinet. 3. Change the installed place if there are heating objects, such as braking resistors, in the surroundings. 4. Install/ add cooling fan or air conditioner to lower the temperature inside the cabinet.
Check if there is any obstruction on the heat sink or if the fan is running.	Remove the obstruction or replace the cooling fan.
Insufficient ventilation space	Increase ventilation space of the drive.
Check if the drive matches the corresponding load	1. Reduce the load 2. Reduce the carrier 3. Replace the drive with a larger capacity model.
The drive has run 100% or more than 100% of the rated output for a long time	Replace the drive with a larger capacity model.

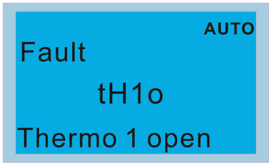
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
17	 AUTO Fault oH2 Heat Sink oH	Board level component overheating (oH2)	Board-level component temperature exceeds the protection level

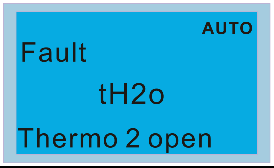
Action and Reset	
Action condition	Refer to the table below for oH2 level of each models
Action time	When board-level component temperature exceeds the protection level for more than 100 ms, oH2 error occurs
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset when board-level component temperature is lower than oH2 error level minus (-) 10°C
Record	Yes
Cause	**Corrective Actions**
Check if the ambient temperature or temperature inside the control cabinet is too high, or if there is obstruction in the ventilation hole of the control cabinet.	1. Check ambient temperature. 2. Regularly inspect the ventilation hole of the control cabinet. 3. Change the installed place if there are heating objects, such as braking resistors, in the surroundings. 4. Install / add cooling fan or air conditioner to lower the temperature inside the cabinet.
Check if there is any obstruction on the heat sink or if the fan is running.	Remove the obstruction or replace the cooling fan.
Insufficient ventilation space	Increase ventilation space of the drive.
Check if the drive matches the corresponding load	1. Reduce the load 2. Reduce the carrier 3. Replace the drive with a larger capacity model.
The drive has run 100% or more than 100% of the rated output for a long time	Replace the drive with a larger capacity model.
Unstable power	Install reactor(s)
Load changes frequently	Reduce load changes

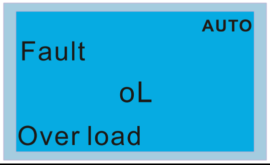
oH1/ oH2 warning level

Model	oH1	oH2	oH warning oH1 warning = (Pr.06-15)
VFD007CP23A-21	110	110	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD015CP23A-21			
VFD022CP23A-21			
VFD037CP23A-21			
VFD055CP23A-21			
VFD075CP23A-21			
VFD110CP23A-21			
VFD150CP23A-21			
VFD185CP23A-21			
VFD220CP23A-21			
VFD300CP23A-21			
VFD370CP23A-00/-21		90	
VFD450CP23A-00/-21			
VFD550CP23A-00/-21			
VFD750CP23A-00/-21			
VFD900CP23A-00/-21			
VFD007CP43A/4EA-21	110	110	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD015CP43B/4EB-21			
VFD022CP43B/4EB-21			
VFD037CP43B/4EB-21			
VFD040CP43A/4EA-21			
VFD055CP43B/4EB-21			
VFD075CP43B/4EB-21			
VFD110CP43B/4EB-21			

Model	oH1	oH2	oH warning oH1 warning = (Pr.06-15)
VFD150CP43B/4EB-21			
VFD185CP43B/4EB-21		110	
VFD220CP43A/4EA-21			oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD370CP43B/4EB-21			
VFD450CP43S-00/-21	110	90	
VFD550CP43S-00/-21			
VFD750CP43B-00/-21			
VFD900CP43A-00/-21			
VFD1100CP43A-00/-21			
VFD1320CP43B-00/-21			
VFD1600CP43A-00/-21			
VFD1850CP43B-00/-21			
VFD2000CP43A-00/-21			
VFD2200CP43A-00/-21			
VFD2500CP43A-00/-21			
VFD2800CP43A-00/-21			
VFD3150CP43A-00 VFD3150CP43C-00/-21			
VFD3550CP43A-00 VFD3550CP43C-00/-21			
VFD4000CP43A-00 VFD4000CP43C-00/-21			
VFD5000CP43A-00 VFD5000CP43C-00/-21		85	
VFD5600CP43A-00 VFD5600CP43C-21	Contact Delta for more information		
VFD6300CP43A-00 VFD6300CP43C-21	Contact Delta for more information		
VFD015CP53A-21	100	85	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD022CP53A-21			
VFD037CP53A-21			
VFD055CP53A-21		70	
VFD075CP53A-21			
VFD110CP53A-21			
VFD150CP53A-21			
VFD185CP63A-21	90	85	oH1 Warning = oH1 – 5 oH2 Warning = oH2 – 5
VFD220CP63A-21			
VFD300CP63A-21			
VFD370CP63A-21			
VFD450CP63A-00/-21	100	65	
VFD550CP63A-00/-21			
VFD750CP63A-00/-21	110		
VFD900CP63A-00/-21			
VFD1100CP63A-00/-21			
VFD1320CP63A-00/-21			
VFD1600CP63A-00/-21			
VFD2000CP63A-00/-21		70	
VFD2500CP63A-00/-21			
VFD3150CP63A-00/-21			
VFD4000CP63A-00/-21			
VFD4500CP63A-00/-21			
VFD5600CP63A-00/-21			
VFD6300CP63A-00/-21			

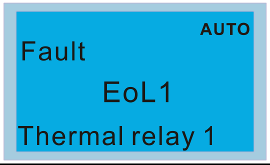
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th colspan="2">Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>18</td><td>
AUTO
Fault
tH1o
Thermo 1 open</td><td colspan="2">IGBT temperature detection failure (tH1o)</td><td>IGBT hardware failure in temperature detection</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">NTC broken or wiring failure</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">When the IGBT temperature is higher than the protection level, and detection time exceeds 100 ms, the tH1o protection activates.</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="3">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="3">Wait for 10 minutes, and then cycle the power. Check if tH1o protection still exists. If yes, return to the factory for repair.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th colspan="2">Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>19</td><td>
AUTO
Fault
tH2o
Thermo 2 open</td><td colspan="2">Capacitor hardware error (tH2o)</td><td>Hardware failure in capacitor temperature detection</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">NTC broken or wiring failure</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">When the IGBT temperature is higher than the protection level, and detection time exceeds 100 ms, the tH2o protection activates.</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="3">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="3">Wait for 10 minutes, and then cycle the power. Check if tH2o protection still exists. If yes, return to the factory for repair.</td></tr>
</table>

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
21	 AUTO Fault oL Over load	Over load (oL)	The AC motor drive detects excessive drive output current. The overload capacity sustains for 1 minute when the drive outputs 150% of the drive's rated output current.

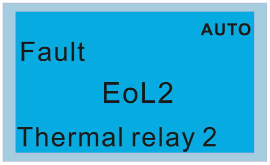
Action and Reset	
Action condition	Based on over load curve and derating curve.
Action time	When the load is higher than the protection level and exceeds allowable time, the oL protection activates.
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset in 5 sec. after the fault is cleared
Record	Yes

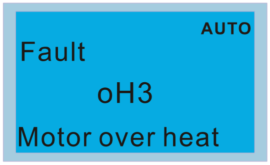
Cause	Corrective Actions
The load is too large	Reduce the load
Accel./Decel. time or the working cycle are too short	Increase the setting value for Pr.01-12–01-19 (accel./decel time)
V/F voltage is too high	Adjust the settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed). Refer to the V/F curve selection of Pr.01-43.
The capacity of the drive is too small	Replace the drive with a larger capacity model.
Overload during low-speed operation	Reduce the load during low-speed operation. Increase the drive capacity. Decrease the carrier frequency of Pr.00-17.
Torque compensation is too large	Adjust the torque compensation (refer to Pr.07-26 Torque Compensation Gain) until the output current reduces and the motor does not stall.
Check if the setting for stall prevention is correct.	Set the stall prevention to the proper value.
Output phase loss	Check the status of three-phase motor. Check if the cable is broken or the screws are loose.
Improper parameter settings for the speed tracking function (including restart after momentary power loss and restart after fault)	Correct the parameter settings for speed tracking. 1. Start the speed tracking function. 2. Adjust the maximum current for Pr.07-09 speed tracking.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
22	 AUTO Fault EoL1 Thermal relay 1	Electronic thermal relay 1 protection (EoL1)	Electronics thermal relay 1 protection. The drive coasts to stop once it activates.

Action and Reset	
Action condition	Start counting when output current > 105% of motor 1 rated current
Action time	Pr.06-14 (if the output current is larger than 105% of motor 1 rated current again within 60 sec., the counting time reduces and is less than Pr.06-14)
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset in 5 sec. after the fault is cleared
Record	Yes

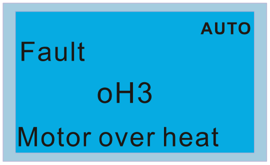
Cause	Corrective Actions
The load is too large	Reduce the load.
Accel./Decel. time or the working cycle is too short	Increase the setting values for Pr.01-12–01-19 (Accel./Decel. time)
V/F voltage is too high	Adjust the settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed). Refer to the V/F curve selection of Pr.01-43.
Overload during low-speed operation. When using a general motor, even it operates below rated current, an overload may still occur during low-speed operation.	Decrease low-speed operation time. Replace the drive with a dedicated to VFD model. Increase the motor capacity.
When using VFD dedicated motors, Pr.06-13=0 (electronic thermal relay selection motor 1 = inverter motor)	Pr.06-13 = 1 electronic thermal relay selection motor 1 = standard motor (motor with fan on the shaft).
Incorrect value of electronic thermal relay	Reset to the correct motor rated current.
The maximum motor frequency is set too low	Reset to the correct motor rated frequency.
One drive to multiple motors	Set Pr.06-13 = 2 electronic thermal relay selection motor 1= disable, and install thermal relay on each motor.
Check if the setting for stall prevention is correct.	Set the stall prevention to the proper value.
Torque compensation is too large	Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the current reduces and the motor does no stall.
Motor fan error	Check the status of the fan, or replace the fan.
Unbalanced three-phase impedance of the motor	Replace the motor.

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th colspan="2">Fault Descriptions</th></tr>
<tr><td>23</td><td>
AUTO
Fault
EoL2
Thermal relay 2</td><td>Electronic thermal relay 2 protection (EoL2)</td><td colspan="2">Electronic thermal relay 2 protection. The drive coasts to stop once it activates.</td></tr>
<tr><td colspan="5">Action and Reset</td></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">Start counting when output current > 105% of motor 2 rated current</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Pr.06-28 (If the output current is larger than 105% of motor 2 rated current again within 60 sec., the counting time reduces and is less than Pr.06-28)</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="3">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Reset in 5 sec. after the fault is cleared</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><td colspan="2">Cause</td><td colspan="3">Corrective Actions</td></tr>
<tr><td colspan="2">The load is too large</td><td colspan="3">Reduce the load</td></tr>
<tr><td colspan="2">Accel./Decel. time or the working cycle are too short</td><td colspan="3">Increase the setting values for Pr.01-12–01-19 (accel./decel. time)</td></tr>
<tr><td colspan="2">V/F voltage is too high</td><td colspan="3">Adjust the settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed).
Refer to the V/F curve selection setting of Pr.01-43.</td></tr>
<tr><td colspan="2">Overload during low-speed operation.
When using general motor, even it operates below rated current, an overload may still occur during low-speed operation.</td><td colspan="3">Decrease low-speed operation time.
Replace the drive with a dedicated to VFD model.
Increase the motor capacity.</td></tr>
<tr><td colspan="2">When using VFD dedicated motors, Pr.06-27 = 0 (electronic thermal relay selection motor 2 = 0 inverter motor)</td><td colspan="3">Pr.06-27 = 1 Electronic thermal relay selection motor 2 = standard motor (motor with fan on the shaft).</td></tr>
<tr><td colspan="2">Incorrect value of electronic thermal relay</td><td colspan="3">Reset to the correct motor rated current.</td></tr>
<tr><td colspan="2">The maximum motor frequency is set too low</td><td colspan="3">Reset to the correct motor rated frequency.</td></tr>
<tr><td colspan="2">One drive to multiple motors</td><td colspan="3">Set Pr.06-27 = 2 Electronic thermal relay selection motor 2 = disable, and install thermal relay on each motor.</td></tr>
<tr><td colspan="2">Check if the setting for stall prevention is correct.</td><td colspan="3">Set the stall prevention to the proper value.</td></tr>
<tr><td colspan="2">Torque compensation is too large</td><td colspan="3">Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the current reduces and the motor does no stall.</td></tr>
<tr><td colspan="2">Motor fan error</td><td colspan="3">Check the status of the fan, or replace the fan.</td></tr>
<tr><td colspan="2">Unbalanced three-phase impedance of the motor</td><td colspan="3">Replace the motor.</td></tr>
</table>

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
24_1	 AUTO Fault oH3 Motor over heat	Motor overheating (oH3) PTC	Motor overheating (PTC) (Pr.03-00–Pr.03-02 = 6 PTC), when PTC input > Pr.06-30, the fault treatment acts according to Pr.06-29.

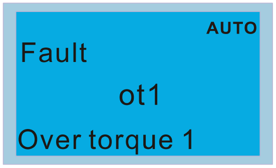
Action and Reset	
Action condition	PTC input value > Pr.06-30 setting (Default = 50%)
Action time	Immediately act
Fault treatment parameter	Pr.06-29 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning
Reset method	When Pr.06-29 = 0, oH3 is a "Warning". The "Warning" is automatically cleared. When Pr.06-29 = 1 or 2, oH3 is a "Fault". You must reset manually.
Reset condition	Immediately reset
Record	When Pr.06-29 = 1 or 2, oH3 is a "Fault", and the fault is recorded.

Cause	Corrective Actions
Motor shaft lock	Remove the shaft lock.
The load is too large	Reduce the load. Increase the motor capacity.
Ambient temperature is too high	Change the installed place if there are heating devices in the surroundings. Install/ add cooling fan or air conditioner to lower the ambient temperature.
Motor cooling system error	Check the cooling system to make it work normally.
Motor fan error	Replace the fan.
Operate at low-speed too long.	Decrease low-speed operation time. Replace the motor with a dedicated to VFD model. Increase the motor capacity.
Accel./Decel. time and working cycle are too short	Increase the setting values for Pr.01-12–01-19 (accel./decel. time)
V/F voltage is too high	Adjust settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed).
Check if the motor rated current matches that on the motor nameplate.	Reset to the correct motor rated current.
Check if the PTC is properly set and wired.	Check the connection between PTC thermistor and the heat protection.
Check if the setting for stall prevention is correct.	Set the stall prevention to the proper value.
Unbalanced three-phase impedance of the motor	Replace the motor.
Harmonics are too high.	Use remedies to reduce harmonics.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
24_2	 AUTO Fault oH3 Motor over heat	Motor overheating (oH3) PT100	Motor overheating (PT100) (Pr.03-00–Pr.03-02 = 11 PT100). When PT100 input > Pr.06-57 (default = 7 V), the fault treatment acts according to Pr.06-29.

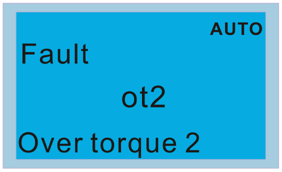
Action and Reset	
Action condition	PT100 input value > Pr.06-57 setting (default = 7 V)
Action time	Immediately act
Fault treatment parameter	Pr.06-29 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning
Reset method	When Pr.06-29 = 0 and the temperature < Pr.06-56, oH3 is automatically cleared. When Pr.06-29 = 1 or 2, oH3 is a “Fault”. You must reset manually.
Reset condition	Immediately reset
Record	When Pr.06-29 = 1 or 2, oH3 is a “Fault”, and the fault is recorded.

Cause	Corrective Actions
Motor shaft lock	Remove the shaft lock.
The load is too large	Reduce the load. Increase the motor capacity.
Ambient temperature is too high	Change the installed place If there are heating devices in the surroundings. Install/ add cooling fan or air conditioner to lower the ambient temperature.
Motor cooling system error	Check the cooling system to make it work normally.
Motor fan error	Replace the fan.
Operate at low-speed too long	Decrease low-speed operation time. Replace the motor with a dedicated to VFD model. Increase the motor capacity.
Accel./Decel. time and working cycle are too short	Increase the setting values for Pr.01-12–Pr.01-19 (accel./decel. time)
V/F voltage is too high	Adjust settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed).
Check if the motor rated current matches that on the motor nameplate.	Reset to the correct motor rated current.
Check if the PT100 is properly set and wired.	Check connection of PT100 thermistor.
Check if the setting for stall prevention is correct.	Set the stall prevention to the proper value.
Unbalanced three-phase impedance of the motor	Replace the motor.
Harmonics are too high	Use remedies to reduce harmonics.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
26	 AUTO Fault ot1 Over torque 1	Over torque 1 (ot1)	When output current exceeds the over-torque detection level (Pr.06-07) and exceeds over-torque detection time (Pr.06-08), and when Pr.06-06 or Pr.06-09 is set to 2 or 4, the ot1 error displays.

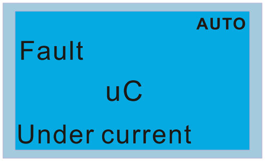
Action and Reset		
Action condition	Pr.06-07	
Action time	Pr.06-08	
Fault treatment parameter	Pr.06-06 0: No function 1: Continue operation after Over-torque detection during constant speed operation 2: Stop after Over-torque detection during constant speed operation 3: Continue operation after Over-torque detection during RUN 4: Stop after Over-torque detection during RUN	
Reset method Reset condition	Auto	When Pr.06-06 = 1 or 3, ot1 is a “Warning”. The warning is automatically cleared when the output current < (Pr.06-07 – 5%)
	Manual	When Pr.06-06 = 2 or 4, ot1 is a “Fault”. You must reset manually.
Record	Immediately reset	
Active level	When Pr.06-06 = 2 or 4, ot1 is a “Fault”, and the fault is recorded.	

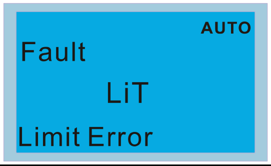
Cause	Corrective Actions
Incorrect parameter setting	Reset Pr.06-07 and Pr.06-08
Mechanical failure (e.g. over-torque, mechanical lock)	Remove the causes of malfunction.
The load is too large	Reduce the load. Replace the motor with a larger capacity model.
Accel./Decel. time and working cycle are too short	Increase the setting values for Pr.01-12–Pr.01-19 (accel./decel. time)
V/F voltage is too high	Adjust settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed).
The motor capacity is too small	Replace the motor with a larger capacity model.
Overload during low-speed operation	Decrease low-speed operation time. Increase the motor capacity.
Torque compensation is too large	Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the current reduces and the motor does no stall.
Improper parameter settings for speed tracking function (including restart after momentary power loss and restart after fault)	Correct the parameter settings for speed tracking. 1. Start the speed tracking function. 2. Adjust the maximum current for Pr.07-09 speed tracking.

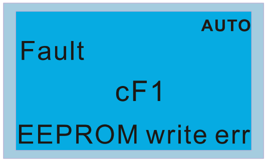
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
27	 AUTO Fault ot2 Over torque 2	Over torque 2 (ot2)	When output current exceeds the over-torque detection level (Pr.06-10) and exceeds over-torque detection time (Pr.06-11), and when Pr.06-09 is set to 2 or 4, the ot2 error displays.

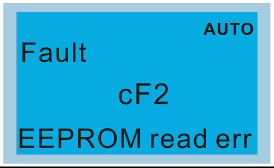
Action and Reset		
Action condition	Pr.06-10	
Action time	Pr.06-11	
Fault treatment parameter	Pr.06-09 0: No function 1: Continue operation after Over-torque detection during constant speed operation 2: Stop after Over-torque detection during constant speed operation 3: Continue operation after Over-torque detection during RUN 4: Stop after Over-torque detection during RUN	
Reset method Reset condition	Auto	When Pr.06-09 = 1 or 3, ot2 is a “Warning”. The warning is automatically cleared when the output current < (Pr.06-10 – 5%).
	Manual	When Pr.06-09 = 2 or 4, ot2 is a “Fault”. You must reset manually.
Record	Immediately reset	
Active level	When Pr.06-09 = 2 or 4, ot2 is a “Fault”, and the fault is recorded.	

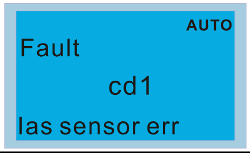
Cause	Corrective Actions
Incorrect parameter setting	Reset Pr.06-07 and Pr.06-08
Mechanical failure (e.g. over-torque, mechanical lock)	Remove the causes of malfunction.
The load is too large.	Reduce the load. Replace the motor with a larger capacity model.
Accel./Decel. time and working cycle are too short	Increase the setting values for Pr.01-12–01-19 (accel./decel. time).
V/F voltage is too high	Adjust the settings for Pr.01-01–01-08 (V/F curve), especially the setting value for the mid-point voltage (if the mid-point voltage is set too low, the load capacity decreases at low speed).
The motor capacity is too small	Replace the motor with a larger capacity model.
Overload during low-speed operation	Decrease low-speed operation time. Increase the motor capacity.
Torque compensation is too large	Adjust the torque compensation (refer to Pr.07-26 torque compensation gain) until the current reduces and the motor does no stall.
Improper parameter settings for speed tracking function (including restart at momentary power loss and restart after fault)	Correct the parameter settings for speed tracking. 1. Start the speed tracking function. 2. Adjust the maximum current for Pr.07-09 speed tracking.

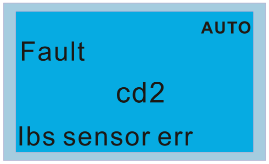
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th colspan="2">Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>28</td><td>
AUTO
Fault
uC
Under current</td><td colspan="2">Under current
(uC)</td><td>Low current detection</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">Pr.06-71</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Pr.06-72</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">Pr.06-73
0: No function
1: Fault and coast to stop
2: Fault and ramp to stop by 2nd deceleration time
3: Warn and operation continue</td></tr>
<tr><td colspan="2" rowspan="2">Reset method
Reset condition</td><td>Auto</td><td colspan="2">When Pr.06-73 = 3, uC is a “Warning”. The warning is automatically cleared when the output current > (Pr.06-71+0.1A).</td></tr>
<tr><td>Manual</td><td colspan="2">When Pr.06-73 = 1 or 2, uC is a “Fault”. You must reset manually.</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Active level</td><td colspan="3">When Pr.06-71 = 1 or 2, uC is a “Fault”, and the fault is recorded.</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Motor cable disconnection</td><td colspan="3">Troubleshoot the connection between the motor and the load.</td></tr>
<tr><td colspan="2">Improper setting of low-current protection</td><td colspan="3">Reset Pr.06-71, Pr.06-72 and Pr.06-73 to proper settings.</td></tr>
<tr><td colspan="2">The load is too low</td><td colspan="3">Check the load status.
Check if the motor capacity matches the load.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>29</td><td>
AUTO
Fault
LiT
Limit Error</td><td>Limit Error (LiT)</td><td>When MIx = 45 (forward run limit) or MIx = 44 (backward run limit) act during operation, LiT error shows.
(This error does not show on the CP2000 drive.)</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">MIx = 44 (backward run limit) or MIx = 45(forward run limit)</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">The limit ON/OFF switch is on incorrect position</td><td colspan="2">Install the limit ON/OFF switch to correct position.</td></tr>
<tr><td colspan="2">Deceleration time is too long, causing the motor cannot stop at limited position</td><td colspan="2">Reduce deceleration time.
Adjust setting values for brake level (Pr.07-01 or the insert position on the brake unit).</td></tr>
<tr><td colspan="2">The motor cannot stop due to over-voltage stall prevention</td><td colspan="2">Reset the over-voltage stall prevention.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.</td></tr>
</table>

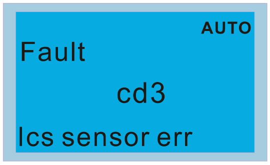
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
30	 AUTO Fault cF1 EEPROM write err	EEPROM write error (cF1)	Internal EEPROM cannot be programmed
Action and Reset			
Action condition		Firmware internal detection	
Action time		cF1 acts immediately when the drive detects the fault	
Fault treatment parameter		N/A	
Reset method		Manual reset	
Reset condition		Immediately reset	
Record		Yes	
Cause		Corrective Actions	
Internal EEPROM cannot be programmed		Press "RESET" key or reset the parameter to the default setting, if cF1 still exists, return to the factory for repair. Cycle the power, if cF1 still exists, return to the factory for repair.	

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
31	 AUTO Fault cF2 EEPROM read err	EEPROM read error (cF2)	Internal EEPROM cannot be read
Action and Reset			
Action condition		Firmware internal detection	
Action time		cF2 acts immediately when the drive detects the fault	
Fault treatment parameter		N/A	
Reset method		Manual reset	
Reset condition		Immediately reset	
Record		Yes	
Cause		Corrective Actions	
Internal EEPROM cannot be read		Press "RESET" key or reset the parameter to the default setting, if cF2 still exists, return to the factory for repair. Cycle the power, if cF2 error still exists, return to the factory for repair.	

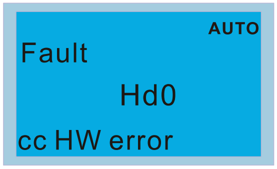
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
33	 AUTO Fault cd1 Ias sensor err	U-phase error (cd1)	U-phase current detection error when power is ON
Action and Reset			
Action condition		Hardware detection	
Action time		cd1 acts immediately when the drive detects the fault	
Fault treatment parameter		N/A	
Reset method		Power-off	
Reset condition		N/A	
Record		Yes	
Cause		Corrective Actions	
Hardware failure		Cycle the power. If cd1 still exists, return to the factory for repair.	

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
34	 AUTO Fault cd2 Ibs sensor err	V-phase error (cd2)	V-phase current detection error when power ON

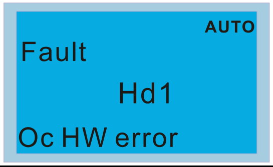
Action and Reset	
Action condition	Hardware detection
Action time	cd2 acts immediately when the drive detects the fault
Fault treatment parameter	N/A
Reset method	Power-off
Reset condition	N/A
Record	Yes
Cause	**Corrective Actions**
Hardware failure	Cycle the power. If cd2 still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
35	 AUTO Fault cd3 Ics sensor err	W-phase error (cd3)	W-phase current detection error when power ON

Action and Reset	
Action condition	Hardware detection
Action time	cd3 acts immediately when the drive detects the fault
Fault treatment parameter	N/A
Reset method	Power-off
Reset condition	N/A
Record	Yes
Cause	**Corrective Actions**
Hardware failure	Cycle the power. If cd3 still exists, return to the factory for repair.

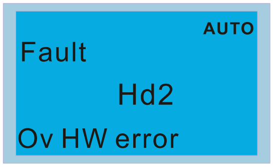
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
36	 AUTO Fault Hd0 cc HW error	cc hardware failure (Hd0)	cc (current clamp) hardware protection error when power is ON

Action and Reset	
Action condition	Hardware detection
Action time	Hd0 acts immediately when the drive detects the fault
Fault treatment parameter	N/A
Reset method	Power-off
Reset condition	N/A
Record	Yes
Cause	**Corrective Actions**
Hardware failure	Cycle the power. If Hd0 still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
37	 AUTO Fault Hd1 Oc HW error	oc hardware error (Hd1)	oc hardware protection error when power is ON

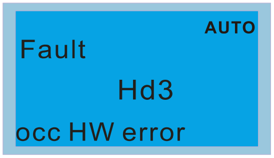
Action and Reset	
Action condition	Hardware detection
Action time	Hd1 acts immediately when the drive detects the fault
Fault treatment parameter	N/A
Reset method	Power-off
Reset condition	N/A
Record	Yes

Cause	Corrective Actions
Hardware failure	Cycle the power. If Hd1 still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
38	 AUTO Fault Hd2 Ov HW error	ov hardware error (Hd2)	ov hardware protection error when power is ON

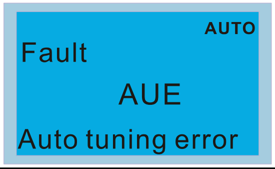
Action and Reset	
Action condition	Hardware detection
Action time	Hd2 acts immediately when the drive detects the fault
Fault treatment parameter	N/A
Reset method	Power-off
Reset condition	N/A
Record	Yes

Cause	Corrective Actions
Hardware failure	Cycle the power. If Hd2 still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
39	 AUTO Fault Hd3 occ HW error	occ hardware error (Hd3)	Protection error of occ IGBT short-circuit detection when power is ON

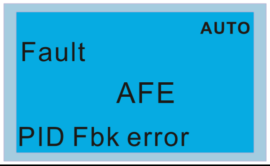
Action and Reset	
Action condition	Hardware detection
Action time	Hd3 acts immediately when the drive detects the fault
Fault treatment parameter	N/A
Reset method	Power-off
Reset condition	N/A
Record	Yes

Cause	Corrective Actions
Hardware failure	Cycle the power. If Hd3 still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
40	 AUTO Fault AUE Auto tuning error	Auto-tuning error (AUE)	Motor auto-tuning error

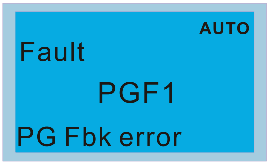
Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes

Cause	Corrective Actions
Press “STOP” key during auto-tuning	Re-execute auto-tuning.
Incorrect motor capacity (too large or too small) and parameter setting	Check motor capacity and related parameters. Set the correct parameters, that is Pr.01-01–Pr.01-02. Set Pr.01-00 larger than motor rated frequency.
Incorrect motor wiring	Check the wiring.
Motor shaft lock	Remove the cause of motor shaft lock.
The electromagnetic contactor is ON at output side (U/V/W) of the drive	Make sure the electromagnetic valve is OFF.
The load is too large.	Reduce the load. Replace the motor with a larger capacity model.
Accel./Decel. time is too short	Increase the setting values for Pr.01-12–Pr.01-19 (Accel./Decel. time).

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
41	 AUTO Fault AFE PID Fbk error	PID loss ACI (AFE)	PID feedback loss (analog feedback signal is only valid when the PID function is enabled)

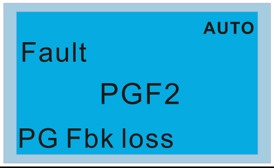
Action and Reset		
Action condition	When the analog input < 4 mA (only detects 4–20 mA analog input)	
Action time	Pr.08-08	
Fault treatment parameter	Pr.08-09 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: Warn and operate at last frequency	
Reset method	Auto	When Pr.08-09 = 3 or 4, AFE is a “Warning”. When the feedback signal is > 4 mA, the ”Warning” is automatically cleared.
	Manual	When Pr.08-09 = 1 or 2, AFE is a “Fault”. You must reset manually.
Reset condition	Immediately reset	
Record	When Pr.08-09 = 1 or 2, AFE is a “Fault”, and the fault is recorded; when Pr.08-09 = 3 or 4, AFE is a “Warning”, and the warning is not recorded.	

Cause	Corrective Actions
PID feedback cable is loose or cut off	Tighten the terminal. Replace the cable with a new one.
Feedback device failure	Replace the device with a new one.
Hardware failure	Check all the wiring. If AFE fault still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
42	 AUTO Fault PGF1 PG Fbk error	PG feedback error (PGF1)	The motor runs in a reverse direction to the frequency command direction. (This error does not show on the CP2000 drive.)

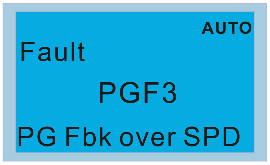
Action and Reset	
Action condition	Software detection
Action time	Pr.10-09
Fault treatment parameter	Pr.10-08 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes

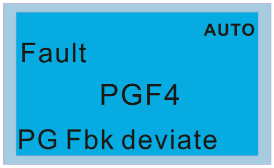
Cause	Corrective Actions
Incorrect parameter setting of encoder	Reset encoder parameter (Pr.10-02).
Check wiring of the encoder	Re-wire the encoder.
PG card or PG encoder failure	Replace PG card or encoder with a new one.
Malfunction caused by interference	Verify wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

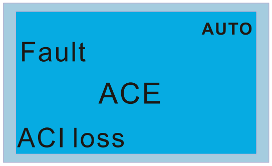
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
43	 AUTO Fault PGF2 PG Fbk loss	PG feedback loss (PGF2)	Pr.10-00 and Pr.10-02 is not set in the PG control mode. When press “RUN” key, PGF2 fault occurs. (This error does not show on the CP2000 drive.)

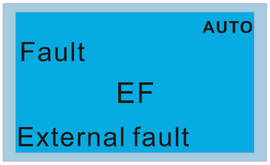
Action and Reset	
Action condition	Software detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes

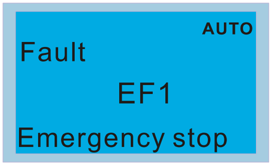
Cause	Corrective Actions
Incorrect setting of encoder parameter	Reset encoder parameters (Pr.10-00 and Pr.10-02)
Incorrect selection of the control mode	Choose the correct control mode.

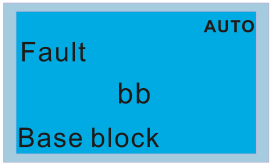
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>44</td><td>
AUTO
Fault
PGF3
PG Fbk over SPD</td><td>PG feedback stall (PGF3)</td><td>Under PG mode, when the motor frequency exceeds the encoder observer stall level (Pr.10-10) and starts to count, the fault time is longer than the detection time of encoder observer stall (Pr.10-11), then PGF3 fault occurs. (This error does not show on the CP2000 drive.)</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Pr.10-10</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Pr.10-11</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">Pr.10-12
0: Warn and keep operation
1: Fault and ramp to stop
2: Fault and coast to stop</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect setting of encoder parameter</td><td colspan="2">Reset encoder parameter (Pr.10-01)</td></tr>
<tr><td colspan="2">Pr. 01-00 is set too small</td><td colspan="2">Set proper value for Pr.01-00.</td></tr>
<tr><td colspan="2">Incorrect setting for ASR parameters and accel./decel. time</td><td colspan="2">Reset ASR parameters.
Set correct accel./decel. time.</td></tr>
<tr><td colspan="2">Incorrect setting for PG feedback stall</td><td colspan="2">Reset proper values for Pr.10-10 and Pr.10-11</td></tr>
</table>

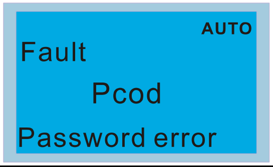
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th colspan="2">Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>45</td><td>
AUTO
Fault
PGF4
PG Fbk deviate</td><td colspan="2">PG slip error (PGF4)</td><td>Under PG mode, when the motor frequency exceeds encoder observer slip range (Pr.10-13) and starts to count, the fault time is longer than the detection time of encoder observer slip (Pr.10-14), PGF4 fault occurs.
(This error does not show on the CP2000 drive.)</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">Pr.10-13</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Pr.10-14</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">Pr.10-15
0: Warn and keep operation
1: Fault and ramp to stop
2: Fault and coast to stop</td></tr>
<tr><td colspan="2" rowspan="2">Reset method</td><td>Auto</td><td colspan="2">When Pr.10-15 = 0, PGF4 is a “Warning”, when the deviation between output frequency and motor frequency is smaller than the encoder observer slip range, the warning is automatically cleared.</td></tr>
<tr><td>Manual</td><td colspan="2">When Pr.10-15 = 1 or 2, PGF4 is a “Fault”. You must reset manually.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">When Pr.10-15 = 1 or 2, PGF4 is a “Fault”, and the fault is recorded.</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect settings for PG feedback parameters</td><td colspan="3">Reset correct values for Pr.10-13 and Pr.10-14.</td></tr>
<tr><td colspan="2">Incorrect settings for ASR parameters and accel./decel. time</td><td colspan="3">Reset ASR parameters.
Set correct accel./decel time.</td></tr>
<tr><td colspan="2">Incorrect settings of encoder parameters</td><td colspan="3">Reset encoder parameters (Pr.10-01).</td></tr>
<tr><td colspan="2">Accel./Decel. time is too short</td><td colspan="3">Reset proper accel./decel. time.</td></tr>
<tr><td colspan="2">Incorrect settings of torque limit parameters (Pr.06-12, Pr.11-17–20)</td><td colspan="3">Reset proper setting values for Pr.06-12 and Pr.11-17–Pr. 17-20.</td></tr>
<tr><td colspan="2">Motor shaft lock</td><td colspan="3">Remove causes of motor shaft lock.</td></tr>
<tr><td colspan="2">Mechanical brake is not released</td><td colspan="3">Check the action sequence of the system.</td></tr>
</table>

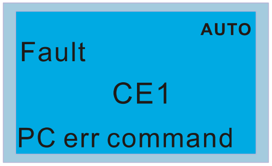
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th colspan="2">Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>48</td><td>
AUTO
Fault
ACE
ACI loss</td><td colspan="2">ACI loss
(ACE)</td><td>Analog input loss (including all the 4–20 mA analog signal)</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">When the analog in conditionput is < 4 mA (only detects 4–20 mA analog input)</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">Pr.03-19
0: Disable
1: Continue operation at the last frequency (warning, ANL is displayed on the keypad)
2: Decelerate to stop (warning, ANL is displayed on the keypad)
3: Stop immediately and display ACE</td></tr>
<tr><td colspan="2" rowspan="2">Reset method</td><td>Auto</td><td colspan="2">When Pr.03-19 = 1 or 2, ACE is a “Warning”. When analog input signal is > 4 mA, the warning is automatically cleared.</td></tr>
<tr><td>Manual</td><td colspan="2">When Pr.03-19 = 3, ACE is a “Fault”. You must reset manually.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">When Pr.03-19 = 3, ACE is a “Fault”, and the fault is recorded.</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">ACI cable is loose or cut off</td><td colspan="3">Tighten the terminal.
Replace the cable with a new one.</td></tr>
<tr><td colspan="2">External device failure</td><td colspan="3">Replace the device with a new one.</td></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="3">Check all the wiring. If ACE still exists, return to the factory for repair.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>49</td><td>
AUTO
Fault
EF
External fault</td><td>External fault (EF)</td><td>External fault. When the drive decelerates based on the setting of Pr.07-20, the EF fault displays on the keypad.</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">MIx = EF and the MI terminal is ON</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">Pr.07-20
0: Coast to stop
1: Stop by the 1st deceleration time
2: Stop by the 2nd deceleration time
3: Stop by the 3rd deceleration time
4: Stop by the 4th deceleration time
5: System deceleration
6: Automatic deceleration (Pr.01-46)</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Manual reset only after the external fault is cleared (terminal status is recovered)</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">External fault</td><td colspan="2">Press RESET key after the fault is cleared.</td></tr>
</table>

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
50	 AUTO Fault EF1 Emergency stop	Emergency stop (EF1)	When the contact of MIx = EF1 is ON, the output stops immediately and displays EF1 on the keypad. The motor is in free running.
Action and Reset			
Action condition	MIx = EF1 and the MI terminal is ON		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	Manual reset		
Reset condition	Manual reset only after the external fault is cleared (terminal status is recovered)		
Record	Yes		
Cause	Corrective Actions		
When MIx = EF1 activates	Verify if the system is back to normal condition, and then press “RESET” key to go back to the default.		

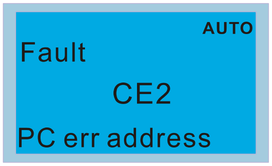
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
51	 AUTO Fault bb Base block	External base block (bb)	When the contact of MIx = bb is ON, the output stops immediately and displays bb on the keypad. The motor is in free running.
Action and Reset			
Action condition	MIx = bb and the MI terminal is ON		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	The display “bb” is automatically cleared after the fault is cleared.		
Reset condition	N/A		
Record	No		
Cause	Corrective Actions		
When MIx=bb activates	Verify if the system is back to normal condition, and then press “RESET” key to go back to the default.		

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
52	 AUTO Fault Pcod Password error	Password is locked (Pcod)	Entering the wrong password three consecutive times
Action and Reset			
Action condition	Entering the wrong password three consecutive times		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	Manual reset		
Reset condition	Power-off		
Record	Yes		
Cause	Corrective Actions		
Incorrect password input through Pr.00-07	1. Input the correct password after rebooting the motor drive. 2. If you forget the password, do the following steps: Step 1: Input 9999 and press ENTER. Step 2: Repeat step 1. Input 9999 and press ENTER. (You need to finish step 1 and step 2 within 10 seconds. If you don’t finish the two steps in 10 seconds, try again.) 3. The parameter settings return to the default when the “Input 9999” process is finished.		

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
54	 AUTO Fault CE1 PC err command	Illegal command (CE1)	Communication command is illegal

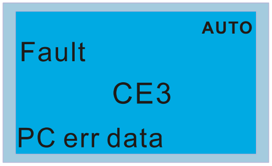
Action and Reset	
Action condition	When the function code is not 03, 06, 10, or 63.
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	No

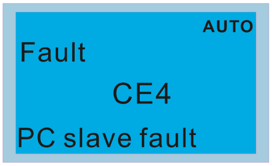
Cause	Corrective Actions
Incorrect communication command from the upper unit	Check if the communication command is correct.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from the upper unit	Check if the setting for Pr.09-02 is the same as the setting for the upper unit.
Disconnection or bad connection of the cable	Check the cable and replace it if necessary.

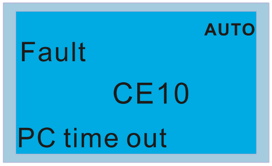
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
55	 AUTO Fault CE2 PC err address	Illegal data address (CE2)	Data address is illegal

Action and Reset	
Action condition	When the data address is correct.
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	No

Cause	Corrective Actions
Incorrect communication command from the upper unit	Check if the communication command is correct.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from the upper unit	Check if the setting for Pr.09-02 is the same as the setting for the upper unit.
Disconnection or bad connection of the cable	Check the cable and replace it if necessary.

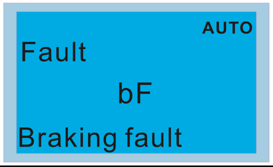
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>56</td><td>AUTO
Fault
CE3
PC err data</td><td>Illegal data value (CE3)</td><td>Data value is illegal</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When the data length is too long</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">No</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect communication command from the upper unit</td><td colspan="2">Check if the communication command is correct.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td colspan="2">Different communication setting from the upper unit</td><td colspan="2">Check if the setting for Pr.09-02 is the same as the setting for the upper unit.</td></tr>
<tr><td colspan="2">Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>57</td><td>AUTO
Fault
CE4
PC slave fault</td><td>Data is written to read-only address (CE4)</td><td>Data is written to read-only address</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When the data is written to read-only address.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">No</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Incorrect communication command from the upper unit</td><td colspan="2">Check if the communication command is correct.</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td colspan="2">Different communication setting from the upper unit</td><td colspan="2">Check if the setting for Pr.09-02 is the same as the setting for the upper unit.</td></tr>
<tr><td colspan="2">Disconnection or bad connection of the cable</td><td colspan="2">Check the cable and replace it if necessary.</td></tr>
</table>

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
58	 AUTO Fault CE10 PC time out	Modbus transmission time-out (CE10)	Modbus transmission time-out occurs

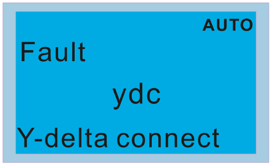
Action and Reset	
Action condition	When the communication time exceeds the detection time for Pr.09-03 time-out.
Action time	Pr.09-03
Fault treatment parameter	Pr.09-02 0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning and continue operation
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes

Cause	Corrective Actions
The upper unit does not transmit the communication command within Pr.09-03 setting time.	Check if the upper unit transmits the communication command within the setting time for Pr.09-03.
Malfunction caused by interference	Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
Different communication setting from the upper unit	Check if the setting for Pr.09-02 is the same as the setting for the upper unit.
Disconnection or bad connection of the cable	Check the cable and replace it if necessary.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
60	 AUTO Fault bF Braking fault	Brake transistor error (bF)	The brake transistor of the motor drive is abnormal. (for the models with built-in brake transistor)

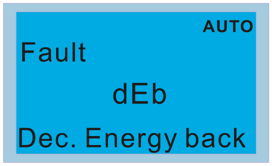
Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes

Cause	Corrective Actions
Hardware error	1. Press “RESET” key to go back to the default. If bF still exists, return to the factory for repair. 2. Power off the motor drive since the internal circuit is abnormal. Use a meter to check if it is short-circuit between B2 to DC-. If short-circuit exists, return to the factory for repair.
Malfunction caused by interference	Verify wiring/grounding of the main circuit to prevent interference.
Using the incorrect brake resistor	Check if the resistance value of the brake resistor matches to the drive.
Incorrect wiring of the brake resistor	Refer to the optional accessories instruction in chapter 7, and verify the wiring.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
61	 AUTO Fault ydc Y-delta connect	Y-connection / Δ-connection switch error (ydc)	An error occurs when Y-Δ switches

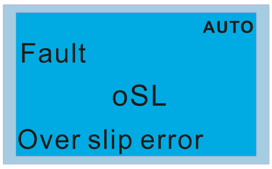
Action and Reset	
Action condition	1. ydc occurs when the confirmation signals of Y-connection and Δ-connection are conducted at the same time. 2. If any of confirmation signals is not conducted within Pr.05-25, ydc occurs.
Action time	Pr.05-25
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Can be reset only when the confirmation signal of Y-connection is conducted if it is Y-connection, or when the confirmation signal of Δ-connection is conducted if it is Δ-connection.
Record	Yes

Cause	Corrective Actions
The electromagnetic valve operates incorrectly during Y-Δ switch.	Check if the electromagnetic valve works normally. If not, replace it.
Incorrect parameter setting	Check if related parameters are all set up and set correctly.
The wiring of Y-Δ switch function is incorrect	Check the wiring.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
62	 AUTO Fault dEb Dec. Energy back	Deceleration energy backup error (dEb)	When Pr.07-13 is not 0, and the power is suddenly off, causing the DC bus voltage lower than the dEb action level, the dEb function acts and the motor ramps to stop. Then dEb displays on the keypad.

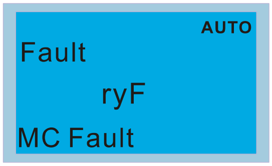
Action and Reset		
Action condition	When Pr.07-13 is not 0, and the DC bus voltage is lower than the level of dEb.	
Action time	Immediately act	
Fault treatment parameter	N/A	
Reset method	Auto	When Pr.07-13 = 2 (dEb with auto-acceleration / auto-deceleration, the drive outputs the frequency after the power is restored): dEb is automatically cleared.
	Hand	When Pr.07-13 = 1 (dEb with auto-acceleration / auto-deceleration, the drive does not output the frequency after the power is restored): The drive stops when dEb acts and the rotation speed becomes 0 Hz, then the drive can be reset manually.
Reset condition	Auto: The fault is automatically cleared. Hand: When the drive decelerates to 0 Hz.	
Record	Yes	

Cause	Corrective Actions
Unstable power source or the power is off	Check the power system.
There is any other large load operates in the power system	1. Replace power system with a larger capacity. 2. Use a different power system from the large load system.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
63	 AUTO Fault oSL Over slip error	Over slip error (oSL)	On the basis of the maximum slip limit set via Pr.10-29, the speed deviation is abnormal. When the motor drive outputs at constant speed, F > H or F < H exceeds the level set via Pr.07-29, and it exceeds the time set via Pr.07-30, oSL shows. oSL occurs in induction motors only.

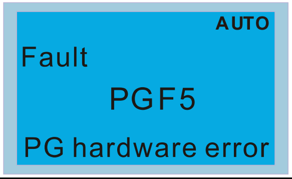
Action and Reset		
Action condition	Pr.07-29 100% of Pr.07-29 = the maximum limit of the slip frequency (Pr.10-29)	
Action time	Pr.07-30	
Fault treatment parameter	Pr.07-31 0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning	
Reset method	Auto	Pr.07-31 = 0 is a warning. When the motor drive outputs at constant speed, and F > H or F < H does not exceed the level set via Pr.07-29 anymore, oSL warning will be cleared automatically.
	Hand	When Pr.07-31 = 1 or 2, oSL is an error, and it needs to reset manually.
Reset condition	Immediately reset	
Record	Pr.07-31 = 1 or 2, oSL is “Fault”, and will be recorded.	

Cause	Corrective Actions
Any of the motor parameters in parameter group 5 may be incorrect	Check the motor parameters
Overload	Decrease the load
Any of the setting value of Pr.07-29, 07-30, and 10-29 is improper	Check the setting of oSL protection function related parameters

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
64	 AUTO Fault ryF MC Fault	Electric valve switch error (ryF)	Electric valve switch error when executing Soft Start

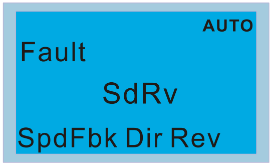
Action and Reset	
Action condition	Hardware detection (Frame D and above)
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset when the electric valve switch is correctly closed
Record	Yes

Cause	Corrective Actions
The input power is abnormal	Check if the power is shut down during the drive operation. Check if the three-phase input power is normal.
Malfunction caused by interference	Verify the wiring/grounding of the main circuit to prevent interference.
Hardware failure	Cycle the power after checking the power. If ryF error still exists, return to the factory for repair.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
65	 AUTO Fault PGF5 PG hardware error	PG hardware error (PGF5)	PG card hardware error (This error does not show on the CP2000 drive.)

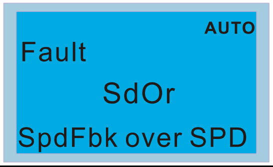
Action and Reset	
Action condition	1. Only for installing a permanent magnetic motor with PG01U/ PG02U: When powering on, Pr.00-04 = 29 < Magnetic Pole Segment> displays 0 or 7 (Wiring Error or No U,V, W Input Signal), then the keypad displays this fault code. 2. The motor drive receives a <RUN> command when powering on, but PG card is not ready to work. Then the keypad displays this fault code.
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Cycle the power to reset this fault message..
Record	Yes

Cause	Corrective Actions
Wiring Error or No U,V, W Input Signal	Re-wire correctly.
Encoder error	Verify if it is a UVW signal encoder
Incorrect setting of encoder parameter	Reset correct values for Pr.10-00
Verify if the motor selecting switch on the PG card is on the right side	Verify if using a UVW signal encoder or a Delta wire-saving encoder.
Wrong PG card	Verify if using a wrong PG card then choose a right one.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
68	 AUTO Fault SdRv SpdFbk Dir Rev	Reverse direction of the speed feedback (SdRv)	Rotating direction is different from the commanding direction detected by the sensorless

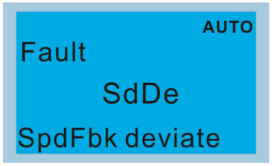
Action and Reset	
Action condition	Software detection
Action time	Pr.10-09
Fault treatment parameter	Pr.10-08 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop
Reset method	Manual reset
Reset condition	Immediately reset
Record	When Pr.10-08 = 1 or 2, SdRv is a “Fault”, and the fault is recorded.

Cause	Corrective Actions
The setting of Pr.10-25 FOC bandwidth of speed observer is improper	Decrease the setting of Pr.10-25
The setting of motor parameter is incorrect	Reset the motor parameter and execute parameter tuning
The motor cable is abnormal or broken	Check if the cable is well functioned or replace the cable
A reverse force is exerted, or the motor runs in a reverse direction at start	Start speed tracking function (Pr.07-12)
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
69	 AUTO Fault SdOr SpdFbk over SPD	Over speed rotation feedback (SdOr)	Over speed rotation detected by sensorless

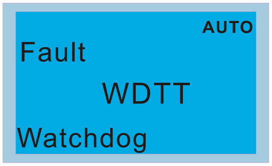
Action and Reset	
Action condition	Pr.10-10
Action time	Pr.10-11
Fault treatment parameter	Pr.10-12 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop
Reset method	Manual reset
Reset condition	Immediately reset
Record	When Pr.10-12 = 1 or 2, SdOr is a “Fault”, and the fault is recorded.

Cause	Corrective Actions
The setting of Pr.10-25 FOC bandwidth of speed observer is improper	Decrease the setting of Pr.10-25
The setting of ASR bandwidth of speed controller is improper	Increase the bandwidth of ASR speed controller
The setting of motor parameter is incorrect	Reset motor parameter and execute parameter tuning
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
70	 AUTO Fault SdDe SpdFbk deviate	Large deviation of speed feedback (SdDe)	A large deviation between the rotating speed and the command detected by the sensorless

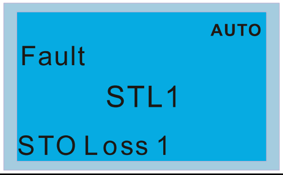
Action and Reset	
Action condition	Pr.10-13
Action time	Pr.10-14
Fault treatment parameter	Pr.10-15 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop
Reset method	Manual reset
Reset condition	Immediately reset
Record	When Pr.10-15 = 1 or 2, SdDe is a “Fault”, and the fault is recorded.

Cause	Corrective Actions
Improper parameter setting for abnormal rotating slip function	Reset proper setting for Pr.10-13 and Pr.10-14
Improper parameter setting for ASR and acceleration/deceleration	Reset ASR parameters Set proper acceleration/deceleration time
The acceleration/deceleration time is too short	Reset proper acceleration/deceleration time
Motor shaft lock	Remove the cause of motor shaft lock
The mechanical brake is not released	Verify the system action timeline
Incorrect parameter setting for torque limit (Pr.06-12, Pr.11-17–20)	Adjust the setting to proper value
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.

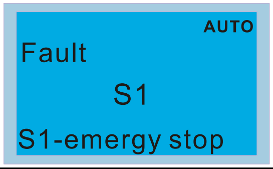
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
71	 AUTO Fault WDTT Watchdog	Watchdog（WDTT）	Watchdog error

Action and Reset	
Action condition	Hardware detection
Action time	N/A
Fault treatment parameter	N/A
Reset method	Hardware failure, and cannot reset. Cycle the power.
Reset condition	N/A
Record	Yes

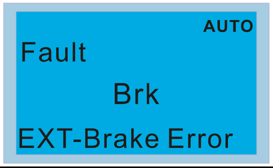
Cause	Corrective Actions
Hardware interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference. If the WDTT fault still exists, return to the factory for repair.

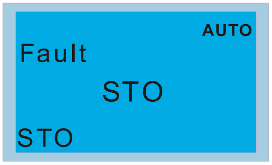
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
72	AUTO Fault STL1 STO Loss 1	STO Loss 1 (STL1)	STO1–SCM1 internal loop detection error

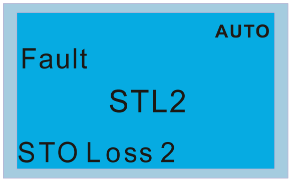
Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Hardware failure, and cannot reset. Cycle the power.
Reset condition	N/A
Record	Yes
Cause	Corrective Actions
STO1 and SCM1 short circuit lines are not connected	Connect the short circuit line
Hardware failure	After you make sure all the wiring is correct, if STOL fault still exists after cycling the power, please return to the factory for repair.
Bad connection of the IO card	Check if the PIN of IO card is broken. Check if the IO card connects to the control board correctly, and if the screws are tightened well.
The IO card does not match the version of the control board	Contact local agent or Delta

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
73	AUTO Fault S1 S1-emergy stop	Emergency stop for external safety (S1)	Emergency stop for external safety

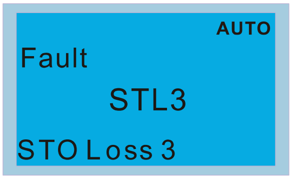
Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset only after S1 error is cleared.
Record	Yes
Cause	Corrective Actions
The switch action of S1 and SCM (OPEN)	Reset the switch and cycle the power.
S1 and SCM short circuit lines are not connected	Re-connect the short circuit lines
Malfunction caused by interference	Verify the wiring/grounding of the main circuit, control circuit and encoder to prevent interference.
Hardware failure	If S1 fault still exists after cycling the power, please return to the factory for repair.
Poor connection of the IO card	Check if the PIN of IO card is broken. Check if the IO card connects to the control board correctly, and if the screws are tightened well.
The IO card does not match the version of the control board	Contact local agent or Delta

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th colspan="2">Fault Descriptions</th></tr>
<tr><td>75</td><td>
AUTO
Fault
Brk
EXT-Brake Error</td><td>External brake error (Brk)</td><td colspan="2">External mechanical brake error
The MO terminal is active when MOx = 12, 42, 47 or 63, but the MIx = 55 does not receive signal for mechanical brake action during the set time of Pr.02-56.</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">MIx = 55 did not receive signal for the mechanical brake action during the set time of Pr.02-56.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Pr.02-56</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="3">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Mechanical brake error</td><td colspan="3">Verify if the mechanical brake can work correctly.
Replace mechanical brake.</td></tr>
<tr><td colspan="2">Incorrect parameter setting</td><td colspan="3">If there is no brake-confirming signal to use, set Pr.02-56 = 0.</td></tr>
<tr><td colspan="2">Signal cable is loose or cut off</td><td colspan="3">Tighten the screws.
Replace the signal cable with a new one.</td></tr>
<tr><td colspan="2">The time of Pr.02-56 is set too short</td><td colspan="3">Increase the time setting of Pr.02-56</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="3">Verify the wiring/grounding of the main circuit, control circuit and encoder to prevent interference.</td></tr>
</table>

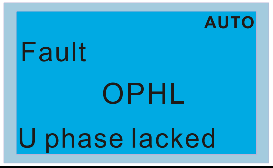
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th colspan="2">Fault Descriptions</th></tr>
<tr><td>76</td><td>
AUTO
Fault
STO
STO</td><td>STO (STO)</td><td colspan="2">Safety Torque Off function active</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">Hardware detection</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2" rowspan="2">Reset method</td><td>Auto</td><td colspan="2">When Pr.06-44 = 1 and after STO error is cleared, it automatically resets.</td></tr>
<tr><td>Manual</td><td colspan="2">When Pr.06-44 = 0 and after STO error is cleared, reset it manually.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Reset only after STO error is cleared.</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">The switch action of STO1/SCM1 and STO2/SCM2 (OPEN)</td><td colspan="3">Reset the switch (ON) and cycle the power</td></tr>
<tr><td colspan="2">Poor connection of the IO card</td><td colspan="3">Check if the PIN of IO card is broken.
Check if the IO card connects to the control board correctly, and if the screws are tightened well.</td></tr>
<tr><td colspan="2">The IO card does not match the version of the control board</td><td colspan="3">Contact local agent or Delta</td></tr>
</table>

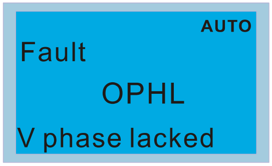
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
77	 AUTO Fault STL2 STO Loss 2	STO Loss 2 (STL2)	STO2–SCM2 internal loop detection error

Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Hardware failure, and cannot reset. Cycle the power.
Reset condition	N/A
Record	Yes
Cause	**Corrective Actions**
STO2 and SCM2 short circuit lines are not connected	Connect the short circuit lines
Hardware failure	After you make sure all the wiring is correct, if STL2 fault still exists after cycling the power, please return to the factory for repair.
Poor connection of the IO card	Check if the PIN of IO card is broken. Check if the IO card connects to the control board correctly, and if the screws are tightened well.
The IO card does not match the version of the control board	Contact local agent or Delta

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
78	 AUTO Fault STL3 STO Loss 3	STO Loss 3 (STL3)	STO1–SCM1 and STO2–SCM2 internal loop detection error

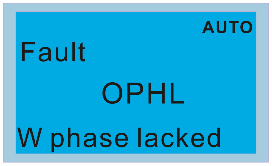
Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Hardware failure, and cannot reset. Cycle the power.
Reset condition	N/A
Record	Yes
Cause	**Corrective Actions**
STO1 and SCM1, or STO2 and SCM2 short circuit lines are not connected	Re-connect the short circuit lines
Hardware failure	After you make sure all the wiring is correct, if STL3 fault still exists after cycling the power, please return to the factory for repair.
Poor connection of the IO card	Check if the PIN of IO card is broken. Check if the IO card connects to the control board correctly, and if the screws are tightened well.
The IO card does not match the version of the control board	Contact local agent or Delta

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
82	 AUTO Fault OPHL U phase lacked	Output phase loss U phase (OPHL)	U phase output phase loss
Action and Reset			
Action condition		Pr.06-47	
Action time		Pr.06-46 Pr.06-48: Use the setting value of Pr.06-48 first if there is DC braking function, and then use that of Pr.06-46.	
Fault treatment parameter		Pr.06-45 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning	
Reset method		Manual reset	
Reset condition		Immediately reset	
Record		Pr.06-45=1 or 2 is "Fault", and will be recorded.	
Cause		Corrective Actions	
The three-phase impedance of motor is unbalanced		Replace the motor.	
The motor is wired incorrectly		Check the cable condition. Replace the cable.	
Using a single-phase motor		Choose a three-phase motor	
The current sensor is damaged		Check the flat cable of the control board. Re-do the wiring and test again if the flat cable is loose. If the fault still exists, return the unit to the factory. Verify that the three-phase current is balanced via a current clamp meter. If it is balanced and the OPHL fault still exists, return the unit to the factory	
The drive capacity is much larger than the motor capacity		Make sure the capacity of the drive and motor match to each other.	

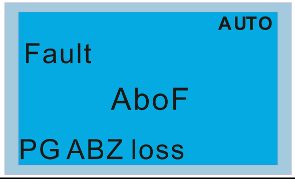
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
83	 AUTO Fault OPHL V phase lacked	Output phase loss V phase (OPHL)	V phase output phase loss

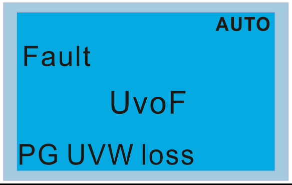
Action and Reset	
Action condition	Pr.06-47
Action time	Pr.06-46 Pr.06-48: Use the setting value of Pr.06-48 first. If DC braking function activates, use that of Pr.06-46.
Fault treatment parameter	Pr.06-45 0: Warn and keep operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning
Reset method	Manual reset
Reset condition	Immediately reset
Record	When Pr.06-45 = 1 or 2, OPHL is a “Fault”, and the fault is recorded.

Cause	Corrective Actions
Unbalanced three-phase impedance of the motor	Replace the motor.
Check if the wiring is incorrect	Check the cable and replace it if necessary.
Check if the motor is a single-phase motor	Choose a three-phase motor.
Check if the current sensor is broken	Check if the control board cable is loose. If yes, reconnect the cable and run the drive to test. If the fault still exists, return to the factory for repair. Check if the three-phase current is balanced with a current clamp meter. If the current is balanced and the OPHL fault still exists, return to the factory for repair.
Check if the drive capacity is larger than the motor capacity	Choose the drive that matches the motor capacity

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
84	 AUTO Fault OPHL W phase lacked	Output phase loss W phase (OPHL)	W phase output phase loss

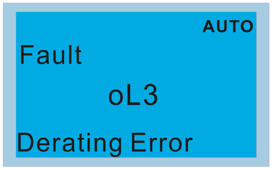
Action and Reset	
Action condition	Pr.06-47
Action time	Pr.06-46 Pr.06-48: Use the setting value of Pr.06-48 first. If DC braking function activates, use that of Pr.06-46.
Fault treatment parameter	Pr.06-45 0: Warn and continue operation 1: Fault and ramp to stop 2: Fault and coast to stop 3: No warning
Reset method	Manual reset
Reset condition	Immediately reset
Record	When Pr.06-45 = 1 or 2, OPHL is a “Fault”, and the fault is recorded.
Cause	**Corrective Actions**
Unbalanced three-phase impedance of the motor	Replace the motor.
Check if the wiring is incorrect	Check the cable and replace it if necessary.
Check if the motor is a single-phase motor	Choose a three-phase motor.
Check if the current sensor is broken	Check if the control board cable is loose. If yes, reconnect the cable and run the drive to test. If the fault still exists, return to the factory for repair. Check if the three-phase current is balanced with a current clamp meter. If the current is balanced and the OPHL fault still exists, return to the factory for repair.
Check if the drive capacity is larger than the motor capacity	Choose the drive that matches the motor capacity

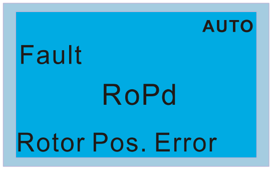
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th colspan="2">Fault Descriptions</th></tr>
<tr><td>85</td><td>
AUTO
Fault
AboF
PG ABZ loss</td><td>PG ABZ loss protection (AboF)</td><td colspan="2">When using PG02U card, the protection for ABZ loss
(This error does not show on the CP2000 drive.)</td></tr>
<tr><td colspan="5">Action and Reset</td></tr>
<tr><td colspan="3">Action condition</td><td colspan="2">Hardware detection</td></tr>
<tr><td colspan="3">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="3">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="3">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="3">Reset condition</td><td colspan="2">Reset Immediately reset</td></tr>
<tr><td colspan="3">Record</td><td colspan="2">Yes</td></tr>
<tr><td colspan="3">Cause</td><td colspan="2">Corrective Actions</td></tr>
<tr><td colspan="3">PG card signal cable is not wired or is broken</td><td colspan="2">Re-wire the PG card</td></tr>
<tr><td colspan="3">PG card screws are loose.</td><td colspan="2">Tighten all PG card *screws*.</td></tr>
<tr><td colspan="3">Malfunction caused by interference</td><td colspan="2">Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.</td></tr>
<tr><td colspan="3">Hardware failure</td><td colspan="2">1. Cycle the power. If the keypad still displays AboF, return to the factory for repair.
2. The VP power on the PG card does not output power or has abnormal voltage level.
3. Encoder is broken.</td></tr>
<tr><td colspan="3">Using a cable between the encoder and the PG card that is too long causes a VP voltage drop that is too large.</td><td colspan="2">1. Reduce the cable length
2. Use power from another source to supply power to the encoder.</td></tr>
</table>

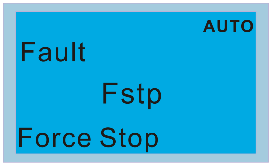
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
86	 AUTO Fault UvoF PG UVW loss	PG UVW loss protection (UvoF)	When using PG02U card, the protection for UVW loss (This error does not show on the CP2000 drive.)

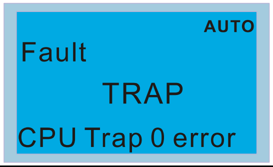
Action and Reset	
Action condition	Hardware detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Reset Immediately reset
Record	Yes

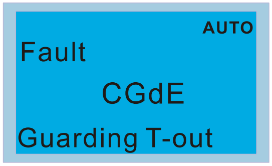
Cause	Corrective Actions
PG card signal cable is not wired or is broken	Re-wire the PG card
PG card screws are loose.	Tighten all PG card *screws*.
Malfunction caused by interference	Verify the wiring of the control circuit and wiring/grounding of the main circuit to prevent interference.
Hardware failure	1. Cycle the power. If the keypad still displays AboF, return to the factory for repair. 2. The VP power on the PG card doesnot output power or has abnormal voltage level. 3. Encoder is broken.
Using a cable between the encoder and the PG card that is too long causes a VP voltage drop that is too large.	1. Reduce the cable length 2. Supply power to the encoder from another power source

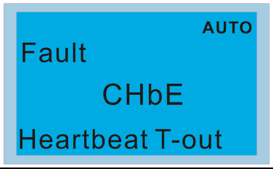
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>87</td><td>
AUTO
Fault
oL3
Derating Error</td><td>Overload protection at low frequency (oL3)</td><td>Low frequency and high current protection</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Software detection</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">The drive operates at a frequency below 15 Hz, and output current is too large.</td><td colspan="2">1. Enhance the heat dissipation capacity for the cabinet.
2. Lower the carrier frequency (Pr.00-17).
3. Decrease the voltage settings that correspond to frequency below 15 Hz in the V/F curve.
4. Change Pr.00-11 to general control mode.
5. Replace the drive with a larger power model.</td></tr>
</table>

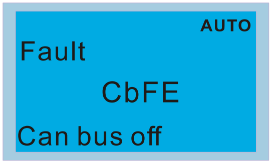
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>89</td><td>
AUTO
Fault
RoPd
Rotor Pos. Error</td><td>Rotor position detection error (RoPd)</td><td>Rotor position detection error protection</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Software detection</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Check if the motor cable is abnormal or broken</td><td colspan="2">Check or replace the cable.</td></tr>
<tr><td colspan="2">Motor coil error</td><td colspan="2">Replace the motor.</td></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="2">IGBT broken. Return to the factory for repair.</td></tr>
<tr><td colspan="2">Drive’s current feedback line error</td><td colspan="2">Cycle the power. If RoPd still occurs during operation, return to the factory for repair.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th colspan="2">Fault Descriptions</th></tr>
<tr><td>90</td><td>
AUTO
Fault
Fstp
Force Stop</td><td>Force to stop (FStp)</td><td colspan="2">Keypad forces PLC to Stop</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">When Pr.00-32 = 1, STOP button on the keypad is valid. When giving the STOP command during the PLC operation, FStp fault will active.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="3">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Pr.00-32 = 1: keypad STOP button is valid</td><td colspan="3">Check if it is necessary to set Pr.00-32 = 0, so the keypad STOP button is invalid.</td></tr>
<tr><td colspan="2">Press STOP button during PLC operation</td><td colspan="3">Verify the timing of STOP function.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th colspan="2">Fault Descriptions</th></tr>
<tr><td>93</td><td>
AUTO
Fault
TRAP
CPU Trap 0 error</td><td>CPU error 0 (TRAP)</td><td colspan="2">CPU crash</td></tr>
<tr><th colspan="5">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="3">Hardware detection</td></tr>
<tr><td colspan="2">Action time</td><td colspan="3">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="3">Cannot reset, power off.</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="3">N/A</td></tr>
<tr><td colspan="2">Record</td><td colspan="3">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="3">Corrective Actions</th></tr>
<tr><td colspan="2">Hardware interference</td><td colspan="3">Verify the wiring of control circuit, and the wiring/grounding of the main circuit to prevent interference.
If TRAP fault still exists, return to the factory for repair.</td></tr>
<tr><td colspan="2">Hardware failure</td><td colspan="3">Return to the factory for repair.</td></tr>
<tr><td colspan="2">CPU is in an infinite loop</td><td colspan="3">Cycle the power. If the TRAP fault still exists, return to the factory for repair.</td></tr>
</table>

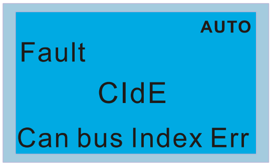
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>101</td><td>AUTO
Fault
CGdE
Guarding T-out</td><td>CANopen guarding error (CGdE)</td><td>CANopen guarding error</td></tr>
<tr><td colspan="4">Action and Reset</td></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When CANopen Node Guarding detects that one of the slaves does not response, the CGdE fault will activate.
The upper unit sets factor and time during configuration.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">The time that upper unit sets during configuration</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">The upper unit sends a reset package to clear this fault</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><td colspan="2">Cause</td><td colspan="2">Corrective Actions</td></tr>
<tr><td colspan="2">The guarding time is too short, or less detection times</td><td colspan="2">Increase the guarding time (Index 100C) and detection times</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
2. Make sure the communication circuit is wired in series.
3. Use CANopen cable or add terminating resistance.</td></tr>
<tr><td colspan="2">Communication cable is broken or bad connected</td><td colspan="2">Check or replace the communication cable.</td></tr>
</table>

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>102</td><td>AUTO
Fault
CHbE
Heartbeat T-out</td><td>CANopen heartbeat error (CHbE)</td><td>CANopen heartbeat error</td></tr>
<tr><td colspan="4">Action and Reset</td></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">When CANopen Heartbeat detects that one of the slaves does not response, the CHbE fault will activate.
The upper unit sets the confirming time of producer and consumer during configuration.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">The confirming time that upper unit sets for producer and consumer during configuration.</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">The upper unit sends a reset package to clear this fault</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><td colspan="2">Cause</td><td colspan="2">Corrective Actions</td></tr>
<tr><td colspan="2">The heartbeat time is too short</td><td colspan="2">Increase heartbeat time (Index 100C)</td></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.
2. Make sure the communication circuit is wired in series.
3. Use CANopen cable or add terminating resistance.</td></tr>
<tr><td colspan="2">Communication cable is broken or bad connected</td><td colspan="2">Check or replace the communication cable.</td></tr>
</table>

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
104	 AUTO Fault CbFE Can bus off	CANopen bus off error (CbFE)	CANopen bus off error

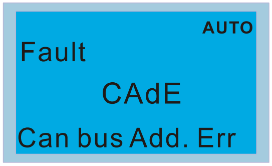
Action and Reset		
Action condition	Hardware	When CANopen card is not installed, CbFE fault will occur.
	Software	When the master received wrong communication package, CbFE fault will occur. Too much interference on BUS When the CAN_H and CAN_L communication cable is short, the master will receive wrong package, and CbFE fault will occur.
Action level	Immediately act	
Fault treatment parameter	N/A	
Reset method	Manual reset	
Reset condition	Cycle the power	
Record	Yes	

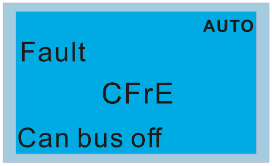
Cause	Corrective Actions
Check if the CANopen card is installed	Make sure the CANopen card is installed.
Check if the CANopen speed is correct	Reset CANopen speed (Pr.09-37)
Malfunction caused by interference	1. Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance. 2. Make sure the communication circuit is wired in series. 3. Use CANopen cable or add terminating resistance.
Communication cable is broken or bad connected	Check or replace the communication cable.

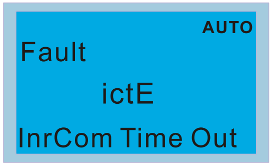
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
105	 AUTO Fault CIdE Can bus Index Err	CANopen index error (CIdE)	CANopen index error

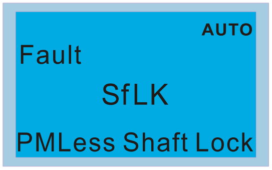
Action and Reset	
Action condition	Software detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Upper unit sends a reset package to clear this fault
Record	Yes

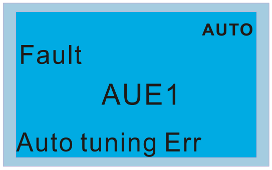
Cause	Corrective Actions
Incorrect setting of CANopen index	Reset CANopen Index (Pr.00-02 = 7)

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
106	 AUTO Fault CAdE Can bus Add. Err	CANopen station address error (CAdE)	CANopen station address error (only supports 1–127)
Action and Reset			
Action condition	Software detection		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	Manual reset (Pr.00-02 = 7)		
Reset condition	N/A		
Record	Yes		
Cause	Corrective Actions		
Incorrect setting of CANopen station address	1. Disable CANopen (Pr.09-36 = 0) 2. Reset CANopen (Pr.00-02 = 7) 3. Reset CANopen station address (Pr.09-36)		

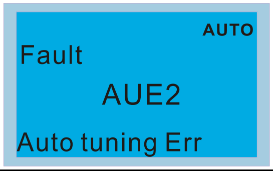
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
107	 AUTO Fault CFrE Can bus off	CANopen memory error (CFrE)	CANopen memory error
Action and Reset			
Action condition	When the user update firmware version of the control board, the FRAM internal data will not be changed, and then CFrE fault will occur.		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	Manual reset		
Reset condition	Pr.00-02 = 7		
Record	Pr.00-21 = 3, the fault is recorded		
Cause	Corrective Actions		
CANopen internal memory error	1. Disable CANopen (Pr.09-36 = 0) 2. Reset CANopen (Pr.00-02 = 7) 3. Reset CANopen station address (Pr.09-36)		

<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>111</td><td>
AUTO
Fault
ictE
InrCom Time Out</td><td>InrCOM time-out error (ictE)</td><td>Internal communication time-out</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Pr.09-31 = -1 – -10 (there is no -9), when the internal communication between Slave and Master is abnormal, IctE fault will occur.</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">Immediately act</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Automatically reset after the internal communication is normal</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Malfunction caused by interference</td><td colspan="2">Verify the wiring and grounding of the communication circuit. It is recommended to separate the communication circuit from the main circuit, or wire in 90 degree for effective anti-interference performance.</td></tr>
<tr><td colspan="2">The communication condition is different with the upper unit</td><td colspan="2">Verify the setting of Pr.09-02 is the same as the setting of upper unit.</td></tr>
<tr><td colspan="2">Communication cable is broken or bad connected</td><td colspan="2">Check or replace the communication cable.</td></tr>
</table>

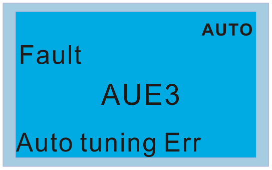
<table>
<tr><th>ID</th><th>Display on LCD Keypad</th><th>Fault Name</th><th>Fault Descriptions</th></tr>
<tr><td>112</td><td>
AUTO
Fault
SfLK
PMLess Shaft Lock</td><td>PMLess shaft lock (SfLK)</td><td>The drive has RUN command with output frequency, but the permanent magnetic motor does not turn.</td></tr>
<tr><th colspan="4">Action and Reset</th></tr>
<tr><td colspan="2">Action condition</td><td colspan="2">Software detection</td></tr>
<tr><td colspan="2">Action time</td><td colspan="2">3 sec.</td></tr>
<tr><td colspan="2">Fault treatment parameter</td><td colspan="2">N/A</td></tr>
<tr><td colspan="2">Reset method</td><td colspan="2">Manual reset</td></tr>
<tr><td colspan="2">Reset condition</td><td colspan="2">Immediately reset</td></tr>
<tr><td colspan="2">Record</td><td colspan="2">Yes</td></tr>
<tr><th colspan="2">Cause</th><th colspan="2">Corrective Actions</th></tr>
<tr><td colspan="2">Improper setting of the speed observer bandwidth</td><td colspan="2">Increase the setting value.</td></tr>
<tr><td colspan="2">Motor shaft lock</td><td colspan="2">Remove causes of the motor shaft lock.</td></tr>
<tr><td colspan="2">Motor error (e.g. demagnetization)</td><td colspan="2">Replace the motor with a new one.</td></tr>
</table>

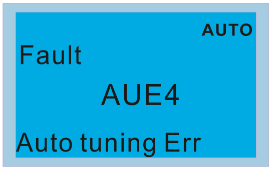
ID	Display on LCD Keypad	Fault Name	Fault Descriptions
142	 AUTO Fault AUE1 Auto tuning Err	Auto-tune error 1 (AUE1)	No feedback current error when motor parameter automatically detects

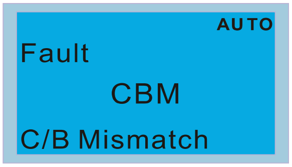
Action and Reset	
Action condition	Software detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes
Cause	Corrective Actions
Motor is not wired	Wire the motor correctly
The electromagnetic contactor is used as an open state on the output side of the drive (U/V/W).	Verify that the electromagnetic valve is closed.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
143	 AUTO Fault AUE2 Auto tuning Err	Auto-tune error 2 (AUE2)	Motor phase loss error when motor parameter automatically detects

Action and Reset	
Action condition	Software detection
Action time	Immediately act
Fault treatment parameter	N/A
Reset method	Manual reset
Reset condition	Immediately reset
Record	Yes
Cause	Corrective Actions
Incorrect motor wiring	Wire the motor correctly.
Motor error	Check if the motor works normally.
The electromagnetic contactor is used as an open state on the output side of the drive (U/V/W).	Verify that the three-phases of the electromagnetic valve are all closed.
Motor U/V/W wire error	Check if the wires are broken.

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
144	 AUTO Fault AUE3 Auto tuning Err	Auto-tune error 3 (AUE3)	No load current I_0 measurement error when motor parameter automatically detects.
Action and Reset			
Action condition	Software detection		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	Manual reset		
Reset condition	Immediately reset		
Record	Yes		
Cause	Corrective Actions		
Incorrect settings for the motor parameter (rated current)	Check the settings for Pr.05-01 / Pr.05-13 / Pr.05-34.		
Motor error	Check if the motor works normally.		

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
148	 AUTO Fault AUE4 Auto tuning Err	Auto-tune error 4 (AUE4)	Leakage inductance Lsigma measurement error when motor parameter automatically detects.
Action and Reset			
Action condition	Software detection		
Action time	Immediately act		
Fault treatment parameter	N/A		
Reset method	Manual reset		
Reset condition	Immediately reset		
Record	Yes		
Cause	Corrective Actions		
Motor error	Check if the motor works normally.		
Incorrect setting of motor parameters (base frequency)	Check the setting of Pr.01-01.		

ID	Display on LCD Keypad	Fault Name	Fault Descriptions
170	 AUTO Fault CBM C/B Mismatch	C/B mismatch (CBM)	Control board matching error (This error does not show on the CP2000 drive.)
Action and Reset			
Action condition	N/A		
Action time	Acts when turning on the drive		
Fault treatment parameter	N/A		
Reset method	Cannot reset		
Reset condition	Cannot reset		
Record	Yes		
Cause	Corrective Actions		
Incorrect control board	Replace with the correct control board. If the CBM still exists, contact Delta for further confirmation.		

Chapter 15 CANopen Overview

The built-in CANopen function is a kind of remote control. You can control the AC motor drive using the CANopen protocol. CANopen is a CAN-based higher layer protocol that provides standardized communication objects, including real-time data (Process Data Objects, PDO), configuration data (Service Data Objects, SDO), and special functions (Time Stamp, Sync message, and Emergency message). It also has network management data, including Boot-up message, NMT message, and Error Control message. Refer to CiA website http://www.can-cia.org/ for details.

Delta CANopen supporting functions:

- Support CAN2.0A Protocol;
- Support CANopen DS301 V4.02;
- Support DSP-402 V2.0.

Delta CANopen supporting services:

- PDO (Process Data Objects): PDO1–PDO4
- SDO (Service Data Object):
  Initiate SDO Download;
  Initiate SDO Upload;
  Abort SDO;
  You can use the SDO message to configure the slave node and access the Object Dictionary in every node.
- SOP (Special Object Protocol):
  Support default COB-ID in Predefined Master/Slave Connection Set in DS301 V4.02;
  Support SYNC service;
  Support Emergency service.
- NMT (Network Management):
  Support NMT module control;
  Support NMT Error control;
  Support Boot-up.

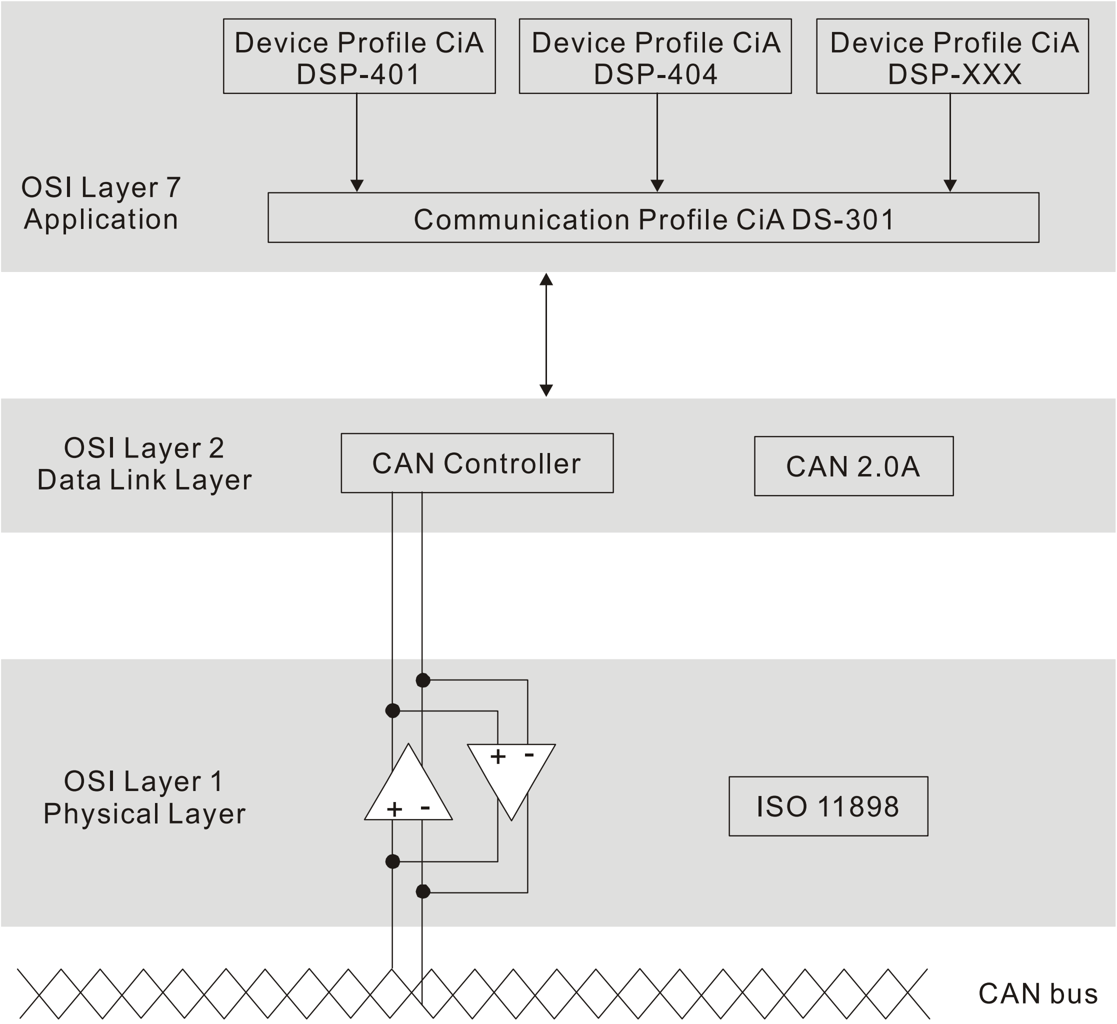
Delta CANopen not supporting service:

- Time Stamp service

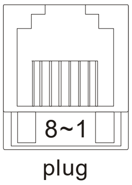
15-1 CANopen Overview

CANopen Protocol

CANopen is a CAN-based higher layer protocol, and was designed for motion-oriented machine control networks such as handling systems. Version 4.02 of CANopen (CiA DS301) is standardized as EN50325-4. The CANopen specifications cover the application layer and communication profile (CiA DS301), as well as a framework for programmable devices (CiA DS302), recommendations for cables and connectors (CiA DS303-1) and SI units and prefix representations (CiA DS303-2).


Device Profile CiA DSP-401
Device Profile CiA DSP-404
Device Profile CiA DSP-XXX
OSI Layer 7 Application
Communication Profile CiA DS-301
OSI Layer 2 Data Link Layer
CAN Controller
CAN 2.0A
OSI Layer 1 Physical Layer
+ -
+ -
ISO 11898
CAN bus

RJ45 Pin Definition



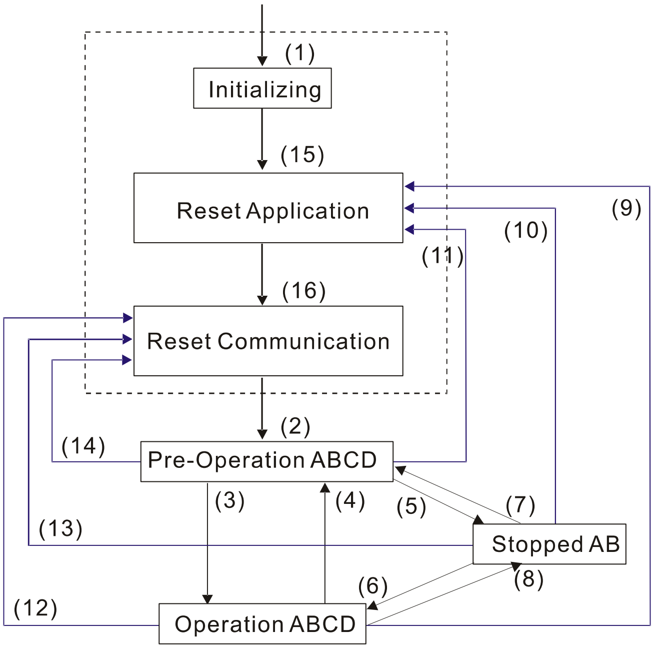
PIN	Signal	Description
1	CAN_H	CAN_H bus line (dominant high)
2	CAN_L	CAN_L bus line (dominant low)
3	CAN_GND	Ground / 0V / V-
6	CAN_GND	Ground / 0V / V-

CANopen Communication Protocol contains the following services:

- NMT (Network Management Object)
- SDO (Service Data Objects)
- PDO (Process Data Object)
- EMCY (Emergency Object)

NMT (Network Management Object)

The Network Management (NMT) follows a Master/Slave structure for executing NMT service. A network has only one NMT master, and the other nodes are slaves. All CANopen nodes have a present NMT state, and the NMT master can control the state of the slave nodes. The following shows the state diagram of a node:



(1) After power is applied, start in the auto-initialization state
(2) Automatically enter the pre-operational state
(3) (6) Start remote node
(4) (7) Enter pre-operational state
(5) (8) Stop remote node
(9) (10) (11) Reset node
(12) (13) (14) Reset communication
(15) Automatically enter the reset application state
(16) Automatically enter the reset communication state

A: NMT
B: Node Guard
C: SDO
D: Emergency
E: PDO
F: Boot-up

	Initializing	Pre-Operational	Operational	Stopped
PDO			○	
SDO		○	○	
SYNC		○	○	
Time Stamp		○	○	
EMCY		○	○	
Boot-up	○			
NMT		○	○	○

SDO (Service Data Objects)

Use SDO to access the Object Dictionary in every CANopen node using the Client / Server model. One SDO has two COB-ID (request SDO and response SDO) to upload or download data between two nodes. There is no data limit for SDOs to transfer data, but it must transfer data by segment when the data exceeds four bytes with an end signal in the last segment.

The Object Dictionary (OD) is a group of objects in a CANopen node. Every node has an OD in the system, and OD contains all parameters describing the device and its network behavior. The access path in the OD is the index and sub-index; each object has a unique index in the OD, and has a sub-index if necessary.

PDO (Process Data Object)

PDO communication can be described by the producer / consumer model. Each node of the network listens to the messages of the transmission node and distinguishes whether the message has to be processed or not after receiving the message. A PDO can be transmitted from one device to one another device or to many other devices. Every PDO has two PDO services: a TxPDO and an RxPDO. PDOs are transmitted in a non-confirmed mode. All transmission types are listed in the following table:

Type Number	PDO				
	Cyclic	Acyclic	Synchronous	Asynchronous	RTR only
0		○	○		
1–240	○		○		
241–251	Reserved				
252			○		○
253				○	○
254				○	
255				○	

- Type number 0 indicates the synchronous aperiodic message between two PDO transmissions.
- Type number 1–240 indicates the number of SYNC message between two PDO transmissions.
- Type number 252 indicates the data is updated (but not sent) immediately after receiving SYNC.
- Type number 253 indicates the data is updated immediately after receiving RTR.
- Type number 254 indicates that Delta CANopen does not support this transmission format.
- Type number 255 indicates the data is an asynchronous aperiodic transmission.

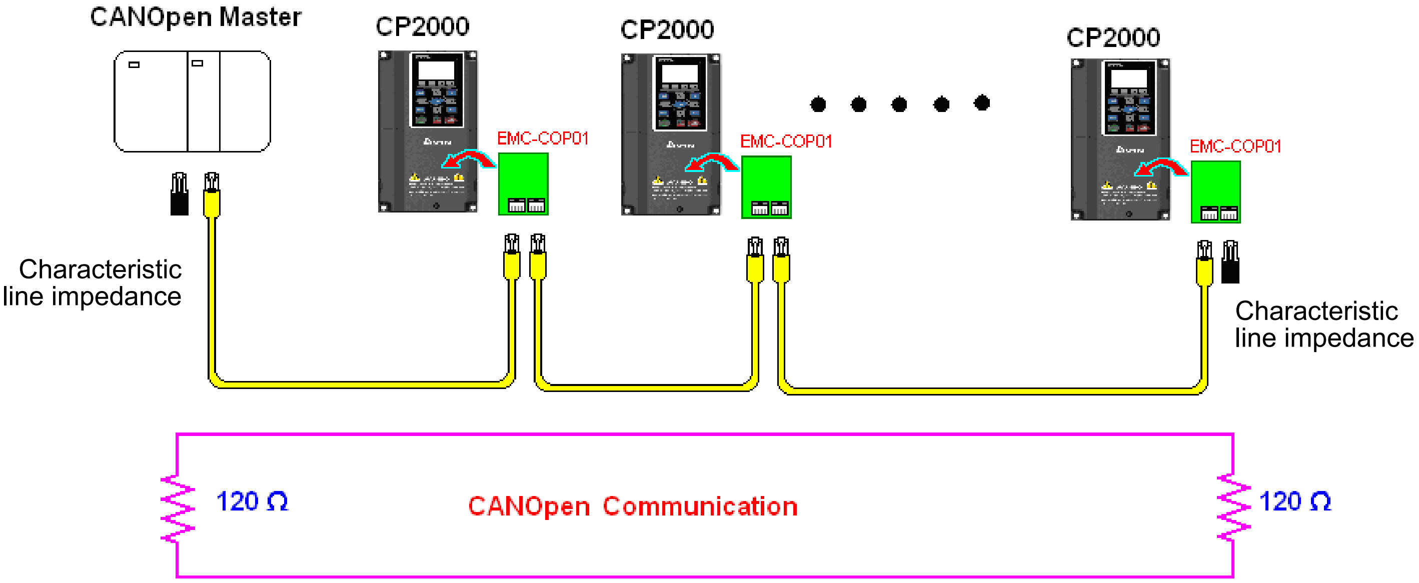
All PDO transmission data must be mapped to the index with Object Dictionary.

EMCY (Emergency Object)

When errors occur inside the hardware, an emergency object is triggered. An emergency object is only sent when an error occurs. As long as there is nothing wrong with the hardware, there is no emergency object warning of an error message.

15-2 Wiring for CANopen

Use an external CANopen communication card EMC-COP01 for CANopen wiring to connect the CANopen to the CP2000 drive. The link uses an RJ45 cable. You must write the two farthest ends with 120 Ω terminating resistors as shown in the picture below.



15-3 CANopen Communication Interface Description

15-3-1 CANopen Control Mode Selection

There are two control modes for CANopen: the DS402 standard (Pr.09-40 = 1) is the default, and the Delta's standard setting (Pr.09-40 = 0). There are two control modes according to Delta's standard. One is the old control mode (Pr.09-30 = 0); this control mode can only control the motor drive under frequency control. The other mode is a new standard (Pr.09-30 = 1); this new control mode allows the motor drive to be controlled under all kinds of modes. The CP2000 currently only supports speed mode. The following table shows the control mode definitions:

CANopen Control Mode Selection	Control Mode	
	Speed	
	Index	Description
DS402 standard Pr.09-40 = 1	6042-00	Target rotating speed (rpm)
	-----	-----
Delta Standard (Old definition) Pr.09-40 = 0, Pr.09-30 = 0	2020-02	Target rotating speed (Hz)
Delta Standard (New definition) Pr.09-40 = 0, Pr.09-30 = 1	2060-03	Target rotating speed (Hz)
	2060-04	Torque Limit (%)

CANopen Control Mode Selection	Operation Control	
	Index	Description
DS402 standard Pr.09-40 = 1	6040-00	Operation Command
	-----	-----
Delta Standard (Old definition) Pr.09-40 = 0, Pr.09-30 = 0	2020-01	Operation Command
Delta Standard (New definition) Pr.09-40 = 0, Pr.09-30 = 1	2060-01	Operation Command
	-----	-----

CANopen Control Mode Selection	Other	
	Index	Description
DS402 standard Pr.09-40 = 1	605A-00	Quick stop processing method
	605C-00	Disable operation processing method
Delta Standard (Old definition) Pr.09-40 = 1, Pr.09-30 = 0	-----	-----
Delta Standard (New definition) Pr.09-40 = 0, Pr.09-30 = 1	-----	-----
	-----	-----

You can use some indices in either DS402 or Delta's standard.

For example:

1. Index that are defined as RO attributes.
2. The corresponding index of available parameter groups: (2000-00–200B-XX)
3. Acceleration / Deceleration Index: 604F 6050
4. Control mode: Index: 6060

15-3-2 DS402 Standard Control Mode

15-3-2-1 Related setting for an AC motor drive (following the DS402 standard)

If you want to use the DS402 standard to control the motor drive, follow these steps:

1. Wire the hardware (refer to Section 15-2 Wiring for CANopen)
2. Set the operation source: set Pr.00-21 to 3 for CANopen communication card control. (Run/stop, forward/reverse run…etc.)
3. Set the frequency source: set Pr.00-20 to 6. Choose the source for the Frequency command from the CANopen setting.
4. Set DS402 for the control mode: Pr.09-40 = 1
5. Set the CANopen station: set Pr.09-36, the range is between 1–127. When Pr.09-36 = 0, the CANopen slave function is disabled. Note that if an error appears (station address error CAdE or CANopen memory error CFrE) when you finish the station setting, set Pr.00-02 = 7 to reset.
6. Set the CANopen baud rate: set Pr.09-37 (CANBUS Baud Rate: 1 Mbps(0), 500 Kbps(1), 250 Kbps (2), 125 Kbps (3), 100 Kbps (4) and 50 Kbps (5))
7. Set the multiple input functions to Quick Stop. You can also choose to enable or disable; the default setting is disabled. If it is necessary to enable the function, set MI terminal to 53 in one of the following parameter: Pr.02-01–Pr.02-08 or Pr.02-26–Pr.02-31. Note that this function is available in DS402 only.

15-3-2-2 The status of the motor drive (by following DS402 standard)

According to the DS402 definition, the motor drive is divided into 3 blocks and 9 statuses as described below.

3 blocks

1. Power Disable: without PWM output
2. Power Enable: with PWM output
3. Fault: one or more errors have occurred.

9 status

1. Start: power ON
2. Not ready to switch on: the motor drive is initiating.
3. Switch ON Disable: occurs when the motor drive finishes initiating.
4. Ready to Switch On: warming up before running.
5. Switch ON: the motor drive has the PWM output, but the reference command is not effective.
6. Operation Enable: able to control normally.
7. Quick Stop Active: when there is a Quick Stop request, stop running the motor drive.
8. Fault Reaction Active: the motor drive detects conditions which might trigger error(s).
9. Fault: One or more errors have occurred in the motor drive.

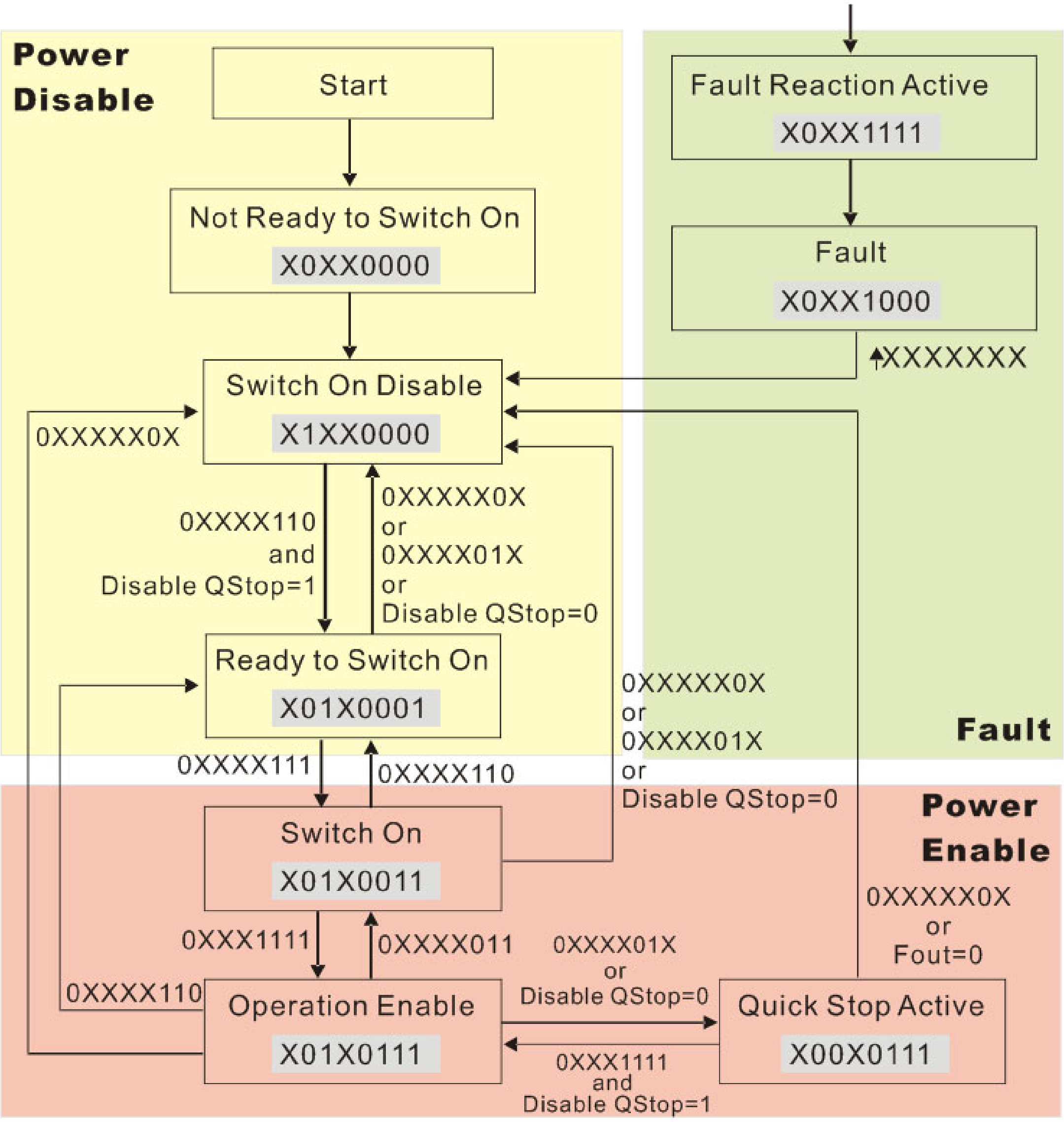
When the motor drive turns on and finishes the initiation, it remains in Ready to Switch On status. To control the operation of the motor drive, change to Operation Enable status. To do this, set the control word's bit0–bit3 and bit7 of the Index 6040H and pair with Index Status Word (Status Word 0X6041). The control steps and index definition are described as below:

Index 6040

15–9	8	7	6–4	3	2	1	0
Reserved	Halt	Fault Reset	Operation	Enable operation	Quick Stop	Enable Voltage	Switch On

Index 6041

15–14	13–12	11	10	9	8	7	6	5	4	3	2	1	0
Reserved	Operation	Internal limit active	Target reached	Remote	Reserved	Warning	Switch on disabled	Quick stop	Voltage enabled	Fault	Operation enable	Switch on	Ready to switch on



Set command 6040 = 0xE, then set another command 6040 = 0xF. Then you can switch the motor drive to Operation Enable. The Index 605A determines the direction of the lines from Operation Enable when the control mode changes from Quick Stop Active. When the setting value is 1–3, both direction lines are active, but when the setting value of 605A is not 1–3, once the motor drive is switched to Quick Stop Active, it is not be able to switch back to Operation Enable.

Index	Sub	Definition	Default	R/W	Size	Unit	PDO Map	Mode	note
605Ah	0	Quick stop option code	2	RW	S16		No		0: disable drive function 1: Slow down on slow down ramp 2: Slow down on quick stop ramp 3: Slow down on the current limit 5: Slow down on slow down ramp and stay in Quick Stop 6: Slow down on quick stop ramp and stay in Quick Stop 7: Slow down on the current limit and stay in Quick Stop

When the control block switches from Power Enable to Power Disable, use 605C to define the stop method.

Index	Sub	Definition	Default	R/W	Size	Unit	PDO Map	Mode	note
605Ch	0	Disable operation option code	1	RW	S16		No		0: Disable drive function 1: Slow down with slow down ramp; disable of the drive function

15-3-2-3 Various mode control method (by following DS402 standard)

CP2000 currently only supports speed control which is described as below:

Speed mode

1. Set CP2000 to speed control mode: set Index6060 to 2.
2. Switch to Operation Enable mode: Set 6040 = 0xE, then set 6040 = 0xF.
3. Set the target frequency: Set target frequency for 6042, since the operation unit of 6042 is rpm, a conversion is required:

$$n = f \times \frac{120}{p}$$

n: rotation speed (rpm) (rounds/minute)

P: motor’s pole number (Pole)

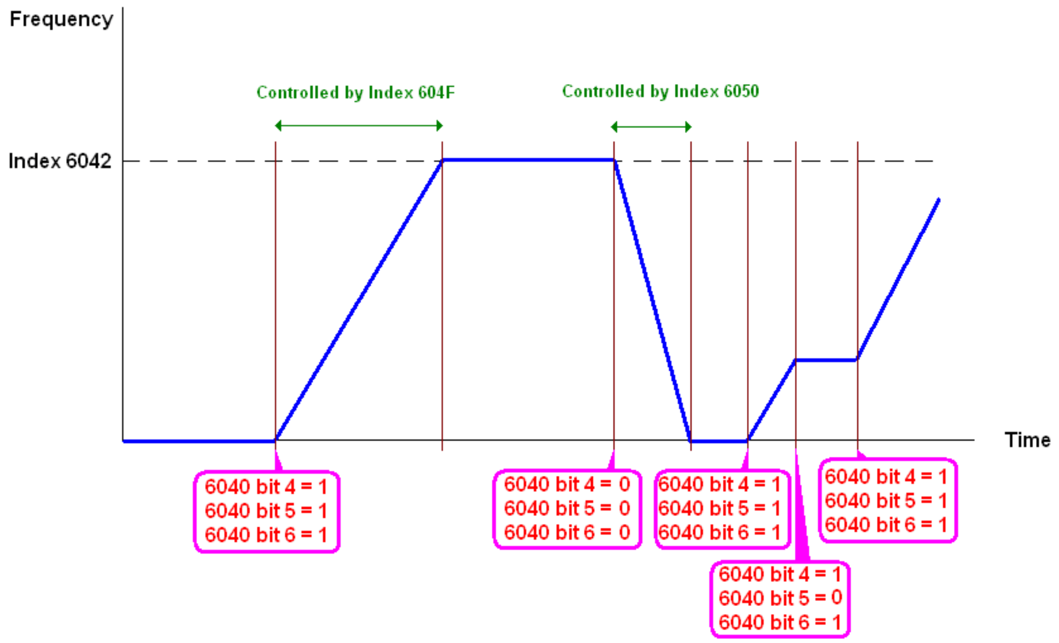
f: rotation frequency (Hz)

For example:

Set 6042H = 1500 (rpm), if the number of poles for the drive is 4 (Pr.05-04 or Pr.05-16), then the motor drive's operation frequency is 1500 / (120/4) = 50 Hz. The 6042 is defined as a signed operation. The plus or minus sign means to rotate clockwise or counter-clockwise

4. To set acceleration and deceleration: Use 604F (Acceleration) and 6050 (Deceleration).
5. Trigger an ACK signal: in the speed control mode, control the bit6–4 of Index 6040. It is defined below:

	Index 6040			SUM
	bit6	bit5	bit4	
Speed mode (Index 6060=2)	1	0	1	Locked at the current signal.
	1	1	1	Run to reach targeting signal.
	Other			Decelerate to 0 Hz.



NOTE 01: Read 6043 to get the current rotation speed. (Unit: rpm)

NOTE 02: Read bit10 of 6041 to check if the rotation speed has reached the targeting value. (0: Not reached; 1: Reached)

15-3-3 Using the Delta Standard (Old definition, only supports speed mode)

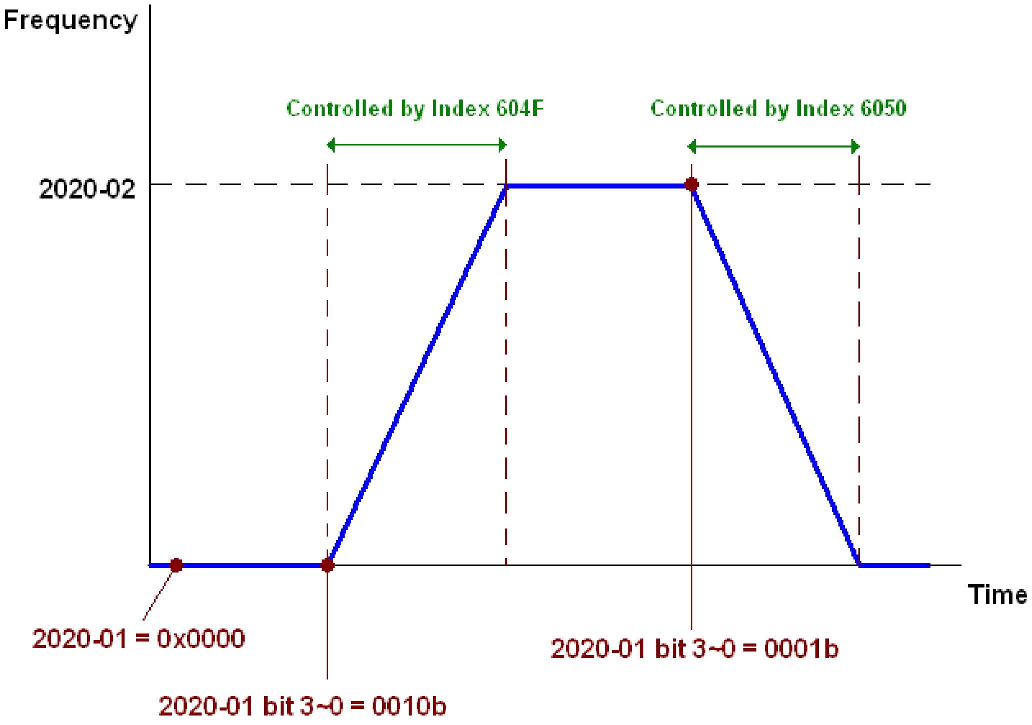
15-3-3-1 Various mode control method (following the Delta old standard)

If you want to use the Delta old standard to control the motor drive, follow these steps:

1. Wire the hardware (refer to Section 15-2 Wiring for CANopen)
2. Set the operation source: set Pr.00-21 to 3 for CANopen communication card control. (Run/stop, forward/ reverse run…, etc.)
3. Set the frequency source: set Pr.00-20 to 6. Choose the source for the Frequency command from the CANopen setting.
4. Set Delta Standard (Old definition, only supports speed mode) as the control mode: Pr.09-40 = 0 and Pr.09-30 = 0.
5. Set the CANopen station: set Pr.09-36; the range is between 1–127. When Pr.09-36 = 0, the CANopen slave function is disabled. Note that if an error appears (station address error CAdE or CANopen memory error CFrE) when you finish the station setting, set Pr.00-02=7 to reset.
6. Set the CANopen baud rate: set Pr.09-37 (CANBUS Baud Rate: 1 Mbps(0), 500 Kbps(1), 250 Kbps(2), 125 Kbps(3), 100 Kbps(4) and 50 Kbps(5))

15-3-3-2 The control method under speed mode

1. Set the target frequency: set 2020-02, the unit is Hz, with 2 decimal places. For example, 1000 is 10.00 Hz.
2. Operation control: set 2020-01 = 0002H for running, and set 2020-01 = 0001H for stopping.



15-3-4 By Using Delta Standard (New Definition)

15-3-4-1 Related settings for an AC motor drive (following the Delta New Standard)

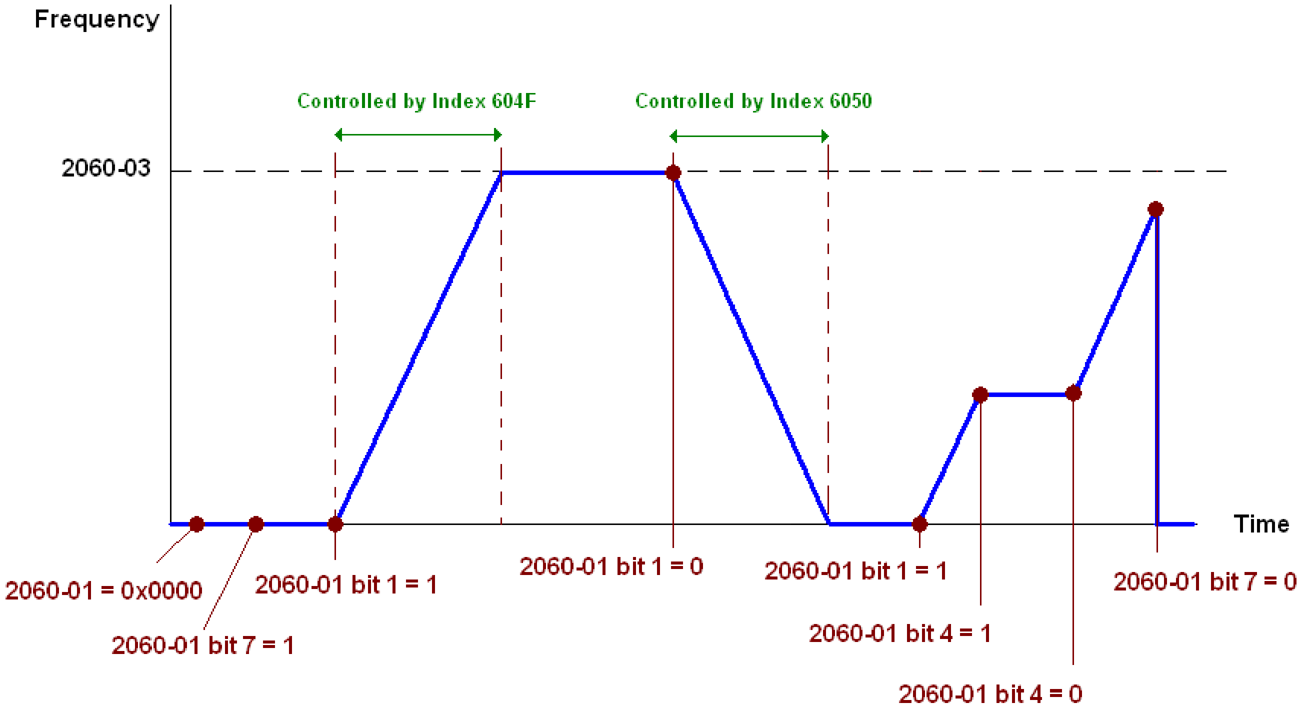
If you want to use the Delta new standard to control the motor drive, follow these steps:

1. Wire the hardware (refer to Section 15-2 Wiring for CANopen)
2. Set the operation source: set Pr.00-21 to 3 for CANopen communication card control. (Run/stop, forward/reverse run…, etc.)
3. Set the frequency source: set Pr.00-20 to 6. Choose the source for the Frequency command from the CANopen setting.
4. Set Delta Standard (New definition) as the control mode: Pr.09-40 = 0 and Pr.09-30 = 1.
5. Set the CANopen station: set Pr.09-36; the range is between 1–127. When Pr.09-36=0, the CANopen slave function is disabled. Note that if an error appears (station address error CAdE or CANopen memory error CFrE) when you finish the station setting, set Pr.00-02 = 7 to reset.)
6. Set the CANopen baud rate: set Pr.09-37 (CANBUS Baud Rate: 1 Mbps (0), 500 Kbps (1), 250 Kbps (2), 125 Kbps (3), 100 Kbps (4) and 50 Kbps(5)).

15-3-4-2 Various mode control method (Delta New Standard)

Speed Mode

1. Set CP2000 to speed control mode: set Index6060 = 2.
2. Set the target frequency: set 2060-03, unit is Hz, with 2 decimal places. For example, 1000 is 10.00Hz.
3. Operation control: set 2060-01 = 008H for Server on, and set 2060-01 = 0081H for running.



NOTE 1: Read 2061-05 to get the current position.

NOTE 2: Read bit0 of 2061 to find if the position has reached to the target position. (0: Not reached, 1: Reached).

15-3-5 DI/ DO/ AI/ AO are controlled via CANopen

To control the DO and AO of the motor drive through CANopen, follow these steps:

1. Define the DO to be controlled by CANopen. For example, set Pr.02-14 = 50 to control RY2.
2. Define the AO to be controlled by CANopen. For example, set Pr.03-23 = 20 to control AFM2.
3. Control the Index mapped by CANopen. To control DO, use control Index 2026-41. To control AO, use control 2026-AX. To set RY2 as ON, set bit1 of Index 2026-41 = 1, then RY2 outputs 1. To control AFM2 output = 50.00%, set Index 2026-A2 = 5000, then AFM2 outputs 50%.

The following table shows the mapping of CANopen DI/ DO/ AI/ AO:

DI:

Terminal	Related Parameters	R/W	Mapping Index
FWD	==	RO	2026-01 bit0
REV	==	RO	2026-01 bit1
MI 1	==	RO	2026-01 bit2
MI 2	==	RO	2026-01 bit3
MI 3	==	RO	2026-01 bit4
MI 4	==	RO	2026-01 bit5
MI 5	==	RO	2026-01 bit6
MI 6	==	RO	2026-01 bit7
MI 7	==	RO	2026-01 bit8
MI 8	==	RO	2026-01 bit9
MI 10	==	RO	2026-01 bit10
MI 11	==	RO	2026-01 bit11
MI 12	==	RO	2026-01 bit12
MI 13	==	RO	2026-01 bit13
MI 14	==	RO	2026-01 bit14
MI 15	==	RO	2026-01 bit15

DO：

Terminal	Related Parameters	R/W	Mapping Index
RY1	Pr.02-13 = 51	RW	2026-41 bit0
RY2	Pr.02-14 = 51	RW	2026-41 bit1
RY3	Pr.02-15 = 51	RW	2026-41 bit2
MO10/RY10	Pr.02-36 = 51	RW	2026-41 bit5
MO11/RY11	Pr.02-37 = 51	RW	2026-41 bit6
RY12	Pr.02-38 = 51	RW	2026-41 bit7
RY13	Pr.02-39 = 51	RW	2026-41 bit8
RY14	Pr.02-40 = 51	RW	2026-41 bit9
RY15	Pr.02-41 = 51	RW	2026-41 bit10

AI：

Terminal	Related Parameters	R/W	Mapping Index
AVI1	==	RO	Value of 2026-61
ACI	==	RO	Value of 2026-62
AVI2	==	RO	Value of 2026-63

AO：

Terminal	Related Parameters	R/W	Mapping Index
AFM1	Pr.03-20 = 21	RW	Value of 26A0h
AFM2	Pr.03-23 = 21	RW	Value of 26A1h
AFM10	Pr.14-12 = 21	RW	Value of 26AAh
AFM11	Pr.14-13 = 21	RW	Value of 26ABh

15-4 CANopen Supporting Index

CP2000 Index:

The parameter index corresponds as following in this example:

Index	**sub-Index**
2000H + Group	member+1

For example:

Pr.10-15 (Encoder Slip Error Treatment)

Group		**member**
10(0AH)	-	15(0FH)

Index = 2000H + 0AH = 200A

Sub Index = 0FH + 1H = 10H

CP2000 Control Index:

Delta Standard Mode (Old definition)

Index	Sub	Definition	Factory Setting	R/W	Size	Note	
2020H	0	Number	3	R	U8		
	1	Control word	0	RW	U16	bit1–0	00B: disable
							01B: stop
							10B: disable
							11B: JOG Enable
						bit3–2	Reserved
						bit5–4	00B: disable
							01B: Direction forward
							10B: Reverse
							11B: Switch Direction
						bit7–6	00B: 1st step Accel. /Decel.
							01B: 2nd step Accel. /Decel.
							10B: 3rd step Accel. /Decel.
							11B: 4th step Accel. /Decel.
						bit11–8	0000B: Master speed
							0001B: 1st step speed
							0010B: 2nd step speed
							0011B: 3rd step speed
							0100B: 4th step speed
							0101B: 5th step speed
							0110B: 6th step speed
							0111B: 7th step speed
							1000B: 8th step speed
							1001B: 9th step speed
							1010B: 10th step speed
							1011B: 11th step speed
							1100B: 12th step speed
							1101B: 13th step speed
							1110B: 14th step speed
							1111B: 15th step speed
						bit12	1: Enable the function of bit6–11
						bit15	Reserved
	2	Freq. command (XXX.XX Hz)	0	RW	U16		
	3	Other trigger	0	RW	U16	bit0	1: E.F. ON

Index	Sub	Definition	Factory Setting	R/W	Size	Note	
						bit1	1: Reset
						bit2	1: Base Block (B.B) ON
						bit15–3	Reserved
2021H	0	Number	10	R	U8		
	1	Error code	0	R	U16	High byte: Warn code Low byte: Error code	
	2	AC motor drive status	0	R	U16	bit1–0	00B: stop
							01B: decelerate to stop
							10B: waiting for operation command
							11B: in operation
						bit2	1: JOG command
						bit4–3	00B: run forward
							01B: switch from run in reverse to run forward
							10B: switch from run forward to run in reverse
							11B: run in reverse
						bit7–5	Reserved
						bit8	1: master frequency command controlled by communication interface
						bit9	1: master frequency command controlled by analog signal input
						bit10	1: operation command controlled by communication interface
						bit11	1: Parameter lock
						bit12	1: Enable the digital keypad copy parameter function
						bit15–13	Reserved
	3	Freq. command (XXX.XX Hz)	0	R	U16		
	4	Output freq. (XXX.XX Hz)	0	R	U16		
	5	Output current (XX.X A)	0	R	U16		
	6	DC bus voltage (XXX.X V)	0	R	U16		
	7	Output voltage (XXX.X V)	0	R	U16		
	8	The current segment run by the multi-segment speed command	0	R	U16		
	9	Reserved	0	R	U16		
	A	Display counter value (c)	0	R	U16		
	B	Display output power angle (XX.X°)	0	R	U16		
	C	Display output torque (XXX.X %)	0	R	U16		
	D	Display actual motor speed (rpm)	0	R	U16		
	10	Power output (X.XXX kWh)	0	R	U16		
	17	Multi-function display (Pr.00-04)	0	R	U16		
2022H	0	Reserved	0	R	U16		
	1	Display output current	0	R	U16		
	2	Display counter value	0	R	U16		
	3	Display actual output frequency (XXX.XX Hz)	0	R	U16		
	4	Display DC bus voltage (XXX.X V)	0	R	U16		

Index	Sub	Definition	Factory Setting	R/W	Size	Note	
	5	Display output voltage (XXX.X V)	0	R	U16		
	6	Display output power angle (XX.X°)	0	R	U16		
	7	Display output power in kW	0	R	U16		
	8	Display actual motor speed (rpm)	0	R	U16		
	9	Display estimate output torque (XXX.X%)	0	R	U16		
	B	Display PID feedback value after enabling PID function in % (To 2 decimal places)	0	R	U16		
	C	Display signal of AVI 1 analog input terminal, 0–10 V corresponds to 0–100% (To 2 decimal places)	0	R	U16		
	D	Display signal of ACI analog input terminal, 4–20 mA /0–10 V corresponds to 0–100% (To 2 decimal places)	0	R	U16		
	E	Display signal of AVI 2 analog input terminal, -10 V–10 V corresponds to -100–100% (To 2 decimal places)	0	R	U16		
	F	Display the IGBT temperature of drive power module in ºC	0	R	U16		
	10	Display the temperature of capacitance in ºC	0	R	U16		
	11	The status of digital input (ON/OFF), refer to Pr.02-12	0	R	U16		
	12	The status of digital output (ON/OFF), refer to Pr.02-18	0	R	U16		
	13	Display the multi-step speed that is executing	0	R	U16		
	14	The corresponding CPU pin status of digital input	0	R	U16		
	15	The corresponding CPU pin status of digital output	0	R	U16		
	1A	Display times of counter overload (0.00–100.00%)	0	R	U16		
	1B	Display GFF in %	0	R	U16		
	1C	Display DC bus voltage ripples (Unit: V_{DC})	0	R	U16		
	1D	Display PLC register D1043 data	0	R	U16		
	1E	Display Pole of Permanent Magnet Motor	0	R	U16		
	1F	User page displays the value in physical measure	0	R	U16		
	20	Output Value of Pr.00-05	0	R	U16		
	21	Number of motor turns when drive operates	0	R	U16		
	22	Operation position of motor	0	R	U16		
	23	Fan speed of the drive	0	R	U16		
	24	Control mode of the drive 0: speed mode	0	R	U16		
	25	Carrier frequency of the drive	0	R	U16		
	26	Reserved					
	27	Motor status					

Index	Sub	Definition	Factory Setting	R/W	Size	Note	
	2A	kWh display					
	2D	Motor actual position low-word					
	2E	Motor actual position high-word					
	2F	PID reference target					
	30	PID bias value					
	31	PID output frequency					

CANopen Remote IO mapping

Index	Sub	R/W	Definition
2026H	01h	R	Each bit corresponds to the different input terminals
	03h–40h	R	Reserved
	41h	RW	Each bit corresponds to the different output terminals
	42h–60h	R	Reserved
	61h	R	AVI1 (%)
	62h	R	ACI (%)
	63h	R	AVI2 (%)
	64h–6Ah	R	Reserved
	6Bh	R	Extension card AI10, 0.0–100.0% (EMC-A22A)
	6Ch	R	Extension card AI11, 0.0–100.0% (EMC-A22A)
	6Dh–A0h	R	Reserved
	A1h	RW	AFM1 (%)
	A2h	RW	AFM2 (%)
	A3h–AAh	RW	Reserved
	ABh	RW	Extension card AO10, 0.0–100.0% (EMC-A22A)
	ACh	RW	Extension card AO11, 0.0–100.0% (EMC-A22A)

Index 2026-01	bit0	bit1	bit2	bit3	bit4	bit5	bit6	bit7	bit8	bit9	bit10	bit11	bit12	bit13	bit14	bit15
1	FWD	REV	MI1	MI2	MI3	MI4	MI5	MI6	MI7	MI8						
2											MI10	MI11	MI12	MI13	MI14	MI15
3											MI10	MI11	MI12	MI13		

1：Control broad I/O (Standard)

2：Add external card, EMC-D611A

3：Add external card, EMC-D42A

Index 2026-41	bit0	bit1	bit2	bit3	bit4	bit5	bit6	bit7	bit8	bit9	bit10	bit11	bit12	bit13	bit14	bit15
1	RY1	RY2		MO1	MO2											
2						MO10	MO11									
3						RY10	RY11	RY12	RY13	RY14	RY15					

1：Control broad I/O (Standard)

2：Add external card, EMC-D42A

3：Add external card, EMC-R6AA

Delta Standard Mode (New definition)

Index	sub	R/W	Size	Descriptions			Speed Mode
				bit	Definition	Priority	
2060h	00h	R	U8				
	01h	RW	U16	0	Ack	4	0: fcmd = 0 1: fcmd = Fset (Fpid)
				1	Dir	4	0: FWD run command 1: REV run command
				2			
				3	Halt		0: drive run till target speed is attained 1: drive stop by deceleration setting
				4	Hold		0: drive run till target speed is attained 1: frequency stop at current frequency
				5	JOG		0: JOG OFF Pulse 1: JOG RUN
				6	QStop		Quick Stop
				7	Power		0:Power OFF 1:Power ON
				8	Reserved		
				9	Ext Cmd2	4	0->1: Absolute position cleared
				10–14	Reserved		
				15	RST	4	Pulse 1: Fault code cleared
	02h	RW	U16		Mode Cmd		0: Speed mode
	03h	RW	U16				Speed command (unsigned decimal)
	04h	RW	U16				
	05h	RW	S32				
	06h	RW					
	07h	RW	U16				
	08h	RW	U16				
2061h	01h	R	U16	0	Arrive		Frequency attained
				1	Dir		0: Motor FWD run 1: Motor REV run
				2	Warn		Warning
				3	Error		Error detected
				4			
				5	JOG		JOG
				6	QStop		Quick stop
				7	Power On		Switch ON
				15–8			
	02h	R					
	03h	R	U16				Actual output frequency
	04h	R					
	05h	R	S32				Actual position (absolute)
	06h	R					
	07h	R	S16				Actual torque

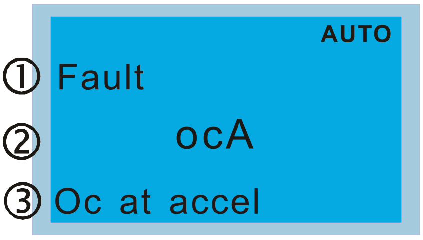
Mapping for CANopen built-in PLC register D (mapping from D900–D999 to 3000H–3063H)

Index	Sub	R/W	Definition
3000	0	RW	PLC D900
3001	0	RW	PLC D901
3002	0	RW	PLC D902
…	…	…	…
3063	0	RW	PLC D999

DS402 Standard

Index	Sub	Definition	Factory Setting	R/W	Size	Unit	PDO Map	Mode	Note
6007h	0	Abort connection option code	2	RW	S16		Yes		0: No action 2: Disable Voltage 3: quick stop
603Fh	0	Error code	0	R0	U16		Yes		
6040h	0	Control word	0	RW	U16		Yes		
6041h	0	Status word	0	R0	U16		Yes		
6042h	0	vl target velocity	0	RW	S16	rpm	Yes	vl	
6043h	0	vl velocity demand	0	RO	S16	rpm	Yes	vl	
6044h	0	vl control effort	0	RO	S16	rpm	Yes	vl	
604Fh	0	vl ramp function time	10000	RW	U32	1ms	Yes	vl	Unit must be: 100 ms, and check if the setting is 0.
6050h	0	vl slow down time	10000	RW	U32	1ms	Yes	vl	
6051h	0	vl quick stop time	1000	RW	U32	1ms	Yes	vl	
605Ah	0	Quick stop option code	2	RW	S16		No		0: disable drive function 1: slow down on slow down ramp 2: slow down on quick stop ramp 5: slow down on slow down ramp and stay in Quick Stop 6: slow down on quick stop ramp and stay in Quick Stop
605Ch	0	Disable operation option code	1	RW	S16		No		0: Disable drive function 1: Slow down with slow down ramp; disable of the drive function
6060h	0	Mode of operation	2	RW	S8		Yes		2: Velocity Mode
6061h	0	Mode of operation display	2	RO	S8		Yes		Same as above

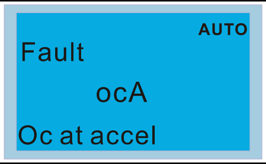
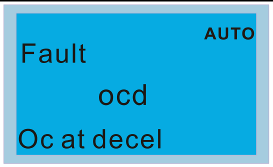
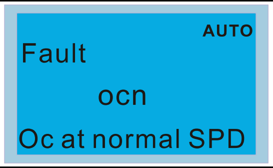
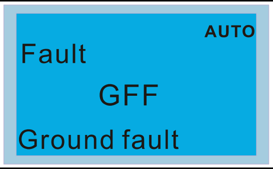
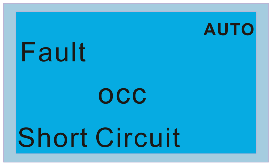
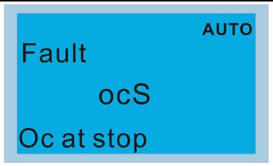
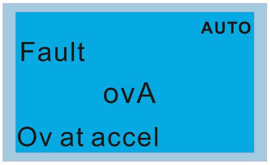
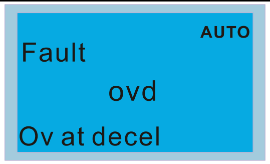
15-5 CANopen Fault Codes

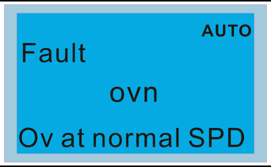
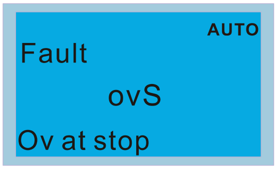
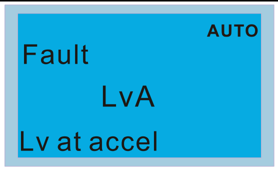
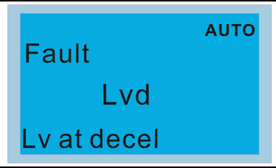
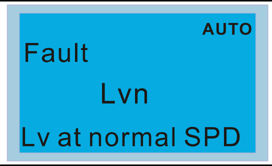
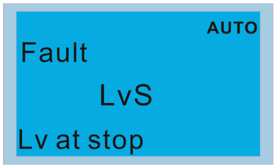
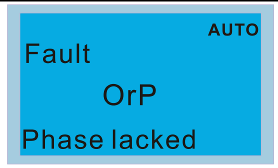
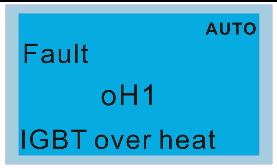
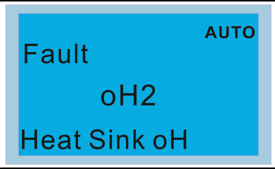
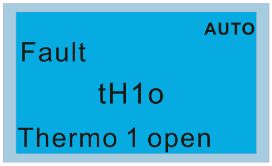
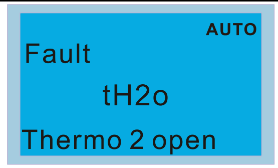


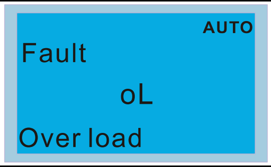
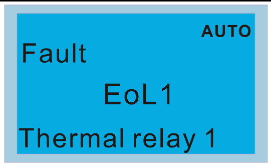
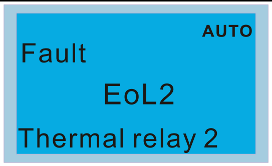
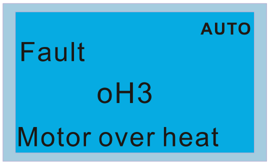
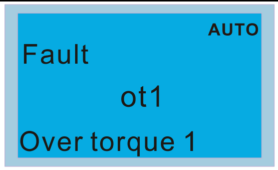
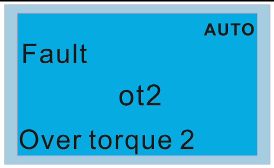
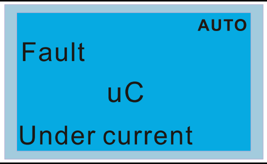
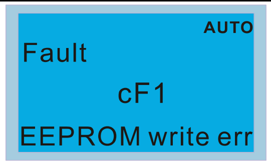
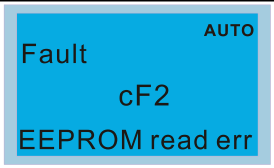
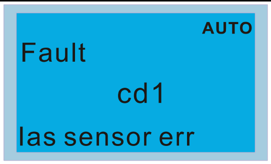
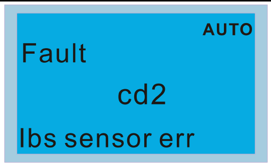
AUTO
Fault
ocA
Oc at accel

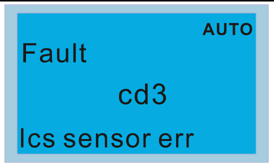
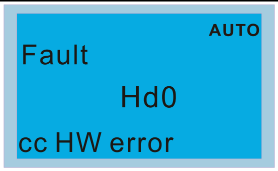
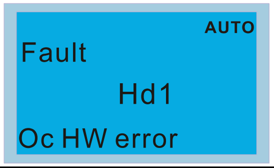
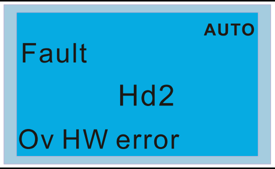
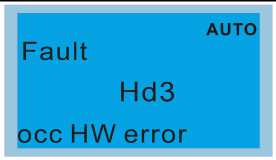
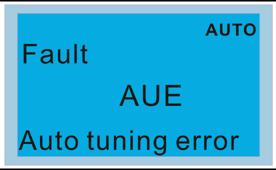
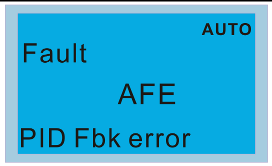
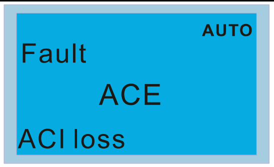
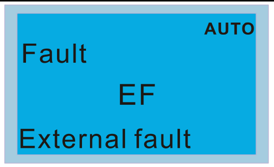
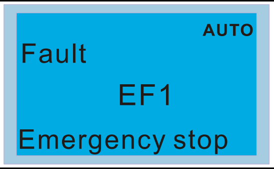
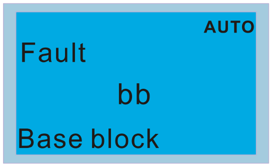
① Display error signal
② Abbreviate error code
③ Display error description

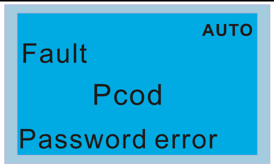
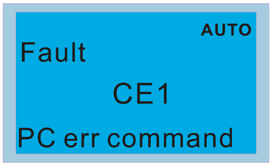
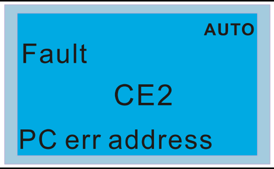
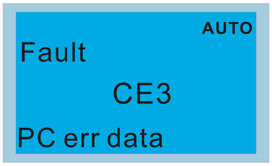
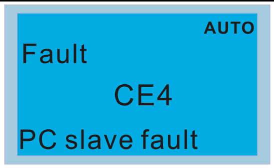
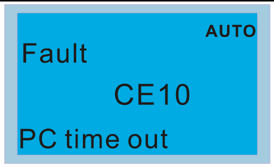
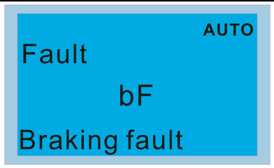
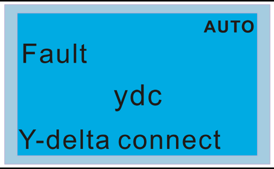
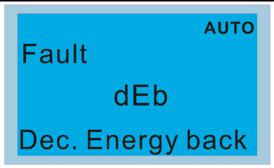
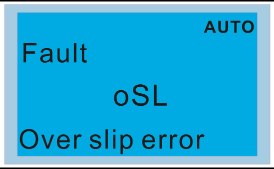
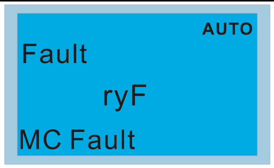
- Refer to setting value of Pr.06-17–Pr.06-22.
- Refer to Chapter 14 Fault Codes for detailed descriptions.

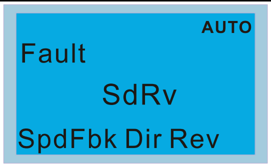
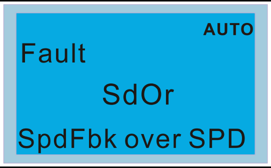
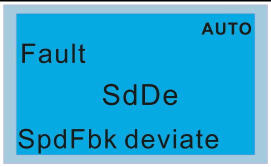
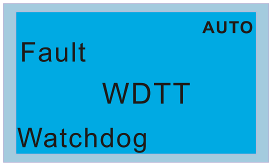
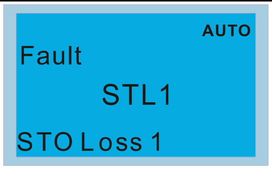
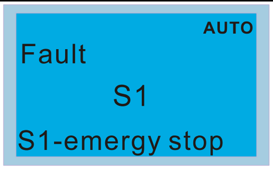
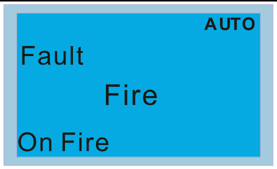
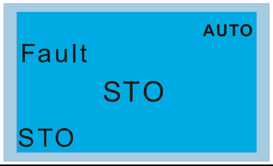
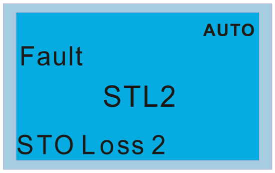
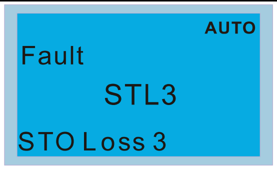
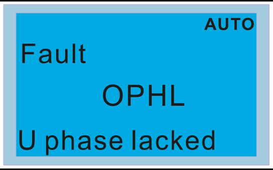
ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
1	 AUTO Fault ocA Oc at accel	0001H	Over-current during acceleration (ocA)	1	2213H
2	 AUTO Fault ocd Oc at decel	0002H	Over-current during deceleration (ocd)	1	2213H
3	 AUTO Fault ocn Oc at normal SPD	0003H	Over-current during steady operation (ocn)	1	2214H
4	 AUTO Fault GFF Ground fault	0004H	Ground fault (GFF)	1	2240H
5	 AUTO Fault occ Short Circuit	0005H	IGBT short circuit between upper bridge and lower bridge (occ)	1	2250H
6	 AUTO Fault ocS Oc at stop	0006H	Over-current at stop (ocS)	1	2314H
7	 AUTO Fault ovA Ov at accel	0007H	Over-voltage during acceleration (ovA)	2	3210H
8	 AUTO Fault ovd Ov at decel	0008H	Over-voltage during deceleration (ovd)	2	3210H

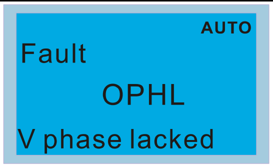
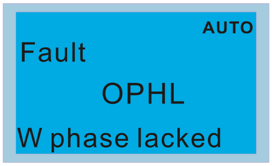
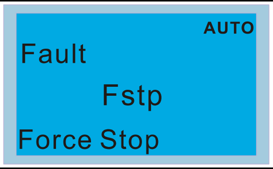
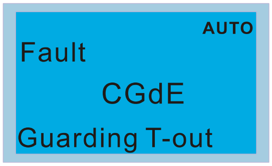
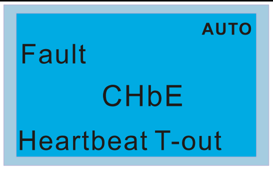
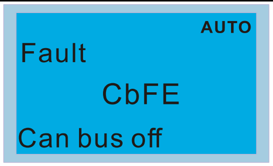
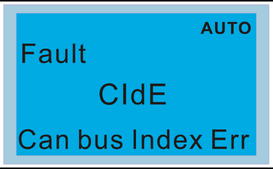
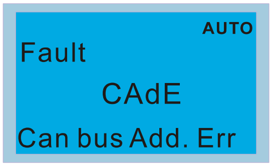
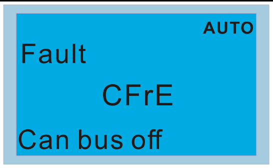
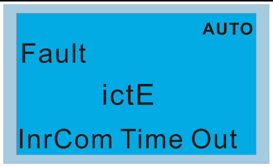
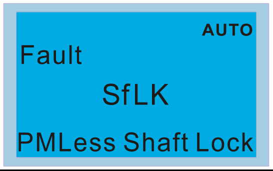
ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
9	 AUTO Fault ovn Ov at normal SPD	0009H	DC bus over-voltage at constant speed (ovn)	2	3210H
10	 AUTO Fault ovS Ov at stop	000AH	Over-voltage at stop (ovS)	2	3210H
11	 AUTO Fault LvA Lv at accel	000BH	Low-voltage during acceleration (LvA)	2	3220H
12	 AUTO Fault Lvd Lv at decel	000CH	Low-voltage during deceleration (Lvd)	2	3220H
13	 AUTO Fault Lvn Lv at normal SPD	000DH	Low-voltage at constant speed (Lvn)	2	3220H
14	 AUTO Fault LvS Lv at stop	000EH	Low-voltage at stop (LvS)	2	3220H
15	 AUTO Fault OrP Phase lacked	000FH	Phase loss protection (OrP)	2	3130H
16	 AUTO Fault oH1 IGBT over heat	0010H	IGBT overheating (oH1)	3	4310H
17	 AUTO Fault oH2 Heat Sink oH	0011H	Heatsink overheating (oH2)	3	4310H
18	 AUTO Fault tH1o Thermo 1 open	0012H	IGBT temperature detection failure (tH1o)	3	FF00H
19	 AUTO Fault tH2o Thermo 2 open	0013H	Capacitor hardware error (tH2o)	3	FF01H

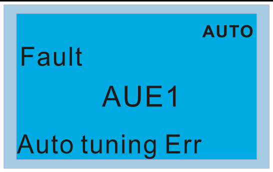
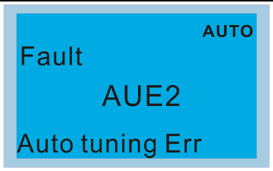
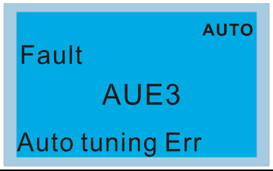
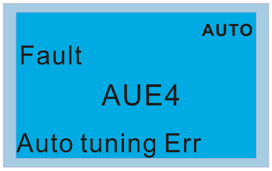
ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
21	 AUTO Fault oL Over load	0015H	Over load (oL)	1	2310H
22	 AUTO Fault EoL1 Thermal relay 1	0016H	Electronic thermal relay 1 protection (EoL1)	1	2310H
23	 AUTO Fault EoL2 Thermal relay 2	0017H	Electronic thermal relay 2 protection (EoL2)	1	2310H
24	 AUTO Fault oH3 Motor over heat	0018H	Motor overheating (oH3)	3	FF20H
26	 AUTO Fault ot1 Over torque 1	001AH	Over torque 1 (ot1)	3	8311H
27	 AUTO Fault ot2 Over torque 2	001BH	Over torque 2 (ot2)	3	8311H
28	 AUTO Fault uC Under current	001CH	Under current (uC)	1	8321H
30	 AUTO Fault cF1 EEPROM write err	001EH	EEPROM write error (cF1)	5	5530H
31	 AUTO Fault cF2 EEPROM read err	001FH	EEPROM read error (cF2)	5	5530H
33	 AUTO Fault cd1 Ias sensor err	0021H	U-phase error (cd1)	1	FF04H
34	 AUTO Fault cd2 Ibs sensor err	0022H	V-phase error (cd2)	1	FF05H

ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
35	 AUTO Fault cd3 Ics sensor err	0023H	W-phase error (cd3)	1	FF06H
36	 AUTO Fault Hd0 cc HW error	0024H	cc (current clamp) hardware error (Hd0)	5	FF07H
37	 AUTO Fault Hd1 Oc HW error	0025H	oc hardware error (Hd1)	5	FF08H
38	 AUTO Fault Hd2 Ov HW error	0026H	ov hardware error (Hd2)	5	FF09H
39	 AUTO Fault Hd3 occ HW error	0027H	occ hardware error (Hd3)	5	FF0AH
40	 AUTO Fault AUE Auto tuning error	0028H	Auto-tuning error (AUE)	1	FF21H
41	 AUTO Fault AFE PID Fbk error	0029H	PID loss ACI (AFE)	7	FF22H
48	 AUTO Fault ACE ACI loss	0030H	ACI loss (ACE)	1	FF25H
49	 AUTO Fault EF External fault	0031H	External fault (EF)	5	9000H
50	 AUTO Fault EF1 Emergency stop	0032H	Emergency stop (EF1)	5	9000H
51	 AUTO Fault bb Base block	0033H	External base block (bb)	5	9000H

ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
52	 AUTO Fault Pcod Password error	0034H	Password is locked (Pcod)	5	FF26H
54	 AUTO Fault CE1 PC err command	0036H	Illegal command (CE1)	4	7500H
55	 AUTO Fault CE2 PC err address	0037H	Illegal data address (CE2)	4	7500H
56	 AUTO Fault CE3 PC err data	0038H	Illegal data value (CE3)	4	7500H
57	 AUTO Fault CE4 PC slave fault	0039H	Data is written to read-only address (CE4)	4	7500H
58	 AUTO Fault CE10 PC time out	003AH	Modbus transmission time-out (CE10)	5	7500H
60	 AUTO Fault bF Braking fault	003CH	Brake transistor error (bF)	4	7110H
61	 AUTO Fault ydc Y-delta connect	003DH	Y-connection / Δ-connection switch error (ydc)	2	3330H
62	 AUTO Fault dEb Dec. Energy back	003EH	Deceleration energy backup error (dEb)	2	FF27H
63	 AUTO Fault oSL Over slip error	003FH	Over slip error (oSL)	7	FF28H
64	 AUTO Fault ryF MC Fault	0040H	Electric valve switch error (ryF)	5	7110H

ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
68	 AUTO Fault SdRv SpdFbk Dir Rev	0044H	Reverse direction of the speed feedback (SdRv)	0	8400H
69	 AUTO Fault SdOr SpdFbk over SPD	0045H	Over speed rotation feedback (SdOr)	0	8400H
70	 AUTO Fault SdDe SpdFbk deviate	0046H	Large deviation of speed feedback (SdDe)	0	8400H
71	 AUTO Fault WDTT Watchdog	0047H	Watchdog (WDTT)	1	6010H
72	 AUTO Fault STL1 STO Loss 1	0048H	STO loss 1 (STL1)	5	FF30H
73	 AUTO Fault S1 S1-emergy stop	0049H	Emergency stop for external safety (S1)	5	FF2AH
74	 AUTO Fault Fire On Fire	004AH	Fire mode (Fire)	7	FF2FH
76	 AUTO Fault STO STO	004CH	Safe torque off (STO)	5	FF31H
77	 AUTO Fault STL2 STO Loss 2	004DH	STO loss 2 (STL2)	5	FF32H
78	 AUTO Fault STL3 STO Loss 3	004EH	STO loss 3 (STL3)	5	FF33H
82	 AUTO Fault OPHL U phase lacked	0052H	Output phase loss U phase (OPHL)	2	2331H

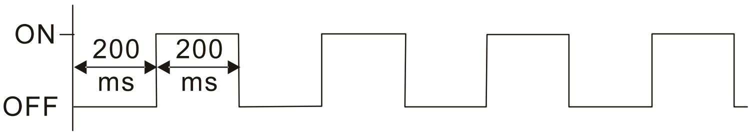
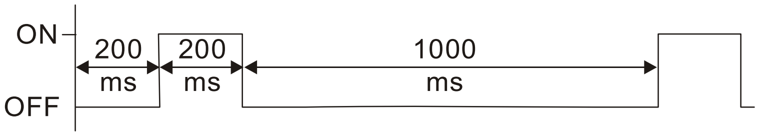
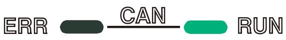
ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
83	 AUTO Fault OPHL V phase lacked	0053H	Output phase loss V phase (OPHL)	2	2332H
84	 AUTO Fault OPHL W phase lacked	0054H	Output phase loss 3 W phase (OPHL)	2	2333H
90	 AUTO Fault Fstp Force Stop	005AH	Force to stop (FStp)	7	FF2EH
101	 AUTO Fault CGdE Guarding T-out	0065H	CANopen guarding error (CGdE)	4	8130H
102	 AUTO Fault CHbE Heartbeat T-out	0066H	CANopen heartbeat error (CHbE)	4	8130H
104	 AUTO Fault CbFE Can bus off	0068H	CANopen bus off error (CbFE)	4	8140H
105	 AUTO Fault CIdE Can bus Index Err	0069H	CANopen index error (CIdE)	4	8100H
106	 AUTO Fault CAdE Can bus Add. Err	006AH	CANopen station address error (CAdE)	4	8100H
107	 AUTO Fault CFrE Can bus off	006BH	CANopen memory error (CFrE)	4	8100H
111	 AUTO Fault ictE InrCom Time Out	006FH	InrCOM time-out error (ictE)	4	7500H
112	 AUTO Fault SfLK PMLess Shaft Lock	0070H	PMLess shaft lock (SfLK)	7	8A00H

ID No.*	Display	Fault code	Description	CANopen fault register (bit0–7)	CANopen fault code
142	 AUTO Fault AUE1 Auto tuning Err	008EH	Auto-tune error 1 (AUE1)	1	FF3DH
143	 AUTO Fault AUE2 Auto tuning Err	008FH	Auto-tune error 2 (AUE2)	1	FF3EH
144	 AUTO Fault AUE3 Auto tuning Err	0090H	Auto-tune error 3 (AUE3)	1	FF3FH
148	 AUTO Fault AUE4 Auto tuning Err	0094H	Auto-tune error 4 (AUE4)	1	FF43H

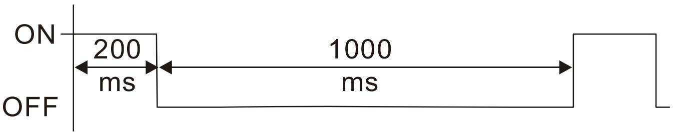
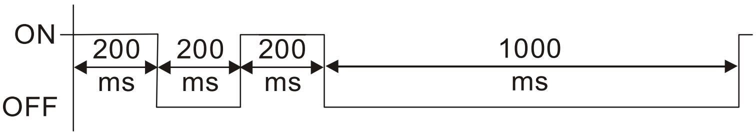
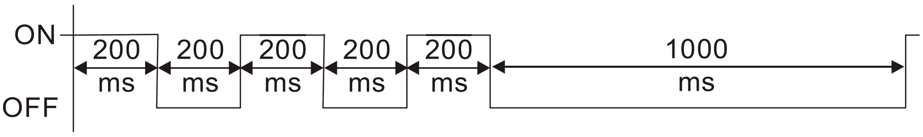
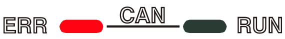
15-6 CANopen LED Function

There are two CANopen flash signs: RUN and ERR.

RUN LED:

LED status	Condition	CANopen State
OFF		Initial
Blinking		Pre-Operation
Single flash		Stopped
ON		Operation

ERR LED:

LED status	Condition/ State
OFF	No Error
Single flash	One Message fail 
Double flash	Node guarding failure or heartbeat message failure 
Triple flash	Synchronization failure  ON OFF 200 ms 200 ms 200 ms 200 ms 200 ms 1000 ms
ON	Bus off 

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Chapter 16 PLC Function Applications

16-1 PLC Summary

16-1-1 Introduction

The commands provided by the CP2000's built-in PLC functions, including the ladder diagram editing tool WPLSoft, as well as the usage of basic commands and applications commands, chiefly retain the operating methods of Delta's PLC DVP series.

16-1-2 WPLSoft ladder diagram editing tool

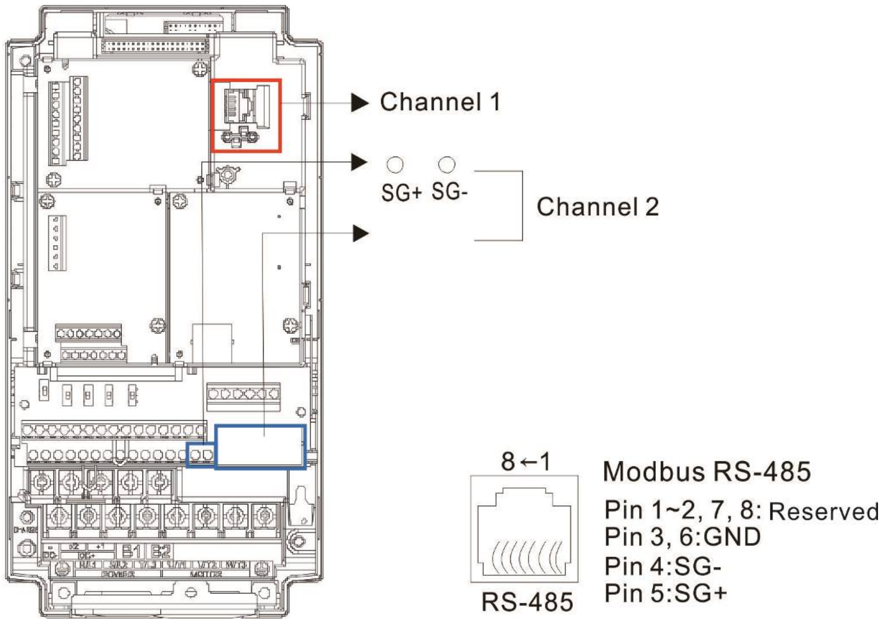
WPLSoft is Delta's program editing software for the DVP and CP2000 programmable controllers in the Windows operating system environment. Apart from general PLC program design general Windows editing functions (such as cut, paste, copy, multiple windows, etc.), WPLSoft also provides many Chinese/English annotation editing and other convenience functions (such as registry editing, settings, file reading, saving, and contact graphic monitoring and settings, etc.).

The following basic requirements that need to install WPLSoft editing software:

Item	System requirements
Operating system	Windows 95/98/2000/NT/ME/XP
CPU	At least Pentium 90
Memory	At least 16 MB (we recommend at least 32 MB)
Hard drive	Hard drive capacity: at least 100MB free space One optical drive (for use in installing this software)
Display	Resolution: 640 × 480, at least 16 colors; it is recommended that the screen area be set at 800 × 600 pixels
Mouse	Ordinary mouse or Windows-compatible device
Printer	Printer with a Windows driver program
RS-485 port	Must have at least an RS-485 port to link to the PLC

16-2 Notes before PLC use

1. The PLC has a preset communications format of 7, N, 2, 9600, with node 2; the PLC node can be changed in Pr.09-35, but this address may not be the same as the drive's address setting of Pr.09-00.
2. The CP2000 provides two communications serial ports that can be used to download PLC programs (see figure below). Channel 1 has a fixed communications format of 19200, 8, N, 2 RTU.



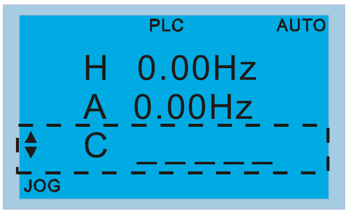
3. The client can simultaneously access data from the converter and internal PLC, which is performed through identification of the node. For instance, if the converter node is 1 and the internal PLC node is 2, then the client command will be
   01 (node) 03 (read) 0400 (address) 0001 (1 data item), indicating that it must read the data in converter Pr.04-00.
   02 (node) 03 (read) 0400 (address) 0001 (1 data item), indicating that it must read the data in internal PLC X0
4. The PLC program will be disabled when uploading/ downloading programs.
5. Please note when using WPR commands to write in parameters, values may be modified up to a maximum of 10^9 times, otherwise a memory write error will occur. The calculation of modifications is based on whether the entered value has been changed. If the entered value is left unchanged, the modifications will not increase afterwards. But if the entered value is different from before, the number of modifications will increase by one. Those parameters listed below are exceptions, proceed to the next page for details:

   - Pr.00-11 Speed control mode
   - Pr.01-12–01-19 Acceleration / Deceleration time 1–4
   - Pr.02-12 Multi-function input mode selection
   - Pr.02-18 Multi-function output direction
   - Pr.04-50–04-59 PLC buffer 0–9
   - Pr.08-04 Upper limit of integral control
   - Pr.08-05 PID output command limit

6. When Pr.00-04 is set as 28, the displayed value is the value of PLC register D1043 (see figure below):

   Keypad KPC-CC01

   Can display 0–65535

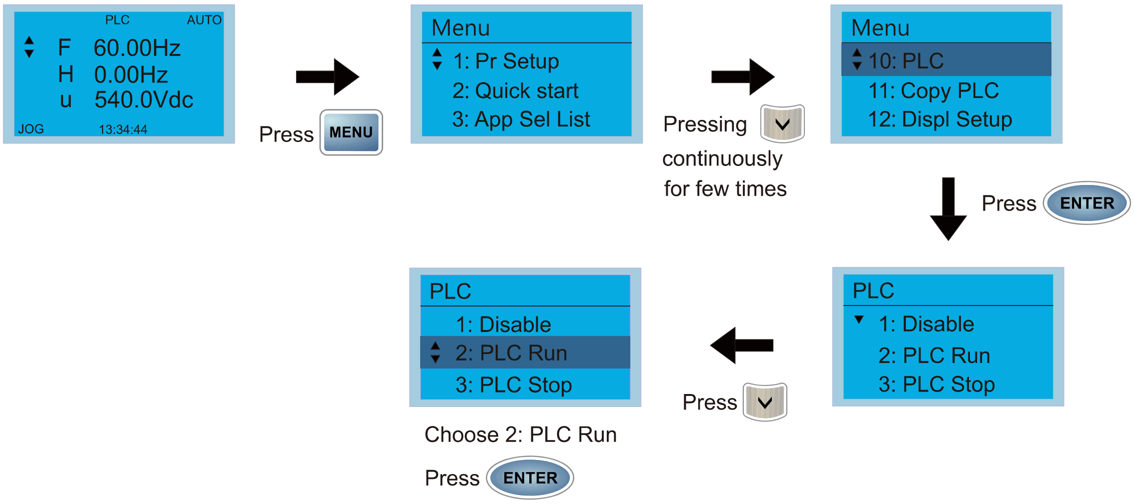
7. In the PLC Run and PLC Stop mode, the content 9 and 10 of Pr.00-02 cannot be set nor be reset to the default value.
8. The PLC can be reset to the default value when Pr.00-02 is set as 6.
9. The corresponding MI function will be disabled when the PLC writes to input contact X.
10. When the PLC controls converter operation, control commands will be entirely controlled by the PLC and will not be affected by the setting of parameter 00-21.
11. When the PLC controls converter frequency commands (FREQ commands), frequency commands will be entirely controlled by the PLC, and will not be affected by the setting of Pr.00-20 or the Hand ON/OFF configuration.
12. When the PLC controls the drive’s operation, if the keypad Stop setting is valid, this will trigger an FStP error and cause stoppage.

16-3 Turn on

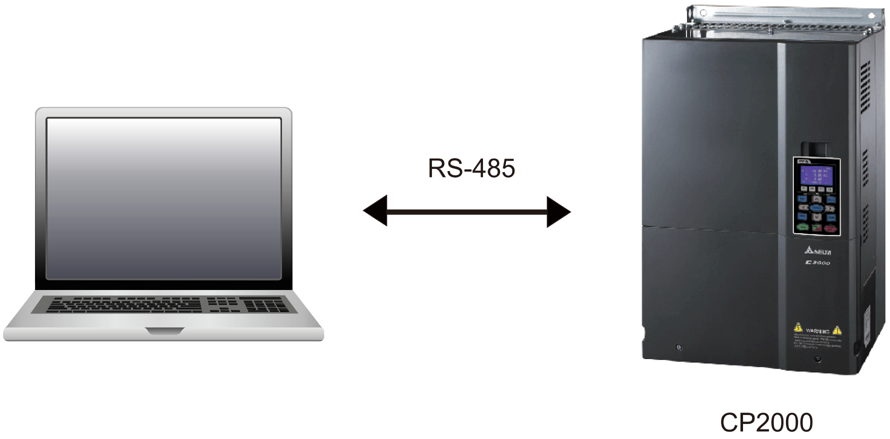
16-3-1 Connect to PC

Start operation of PLC functions in accordance with the following four steps

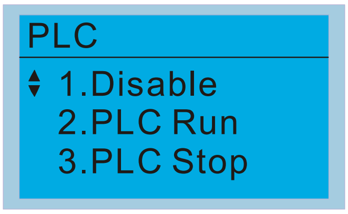
1. After pressing the Menu key and selecting 4: PLC on the KPC-CC01 digital keypad, press the Enter key (see figure below).



2. Wiring: Connect the driver's RJ45 communications interface to a PC via the RS-485



3. PLC function usage



- PLC functions are as shown in the figure on the left; select item 2 and implement PLC functions.

1: No function (Disable)

2: Enable PLC (PLC Run)

3: Stop PLC functions (PLC Stop)

- When the external multifunctional input terminals (MI1–MI8) are in PLC Mode select bit0 (51) or PLC Mode select bit1 (52), and the terminal contact is closed or open, it will compulsorily switch to the PLC mode, and keypad switching will be ineffective. Corresponding actions are as follows:

PLC mode Using KPC-CC01	PLC Mode select bit1(52)	PLC Mode select bit0 (51)
Disable	OFF	OFF
PLC Run	OFF	ON
PLC Stop	ON	OFF
Maintain previous state	ON	ON

NOTE

- When input/output terminals (FWD REV MI1–MI8, MI10–15, Relay1–3, RY10–RY15, MO10–MO11,) are included in the PLC program, these input/output terminals will only be used by the PLC. As an example, when the PLC program controls Y0 during PLC operation (PLC1 or PLC2), the corresponding output terminal relay (RA/RB/RC) will operate in accordance with the program. At this time, the multifunctional input/output terminal setting will be ineffective. Because these terminal functions are already being used by the PLC, the DI DO AO in use by the PLC can be determined by looking at Pr.02-52, Pr.02-53, and Pr.03-30.
- When the PLC's procedures use special register D1040, the corresponding AO contact AFM1 will be occupied, and AFM2 corresponding to special register D1045 will have the same situation.
- Pr.03-30 monitors the state of action of the PLC function analog output terminal; bit0 corresponds to the AFM1 action state, and bit1 corresponds to the AFM2 action state.

16-3-2 I/O device explanation

Input devices:

Serial No.	X0	X1	X2	X3	X4	X5	X6	X7	X10	X11	X12	X13	X14	X15	X16	X17
1	FWD	REV	MI1	MI2	MI3	MI4	MI5	MI6	MI7	MI8						
2											MI10	MI11	MI12	MI13	MI14	MI15
3											MI10	MI11	MI12	MI13		

1: Control I/O

2: Extension card: EMC-D611A (D1022=4)

3: Extension card: EMC-D42A (D1022=5)

Output devices:

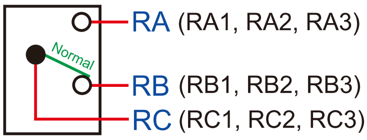
Serial No.	Y0	Y1	Y2	Y3	Y4	Y5	Y6	Y7	Y10	Y11	Y12	Y13	Y14	Y15	Y16	Y17
1	RY1	RY2	RY3													
2						MO10	MO11									
3						RY10	RY11	RY12	RY13	RY14	RY15					

1: Control I/O

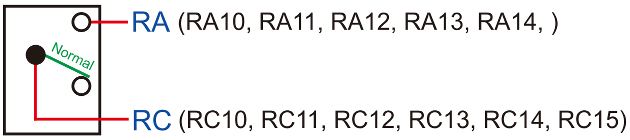
2: Extension card: EMC-D42A (D1022=5)

3: Extension card: EMC-R6AA (D1022=6)

RY1 / RY2 / RY3



RY10 / RY11 / RY12 / RY13 / RY14 / RY15


RA (RA10, RA11, RA12, RA13, RA14,)
Normal
RC (RC10, RC11, RC12, RC13, RC14, RC15)

16-3-3 Installation WPLSoft

Download and install WPLSoft editing software in Delta's website:

After completing installation, the WPLSoft program will be installed in the designated subfolder "C: \Program Files\Delta Industrial Automation\WPLSoft x.xx".

16-3-4 Program writing

Step 1: Click on the WPLSoft icon to start the editing software. (See figure 16-1)

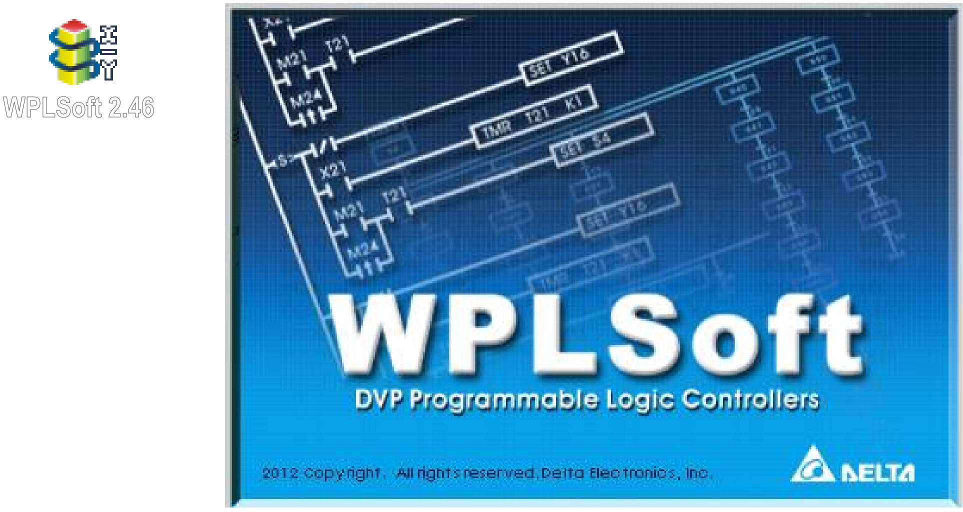

WPLSoft 2.46
WPLSoft
DVP Programmable Logic Controllers
2012 copyright. All rights reserved. Delta Electronics, Inc.
DELTA

Figure 16-1 (Left: WPLSoft icon; Right: Start WPLSoft)

Step 2: The WPLSoft editing window appears (see figure 16-2 below). When running WPLSoft for the first time, before "New file" has been used, only the "File (F)," "Communications (C)," View (V)," "Options (O)," and "Help (H)" columns will appear on the function toolbar.

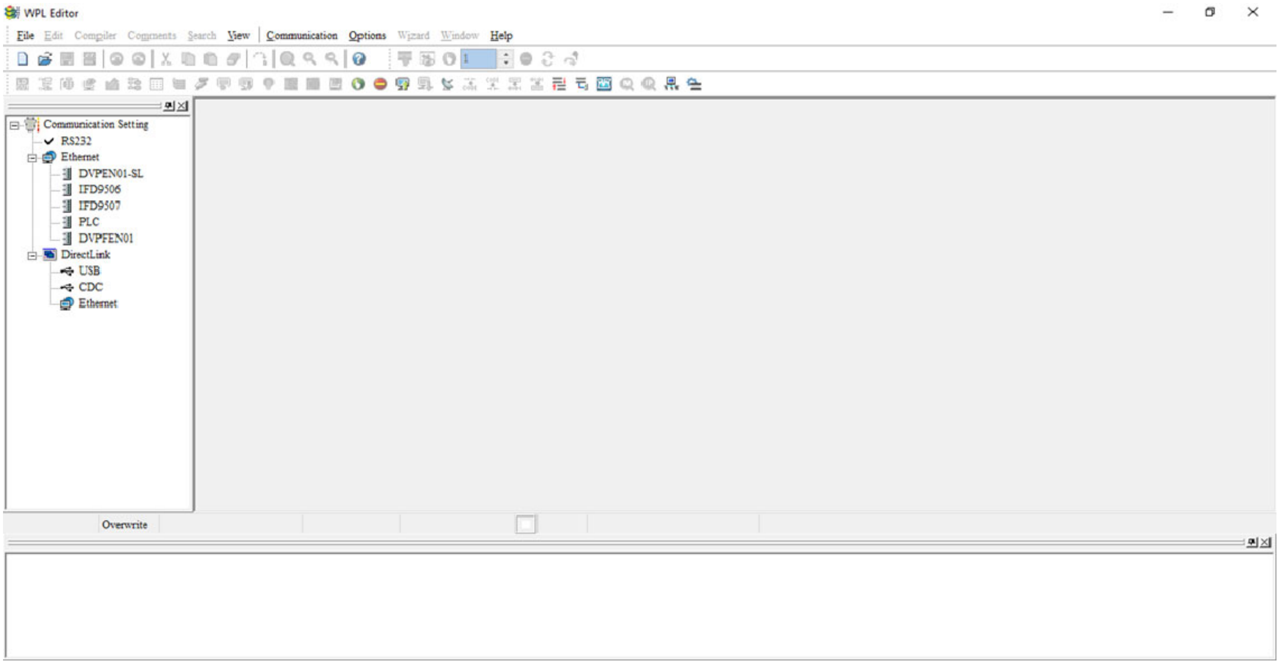


Figure 16-2

NOTE After running WPLSoft for the second time, the last file edited will open and be displayed in the editing window. The following figure 16-3 provides an explanation of the WPLSoft editing software window:

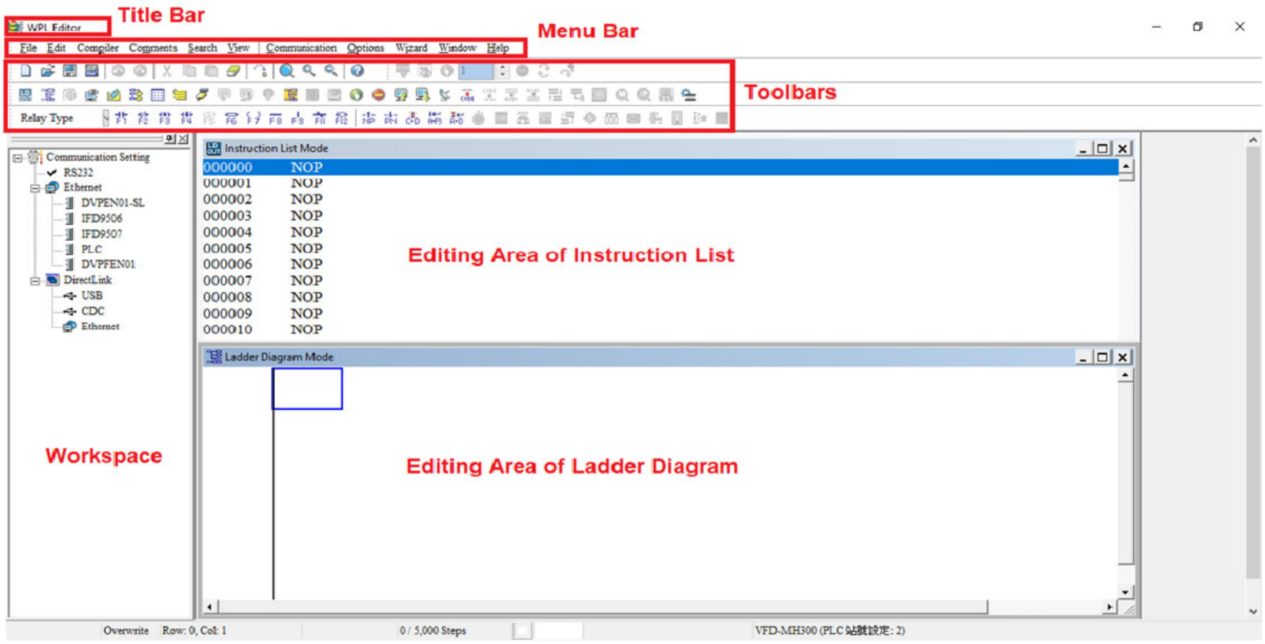


Figure 16-3

Step 3: Click on the icon on the toolbar: opens new file (Ctrl+N), see figure 16-4 below

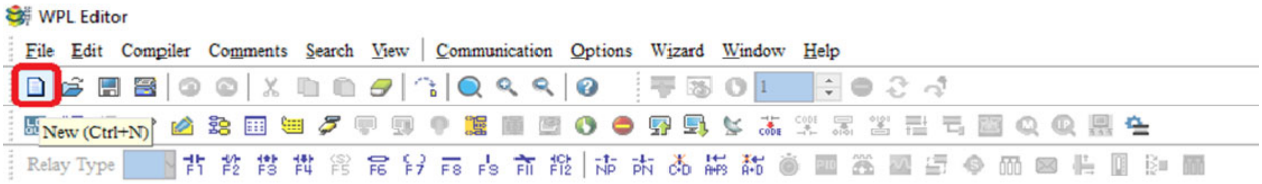

WPL Editor
File Edit Compiler Comments Search View Communication Options Wizard Window Help
New (Ctrl+N)
Relay Type
F1 F2 F3 F4 F5 F6 F7 F8 F9 F11 F12

Figure 16-4

NOTE You can also find “New file (N) (Ctrl+N)” in the "File (F)", as shown in figure 16-5 below.

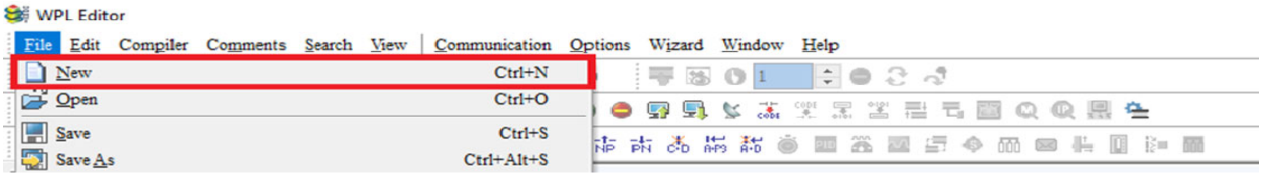
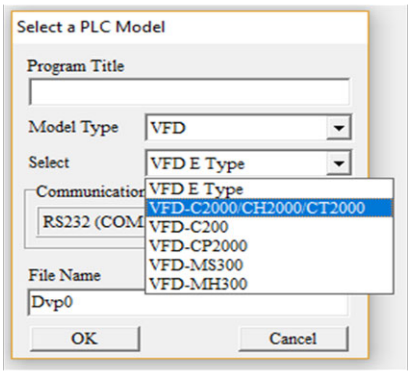

WPL Editor
File Edit Compiler Comments Search View Communication Options Wizard Window Help
New Ctrl+N
Open Ctrl+O
Save Ctrl+S
Save As Ctrl+Alt+S

Figure 16-5

Step 4: The "Device settings" window will appear after clicking, see figure 16-6 below. You can now enter the project title and filename, and select the device and communication settings to be used.



Select a PLC Model

Program Title:

Model Type: VFD

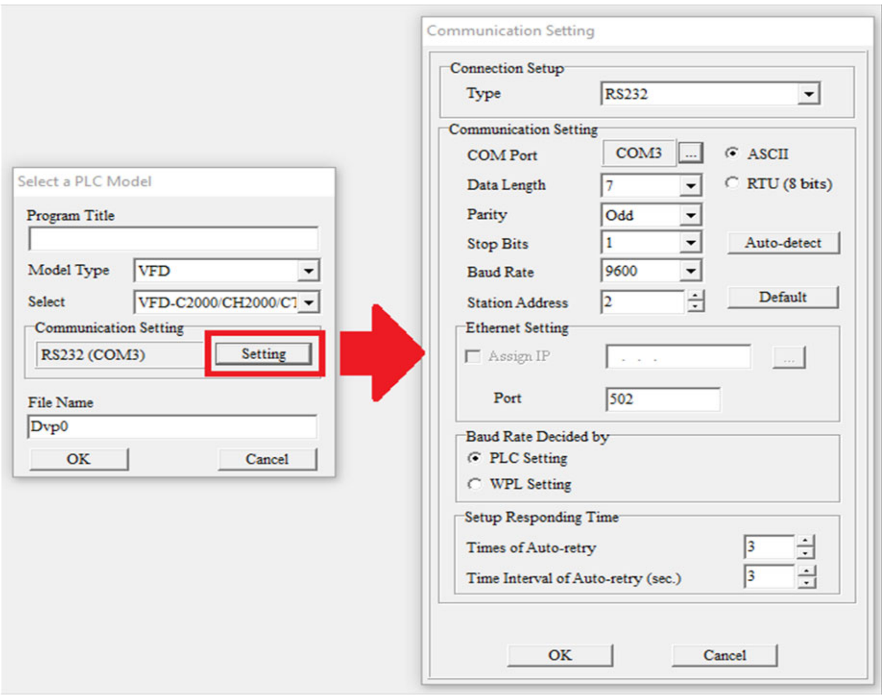
Select: VFD E Type

Communication: RS232 (COM

File Name: Dvp0

Figure 16-6

Communications settings: Perform settings in accordance with the desired communications method. See figure 16-7 below.



Select a PLC Model

Program Title:

Model Type: VFD

Select: VFD-C2000/CH2000/C1

Communication Setting: RS232 (COM3)

File Name: Dvp0

Communication Setting

Connection Setup

Type: RS232

Communication Setting

COM Port: COM3

Data Length: 7

Parity: Odd

Stop Bits: 1

Baud Rate: 9600

Station Address: 2

● ASCII

○ RTU (8 bits)

Ethernet Setting

☐ Assign IP

Port: 502

Baud Rate Decided by

● PLC Setting

○ WPL Setting

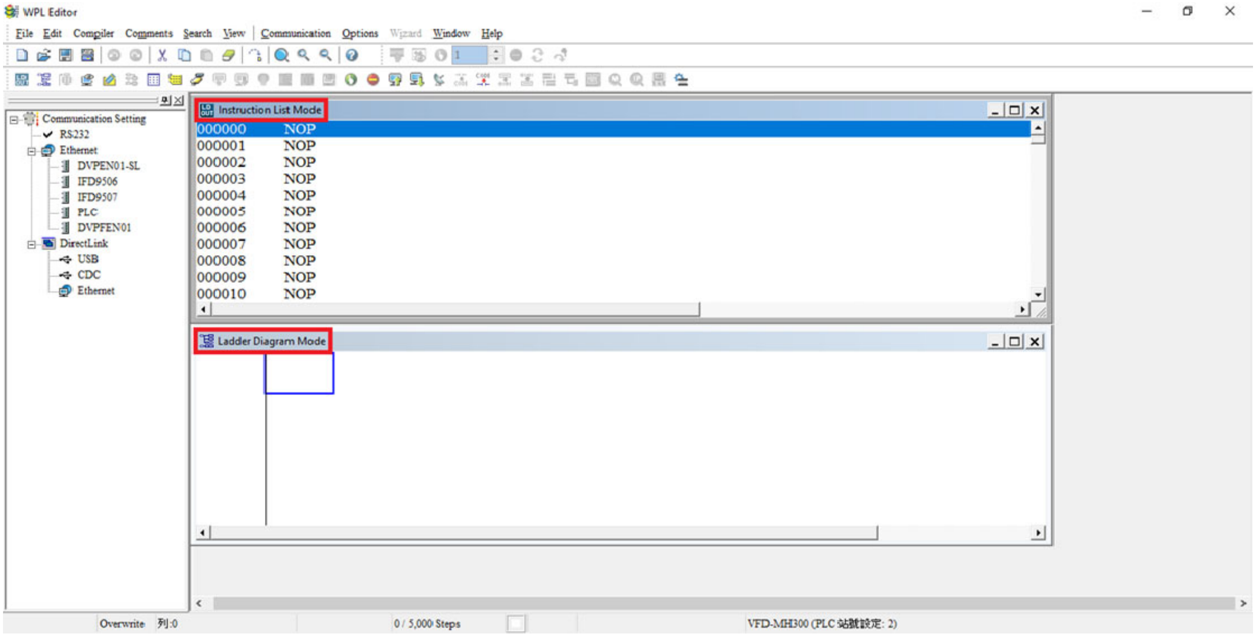
Setup Responding Time

Times of Auto-retry: 3

Time Interval of Auto-retry (sec.): 3

Figure 16-7

Step 5: Press Confirm after completing settings and begin program editing. There are two program editing methods; you can choose whether to perform editing in the command mode or the ladder diagram mode (see figure 16-8 below).



```
000000    NOP
000001    NOP
000002    NOP
000003    NOP
000004    NOP
000005    NOP
000006    NOP
000007    NOP
000008    NOP
000009    NOP
000010    NOP
```

Figure 16-8

NOTE In ladder diagram mode, you can perform program editing using the buttons on the function icon row (see figure 16-9 below).

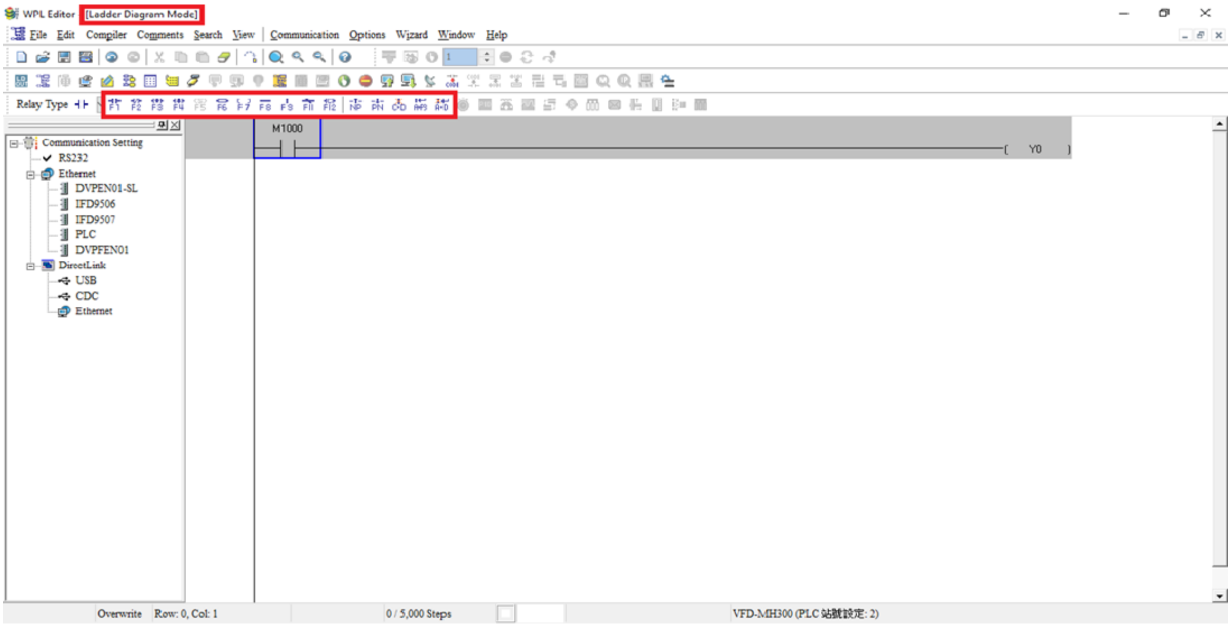

WPL Editor [Ladder Diagram Mode]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
Relay Type
F1 F2 F3 F4 F5 F6 F7 F8 F9 F11 F12 NP PN CD INV R-0
Communication Setting
RS232
Ethernet
DVPEN01-SL
IFD9506
IFD9507
PLC
DVPFEN01
DirectLink
USB
CDC
Ethernet
M1000
Y0
Overwrite Row: 0, Col: 1
0 / 5,000 Steps
VFD-MH300 (PLC 站號設定: 2)

Figure 16-9

Basic Operation-Example

Input the ladder diagram as the figure below. The following steps can be operated through the mouse or function key (F1–F12) on the keyboard.

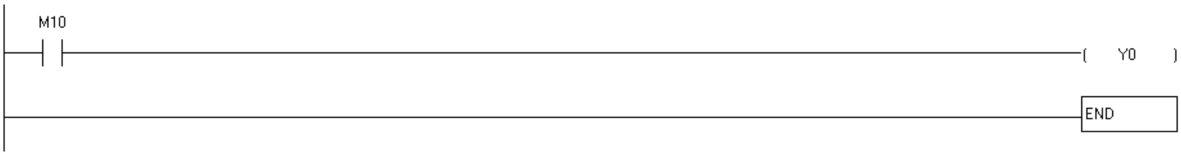


Figure 16-10

Step 1: The following screen will appear after a new file is established:

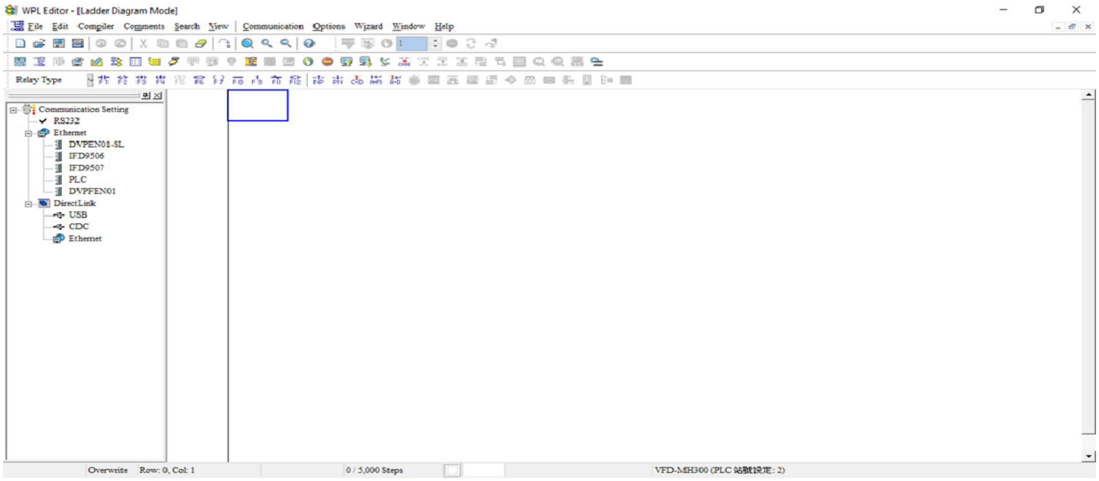
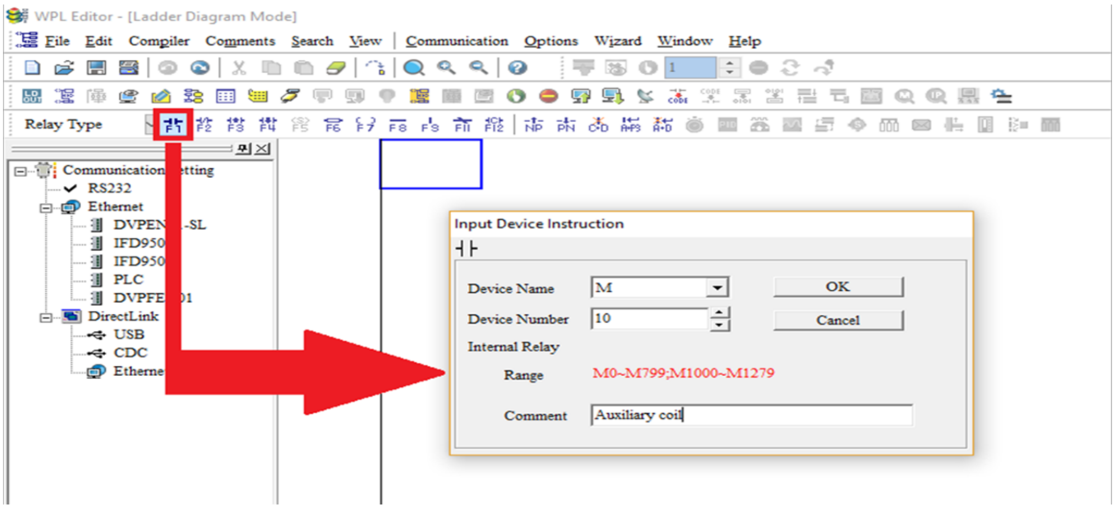


Figure 16-11

Step 2: Click on the always-open switch icon F1 or press the function key F1. After the name of the input device and the comment dialog box have appeared, the device name (such as "M"), device number (such as "10"), and input comments (such as "auxiliary contact") can be selected; press the OK button when finished (see figure 16-12 and 16-13 below).


WPL Editor - [Ladder Diagram Mode]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
Relay Type
Communication Setting
RS232
Ethernet
PLC
DirectLink
USB
CDC
OK
Cancel

Input Device Instruction

Device Name: M

Device Number: 10

Internal Relay

Range: M0~M799;M1000~M1279

Comment: Auxiliary coil

Figure 16-12

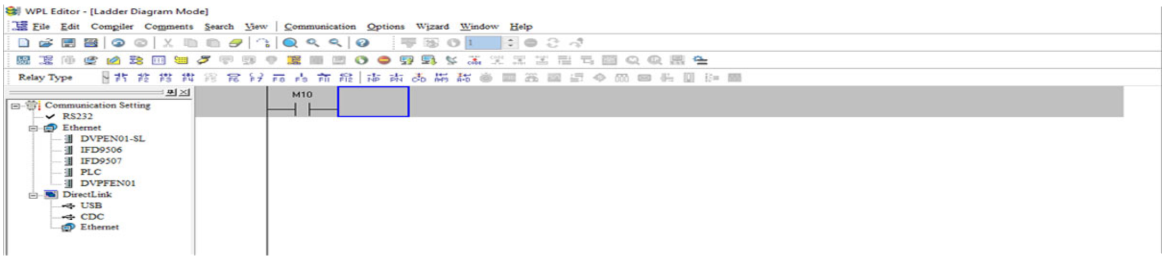
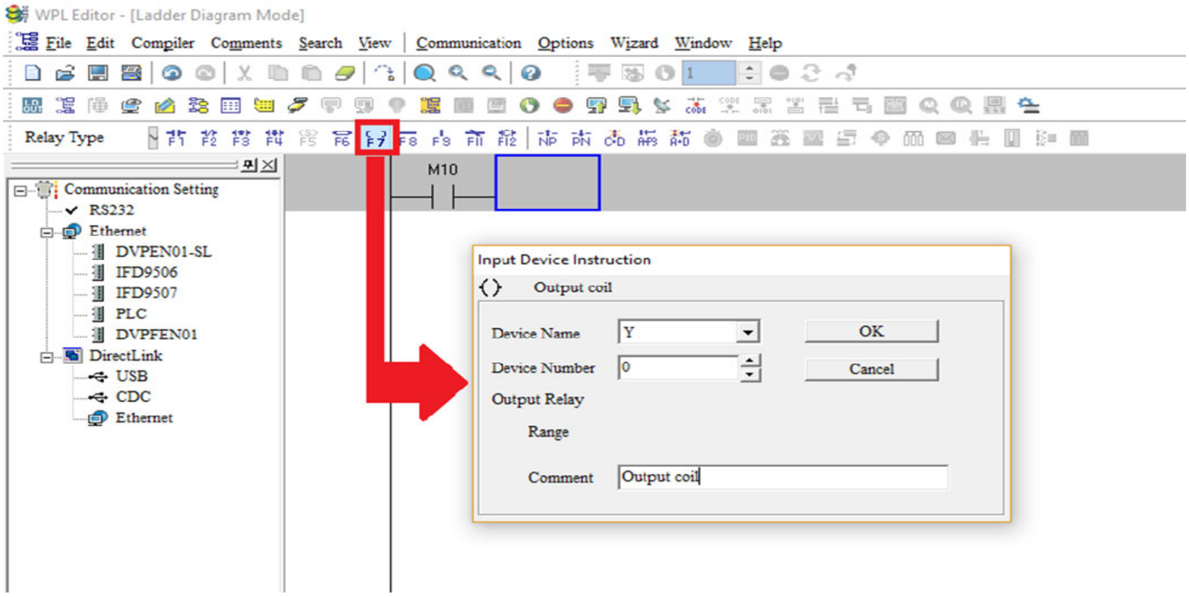

WPL Editor - [Ladder Diagram Mode]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
Relay Type
Communication Setting
RS232
Ethernet
DVPEN01-SL
IFD9506
IFD9507
PLC
DVPFEN01
DirectLink
USB
CDC
Ethernet
M10

Figure 16-13

Step 3: Click on the output coil icon F7 or press function key F7. After the name of the input device and the comment dialog box have appeared, the device name (such as "Y"), device number (such as "0"), and input comments (such as "output coil") can be selected; press the OK button when finished (see figure 16-14 and 16-15 below).


WPL Editor - [Ladder Diagram Mode]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
Relay Type
Communication Setting
RS232
Ethernet
DVPEN01-SL
IFD9506
IFD9507
PLC
DVPFEN01
DirectLink
USB
CDC
Ethernet
M10
OK
Cancel

Input Device Instruction

{ } Output coil

Device Name: Y

Device Number: 0

Output Relay

Range

Comment: Output coil

Figure 16-14

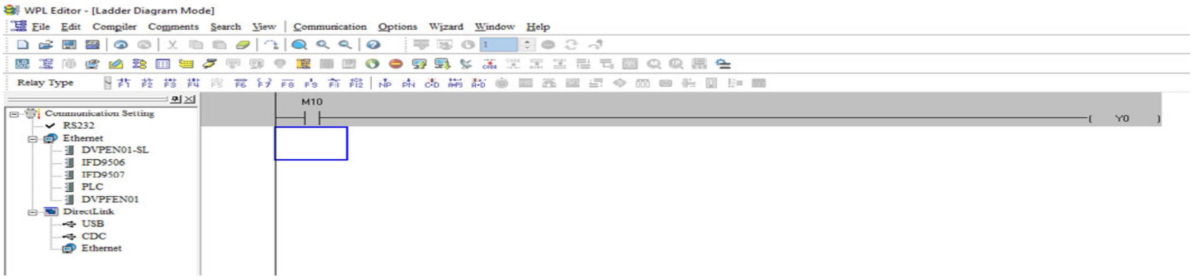
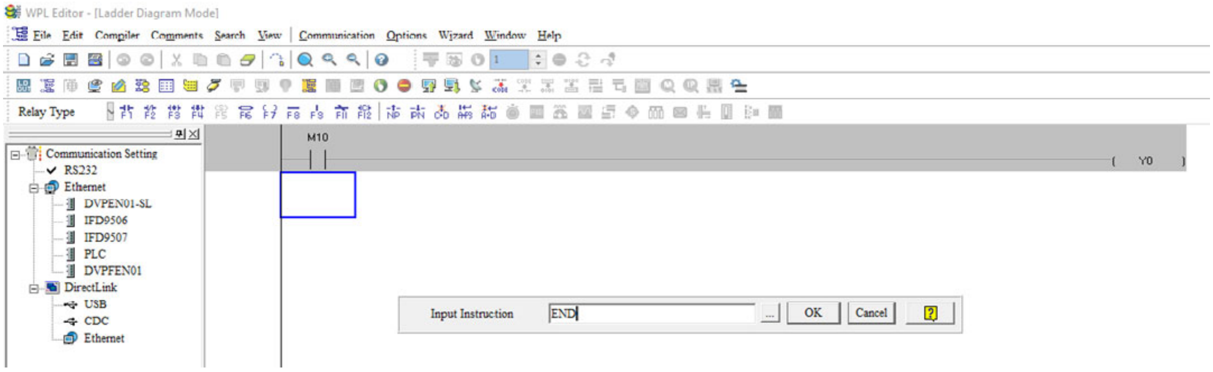

WPL Editor - [Ladder Diagram Mode]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
Relay Type
Communication Setting
RS232
Ethernet
DVPEN01-SL
IFD9506
IFD9507
PLC
DVPFEN01
DirectLink
USB
CDC
Ethernet
M10
Y0

Figure 16-15

Step 4: Press “ENTER” button, when the “Input Instructions” window appears, key in “END” in the field and press the OK button (see figure 16-16 and 16-17 below).



Input Instruction: END

Figure 16-16

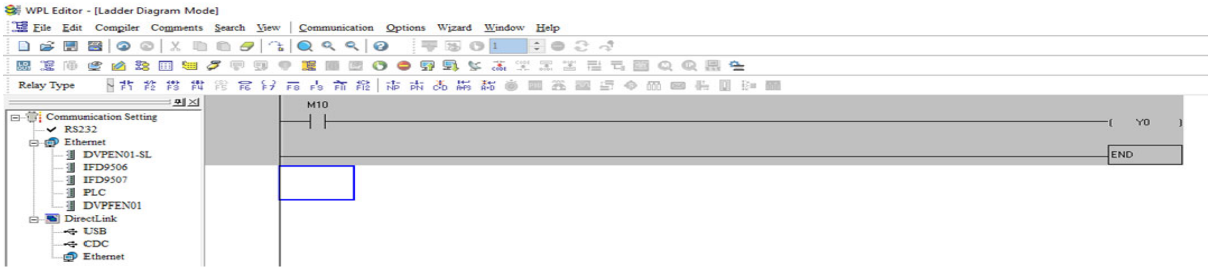
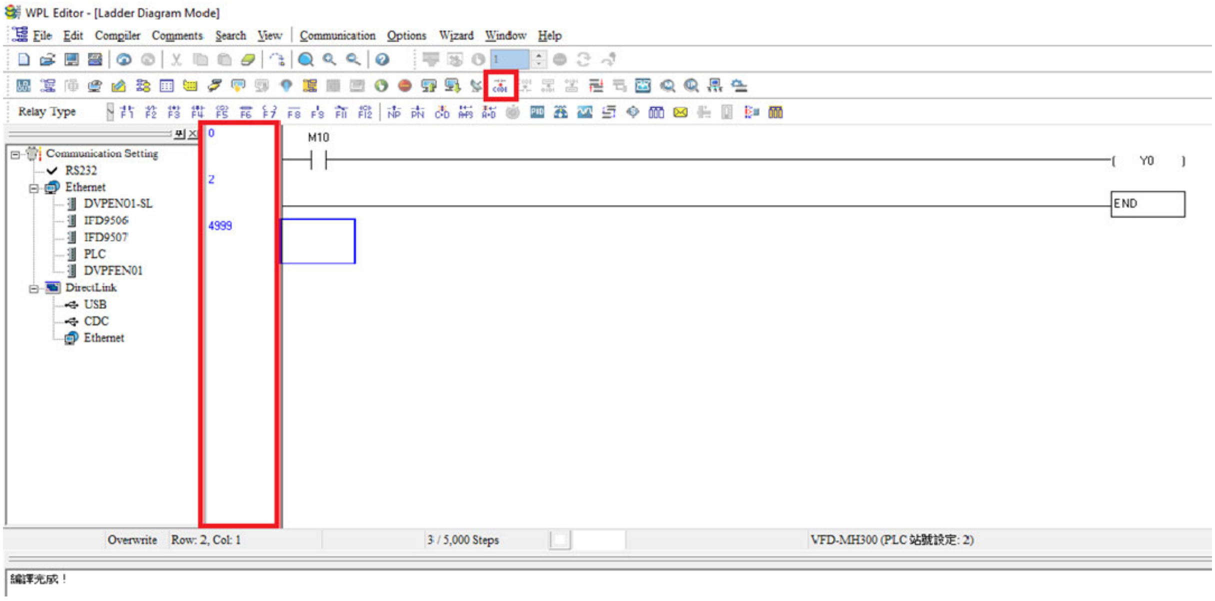

WPL Editor - [Ladder Diagram Mode]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
Relay Type
Communication Setting
RS232
Ethernet
DVPEN01-SL
IFD9506
IFD9507
PLC
DVPFEN01
DirectLink
USB
CDC
Ethernet
M10
Y0
END

Figure 16-17

Step 5: Click on the “Ladder diagram => Code” icon, which will compile the edited ladder diagram as a command program. After compiling, the number of steps will appear on the left side of the busbar (see figure 16-18 below).



Overwrite Row: 2, Col: 1 3 / 5,000 Steps VFD-MH300 (PLC站號設定: 2)

編譯完成！

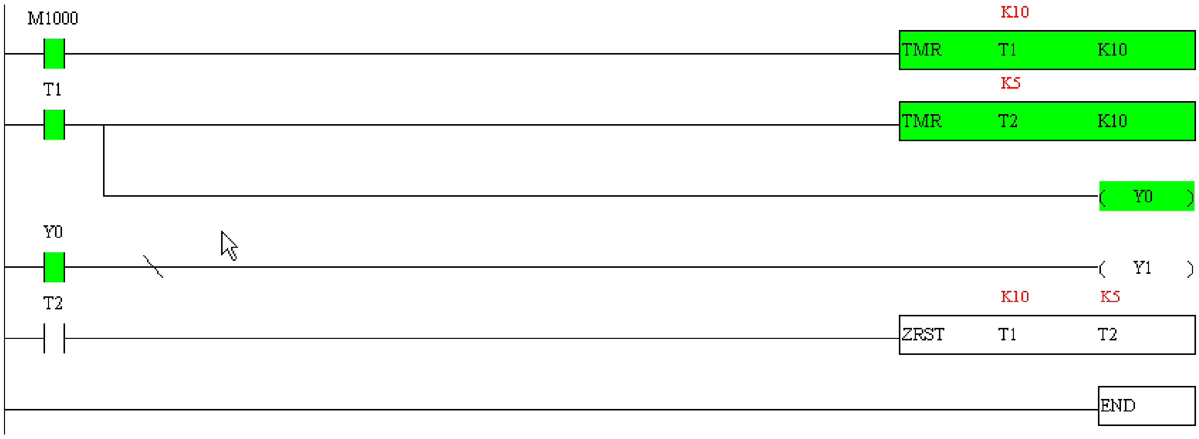
Figure 16-18

16-3-5 Program download

After inputting a program using WPLSoft, select compile . After completing compilation, select the to download a program. WPLSoft will perform program download with the online PLC in the communications format specified in communications settings.

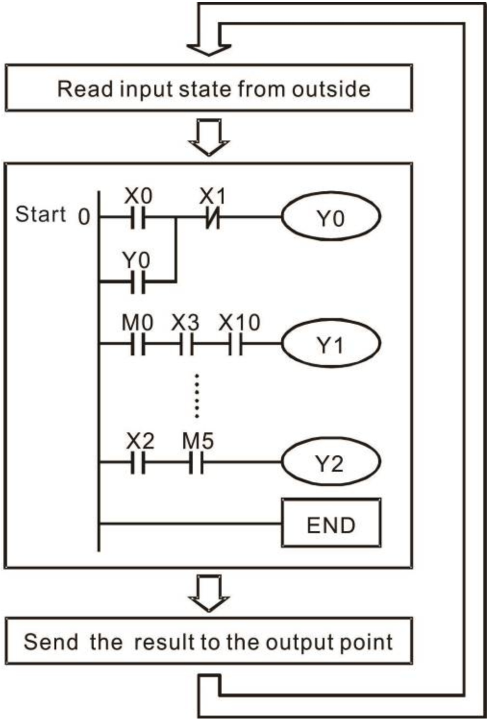
16-3-6 Program monitoring

While confirming that the PLC is in the Run mode, after downloading a program, click on in the communications menu and select start ladder diagram control (see figure below)



16-4 Basic principles of PLC ladder diagrams

16-4-1 Schematic diagram of PLC ladder diagram program scanning


Read input state from outside
Start 0
X0
X1
Y0
Y0
M0
X3
X10
Y1
X2
M5
Y2
END
Send the result to the output point

Output results are calculated on the basis of the ladder diagram configuration (internal devices will have real-time output before results are sent to an external output point)

Repeated implementation

16-4-2 Introduction to ladder diagrams

Ladder diagrams comprise a graphic language widely applied in automatic control, and employs common electrical control circuit symbols. After a ladder diagram editor has been used to create a ladder pattern, PLC program designed is completed. The use of a graphic format to control processes is very intuitive, and is readily accepted by personnel who are familiar with electrical control circuit technology. Many of the basic symbols and actions in a ladder diagram comprise commonly seen electrical devices in conventional automatic control power distribution panels, such as buttons, switches, relays, timers, and counters.

Internal PLC devices: The types and quantities of internal PLC devices vary in different brands of products. Although these internal devices use the same names as conventional electrical control circuit elements such as relays, coils, and contacts, a PLC does not actually contain these physical devices, and they instead correspond to basic elements in the PLC's internal memory (bits). For instance, if a bit is 1, this may indicate that a coil is electrified, and if that bit is 0, it will indicate that the coil is not electrified. An N.O. contact (Normal Open, or contact a) can be used to directly read the value of the corresponding bit, and an N.C. contact (Normal Close, or contact b) can be used to obtain the inverse of the bit's value. Multiple relays occupy multiple bits, and 8 bits comprise one byte; two bytes comprise one word, and two words comprise a double word. When multiple relays are processing at the same time (such as addition / subtraction or displacement, etc.), a byte, word, or double word can be used. Furthermore, a PLC contains two types of internal devices: a timer and a counter. It not only has a coil, but can count time and numerical values. Because of this, when it is necessary to process some numerical values, these values are usually in the form of bytes, words, or double words.

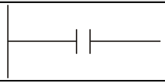
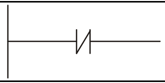
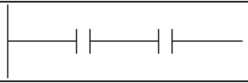
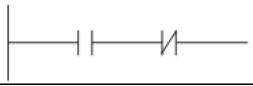
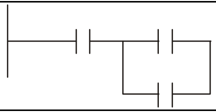
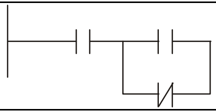
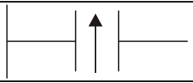
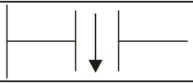
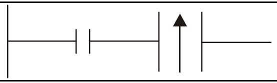
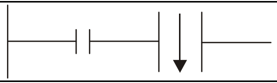
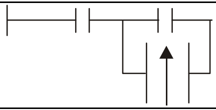
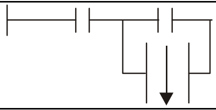
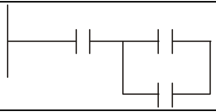
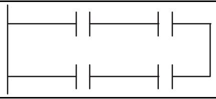
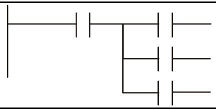
The various internal devices in a PLC all account for a certain quantity of storage units in the PLC's storage area. When these devices are used, the content of the corresponding storage area is red in the form of bits, bytes, or words.

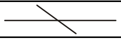
Introduction to the basic internal devices in a PLC

Device type	Description of Function
Input Relay	An input relay constitutes the basic unit of storage in a PLC's internal memory corresponding to an external input point (which serves as a terminal connecting with an external input switch and receiving external input signals). It is driven by external input signals, to which it assigns values of 0 or 1. A program design method cannot change the input relay status, and therefore cannot rewrite the corresponding basic units of an input relay, and WPLSoft cannot be used to perform compulsory ON / OFF actions. A relay's contacts (contacts a and b) can be used an unlimited number of times. An input relay with no input signal must be left idle and cannot be used for some other purpose. ☑ Device indicated as: X0, X1, X7, X10, X11, etc. This device is expressed with the symbol "X," and a device's order is indicated with an octal number. Input point numbers are indicated in Section 16-8 I/O devices explanation.
Output Relay	An output relay constitutes the basic unit of storage in a PLC's internal memory corresponding to an external output point (which connects with an external load). It may be driven by an input relay contact, a contact on another internal device, or its own contacts. It uses one N.O. contact to connect with external loads or other contacts, and, like input contacts, can use the contact an unlimited number of times. An output relay with no input signal will be idle, but may be used an internal relay if needed. ☑ Device indicated as: Y0, Y1, Y7, Y10, Y11, etc. This device is expressed with the symbol "Y," and a device's order is indicated with an octal number. Output point numbers are indicated in Section 16-8 I/O devices explanation.
Internal Relay	Internal relays have no direct connection with the outside. These relays are auxiliary relays inside a PLC. Their function is the same as that of an auxiliary (central) relay in an electrical control circuit: Each auxiliary relay corresponding to a basic unit of internal storage; they can be driven by input relay contacts, output relay contacts, and the contacts of other internal devices. An internal auxiliary relay's contact can also be used an unlimited number of times. Internal relays have no outputs to outside, and must output via an output point. ☑ Device indicated as: M0, M1 to M799, etc. This device is expressed as the symbol "M," expressed, and its order is expressed as a decimal number.
Counter	A counter is used to perform counting operations. A count setting value (such as the number of pulses to be counted) must be assigned when a counter is used. A counter contains a coil, contact, and a counting storage device. When the coil goes from OFF to ON, this indicates that the counter has an input pulse, and one is added to its count. There are 16 bits that can be employed by the user. ☑ Device indicated as: C0, C1 to C79, etc. This device is expressed as the symbol "C," expressed, and its order is expressed as a decimal number.
Timer	A timer is used to complete control of timing. The timer contains a coil, contact, and a time value register. When the coil is electrified, if the preset time is reached, the contact will be actuated (contact a will close, contact b will open), and the timer's fixed value be given by the set value. Timer has a regulated clock cycle (timing units: 100 ms). As soon as power to the coil is cut off, the contact will no longer be actuated (contact a will open, contact b will close), and the original timing value will return to zero.

Device type	Description of Function
	☑ Device indicated as: T0, T1 to T159, etc. The device is expressed as the symbol "T," and its order is expressed as a decimal number.
Data register	When a PLC is used to perform various types of sequence control and set time value and count value control, it most commonly perform data processing and numerical operations, and data registers are used exclusively for storage of data and various parameters. Each data register contains 16 bits of binary data, which means that it can store one word. Two data registers with adjacent numbers can be used to process double words. Device indicated as: D0, D1 to D399, etc. The device is expressed as the symbol "D," and its order is expressed as a decimal number.

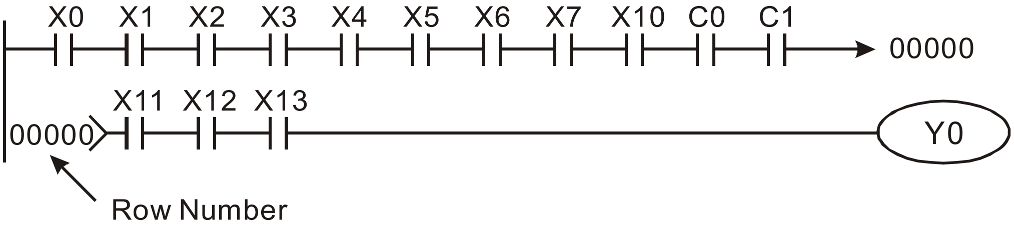
Ladder diagram images and their explanation

Ladder diagram structures	Explanation of commands	Command	Using Device
	N.O. switch, contact a	LD	X、Y、M、T、C
	N.C. switch, contact b	LDI	X、Y、M、T、C
	Series N.O.	AND	X、Y、M、T、C
	Series N.C.	ANI	X、Y、M、T、C
	Parallel N.O.	OR	X、Y、M、T、C
	Parallel N.C.	ORI	X、Y、M、T、C
	Positive edge-triggered switch	LDP	X、Y、M、T、C
	Negative edge-triggered switch	LDF	X、Y、M、T、C
	Positive edge-triggered series	ANDP	X、Y、M、T、C
	Negative edge-triggered series	ANDF	X、Y、M、T、C
	Positive edge-triggered parallel	ORP	X、Y、M、T、C
	Negative edge-triggered parallel	ORF	X、Y、M、T、C
	Block series	ANB	N/A
	Block parallel	ORB	N/A
	Multiple outputs	MPS MRD MPP	N/A

Ladder diagram structures	Explanation of commands	Command	Using Device
	Coil driven output commands	OUT	Y、M
	Some basic commands, applications commands	Some basic commands Applications commands	
	Inverted logic	INV	N/A

16-4-3 Overview of PLC ladder diagram editing

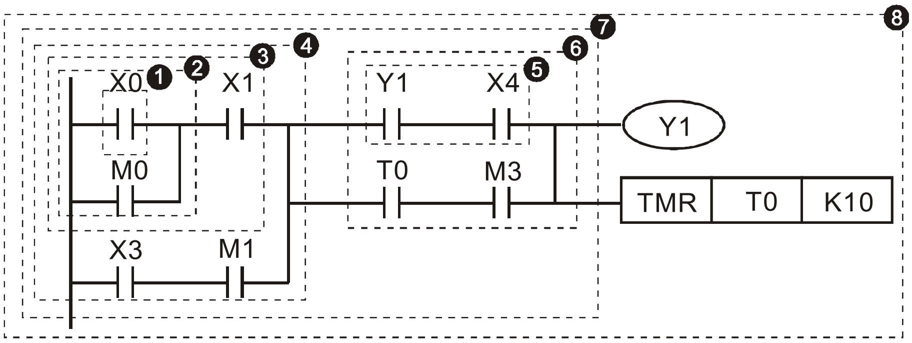
The program editing method begins from the left busbar and proceeds to the right busbar (the right busbar is omitted when editing using WPLSoft). Continue to the next row after completing each row; there is a maximum of 11 contacts on each row. If this is not sufficient, a continuous line will be will be generated to indicate the continued connection and more devices can be added. A continuous series of numbers will be generated automatically and identical input points can be used repeatedly. See figure below:



The ladder diagram programming method involves scanning from the upper left corner to the lower right corner. The coils and applications command computing box are handled in the output, and the ladder diagram is placed on the farthest right. Taking the figure below as an example, we can gradually analyze the procedural sequence of the ladder diagram. The number in the upper right corner gives the sequential order.

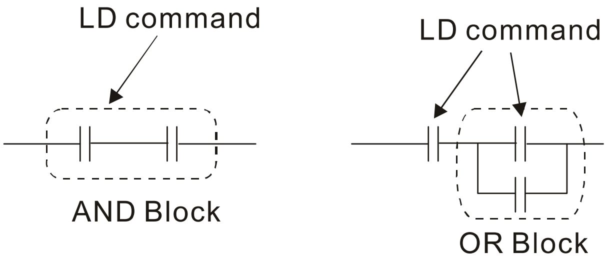
Explanation of command sequence

```
1    LD    X0
2    OR    M0
3    AND   X1
4    LD    X3
     AND   M1
     ORB
5    LD    Y1
     AND   X4
6    LD    T0
     AND   M3
     ORB
7    ANB
8    OUT   Y1
     TMR   T0    K10
```

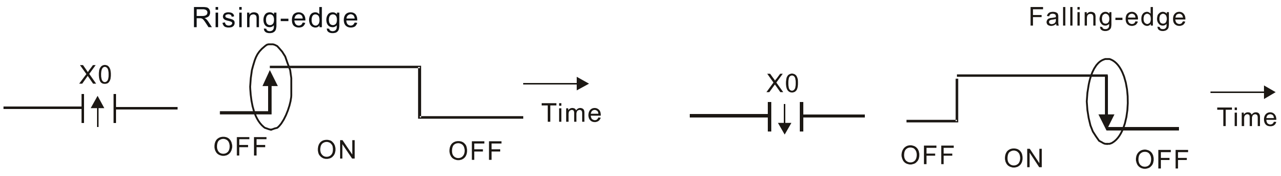


Explanation of basic structure of ladder diagrams

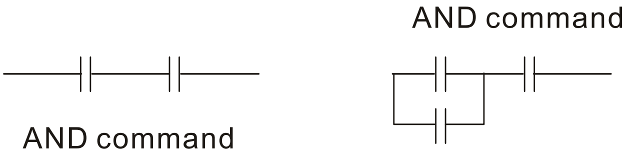
LD (LDI) command: An LD or LDI command is given at the start of a block.



LDP and LDF have this command structure, but there are differences in their action state. LDP, LDF only act at the rising or falling edge of a conducting contact. (see figure below):

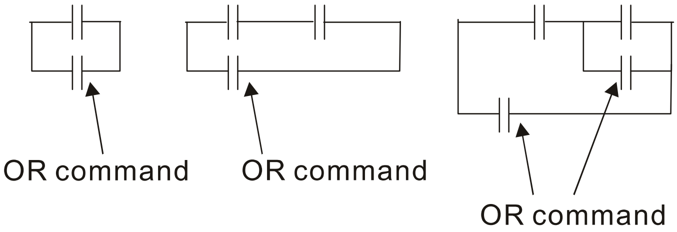


AND (ANI) command: A series configuration in which a single device is connected with one device or a block.



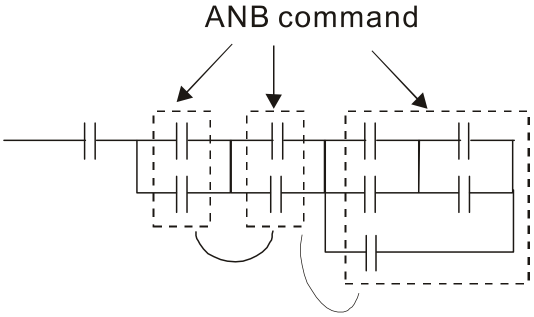
ANDP, ANDF also have structures like this, but their action occurs at the rising and falling edge.

OR (ORI) command: A single device is connected with one device or a block.

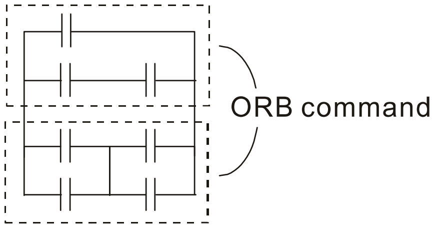


ORP, ORF also have identical structures, but their action occurs at the rising and falling edge.

ANB command: A configuration in which one block is in series with one device or block.



ORB command: A configuration in which one block is in parallel with one device or block.

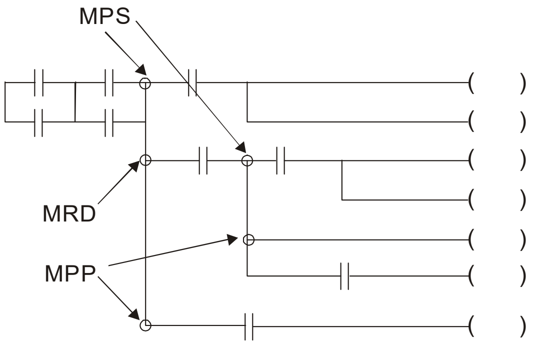


In the case of ANB and ORB operations, if a number of blocks are connected, they should be combined to form a block or network from the top down or from left to right.

MPS, MRD, MPP commands: Branching point memory for multiple outputs, enabling multiple, different outputs. The MPS command begins at a branching point, where the so-called branching point refers to the intersection of horizontal and vertical lines. We have to rely on the contact status along a single vertical line to determine whether the next contact can give a memory command. While each contact is basically able to give memory commands, in view of convenience and the PLC's capacity restrictions, this can be omitted from some places when converting a ladder diagram. The structure of the ladder diagram can be used to judge what kinds of contact memory commands are used.

MPS can be distinguished by use of the "┬" symbol; this command can be used consecutively for up to 8 times. The MRD command is read from branching point memory; because logic states along any one vertical line must be the same, in order to continue analysis of other ladder diagrams, the original contact status must be read.

MRD can be distinguished by use of the "├" symbol. The MPP command is read from the starting state of the uppermost branching point, and it is read from the stack (pop); because it is the final command along a vertical line, it indicates that the state of the vertical line can be concluded. MPP can be distinguished by use of the "└" symbol. Although there should basically be no errors when using the foregoing analytical approach, the compiling program may sometimes omit identical state output, as shown in the following figure:



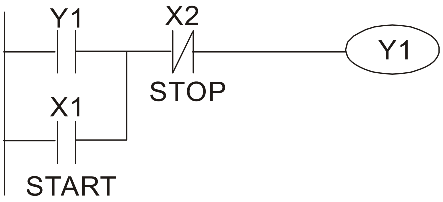
16-4-4 Commonly-used basic program design examples

Start, stop, and protection

Some applications may require a brief close or brief break using the buttons to start and stop equipment. A protective circuit, therefore, must be designed to maintain continued operation in these situations; this protective circuit may employ one of the following methods:

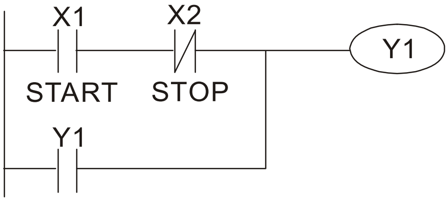
Example 1: Priority stop protective circuit

When the start N.O. contact X1 = ON, and the stop N.C. contact X2 = OFF, Y1 = ON; if X2 = ON at this time, coil Y1 will no longer be electrified, and this is therefore referred to as priority stop.



Example 2: Priority start protective circuit

When start N.O. contact X1 = ON, and the stop N.C. contact X2 = OFF, Y1 = ON, and coil Y1 will be electrified and protected. At this time, if X2 = ON, coil Y1 will still protect the contact and continue to be electrified, and this is therefore priority start.

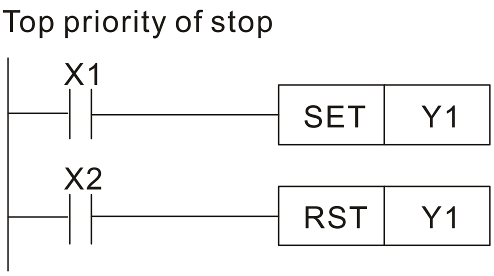


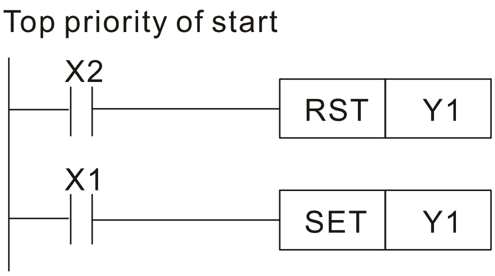
Example 3: Setting (SET) and reset (RST) command protective circuit

The following figure shows a protective circuit composed of RST and SET commands.

Priority stop occurs when the RST command is placed after the SET command. Because the PLC executes programs from the top down, at the end of the program, the state of Y1 will indicate whether coil Y1 is electrified. When X1 and X2 are both actuated, Y1 will lose power, and this is therefore priority stop.

Priority start occurs when the SET command is placed after the RST command. When X1 and X2 are both actuated, Y1 will be electrified, and this is therefore priority start.

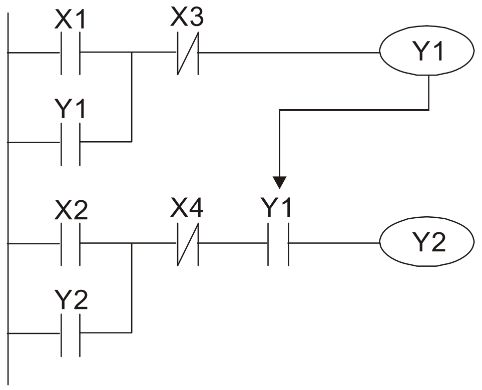


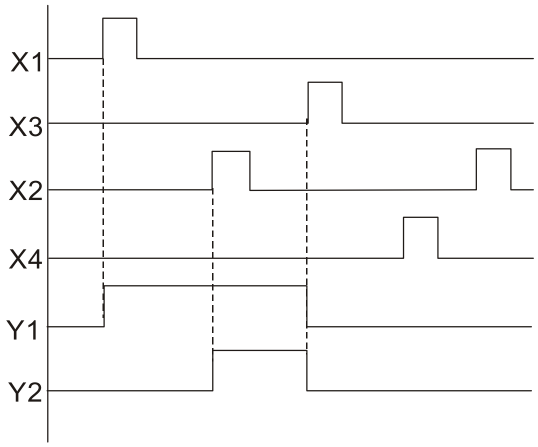


Commonly-used control circuits

Example 4: Conditional control

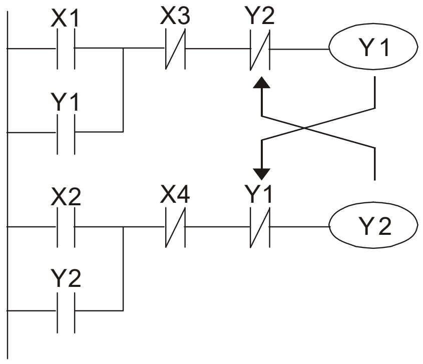
X1 and X3 respectively starts and stops Y1; X2 and X4 respectively starts and stops Y2. All of these have protective circuits. Because Y1's N.O. contact is series connected with Y2's circuit, it becomes an AND condition for the actuation of Y2. The action of Y1 is therefore a condition for the action of Y2, and Y1 must be actuated before Y2 can be actuated.

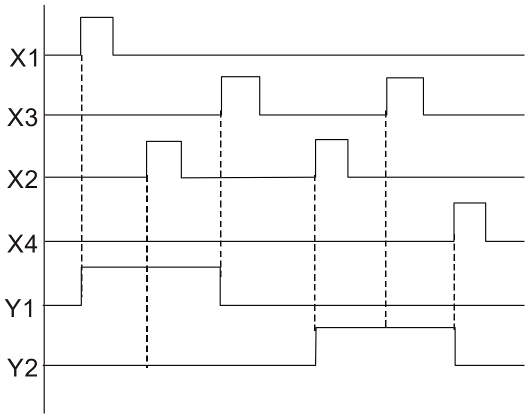




Example 5: Interlocking control

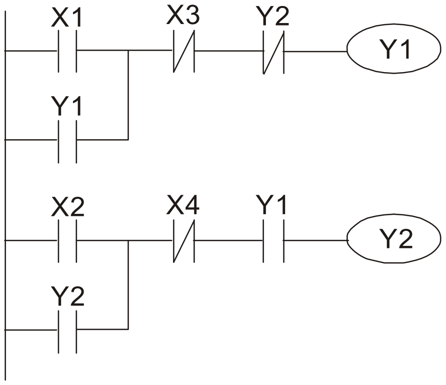
The figure below shows an interlocking control circuit. Depending on which of the start contacts X1, X2 is valid first, the corresponding output Y1 or Y2 will be actuated, and when one is actuated, the other will not be actuated. This implies that Y1 and Y2 cannot be actuated at the same time (interlocking effect). Even if both X1 and X2 are valid at the same time, because the ladder diagram program is scanned from the top down, it is impossible for Y1 and Y2 to be actuated at same time. This ladder diagram assigns priority only to Y1.





Example 6: Sequence control

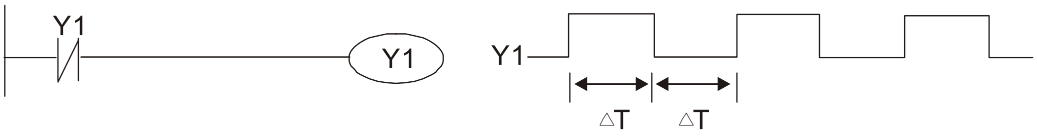
If the N.C. contact of Y2 in the interlocking control configuration of example 5 is put in series with the Y1 circuit, so that it is an AND condition for actuation of Y1 (see figure below), not only is Y1 a condition for the actuation of Y2 in this circuit, the actuation of Y2 will also stop the actuation of Y1. This configuration confirms the actuation order of Y1 and Y2.



Example 7: Oscillating circuit

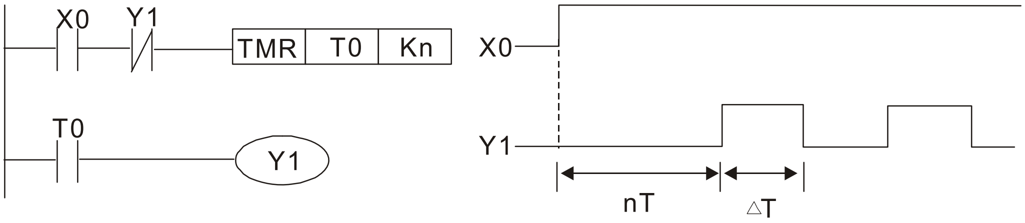
Oscillating circuit with a period of ΔT+ΔT

The figure below shows a very simple ladder diagram. When starting to scan the Y1 N.C. contact, because the Y1 coil has lost power, the Y1 N.C. contact will be closed. When the Y1 coil is then scanned, it will be electrified, and the output will be 1. When the Y1 N.C. contact is scanned in the scanning cycle, because Y1 coil is electrified, the Y1 N.C. contact will be open, the Y1 coil will then lose power, and the output will be 0. Following repeated scanning, the output of Y1 coil will have an oscillating waveform with a period of ΔT (On) +ΔT (Off).



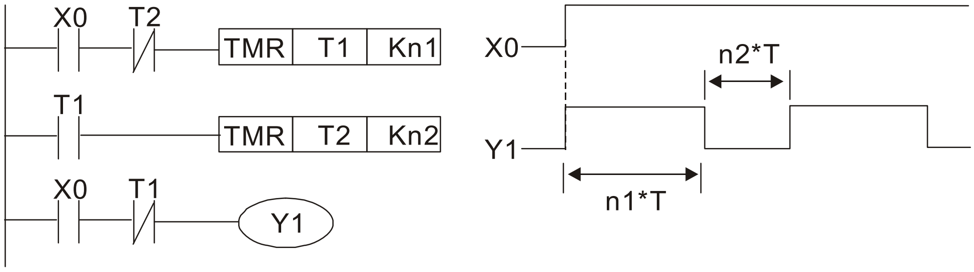
Oscillating circuit with a period of nT+ΔT

The program of the ladder diagram shown below uses timer T0 to control coil Y1's electrified time. After Y1 is electrified, it causes timer T0 to close during the next scanning cycle, which will cause the output from Y1 to have the oscillating waveform shown in the figure below. Here n is the timer's decimal setting value, and T is the clock cycle of the timer.



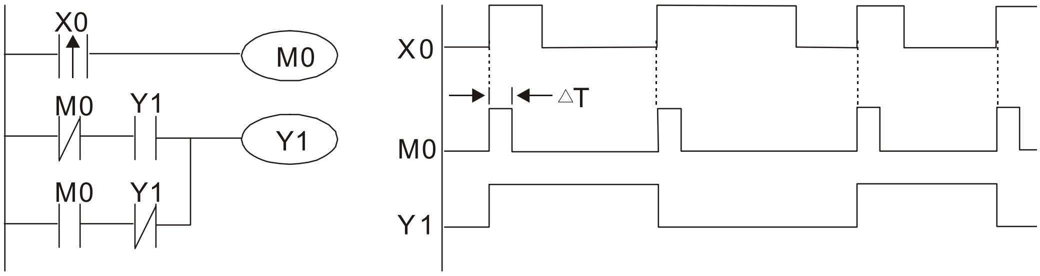
Example 8: Flashing circuit

The following figure shows an oscillating circuit of a type commonly used to cause an indicator light to flash or buzzers to buzz. It uses two timers to control the ON and OFF time of Y1 coil. Here n1, n2 are the timing set values of T1 and T2, and T is the clock cycle of the timer.



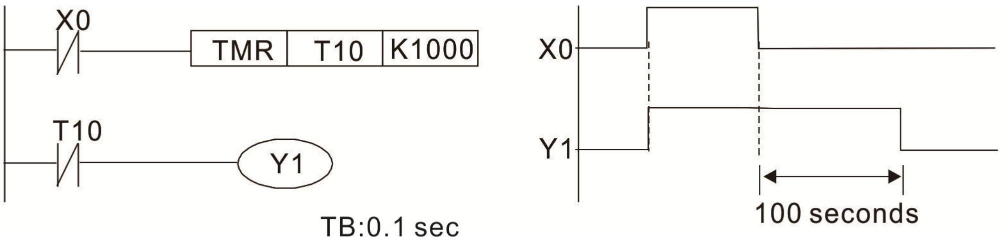
Example 9: Triggering circuit

In the figure below, a command consisting of the differential of the rising edge of X0 causes coil M0 to generate a single pulse for ΔT (length of one scanning cycle), and coil Y1 is electrified during this scanning cycle. Coil M0 loses power during the next scanning cycle, N.C. contact M0 and N.C. contact Y1 are both closed. This causes coil Y1 to stay in an electrified state until there is another rising edge in input X0, which again causes the electrification of coil M0 and the start of another scanning cycle, while also causing coil Y1 to lose power, etc. The sequence of these actions can be seen in the figure below. This type of circuit is commonly used to enable one input to perform two actions in alternation. It can be seen from the time sequence in the figure below that when input X0 is a square wave signal with a period of T, the output of coil Y1 will be a square wave signal with a period of 2T.

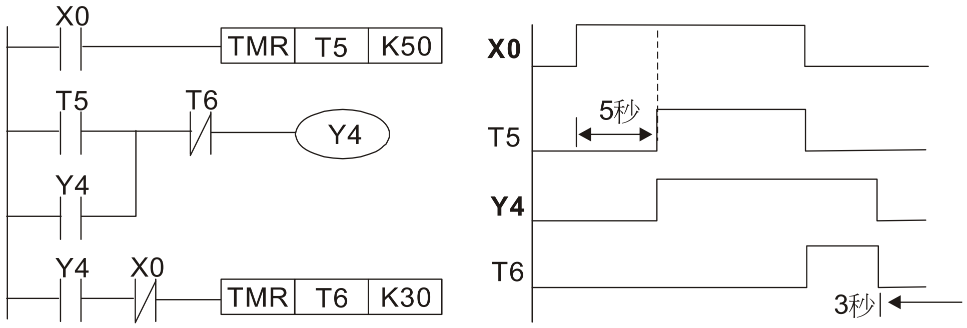


Example 10: Delay circuit

When input X0 is ON, the timer T10 is in no power status because the corresponding N.C. contact is OFF, and the output coil Y1 is electrified. T10 receives power and begins timing only after input X0 is OFF, and the output coil Y1 is delayed for 100 sec. (K1000 × 0.1 sec. = 100 sec.) before losing power; refer to the sequence of actions in the figure below.

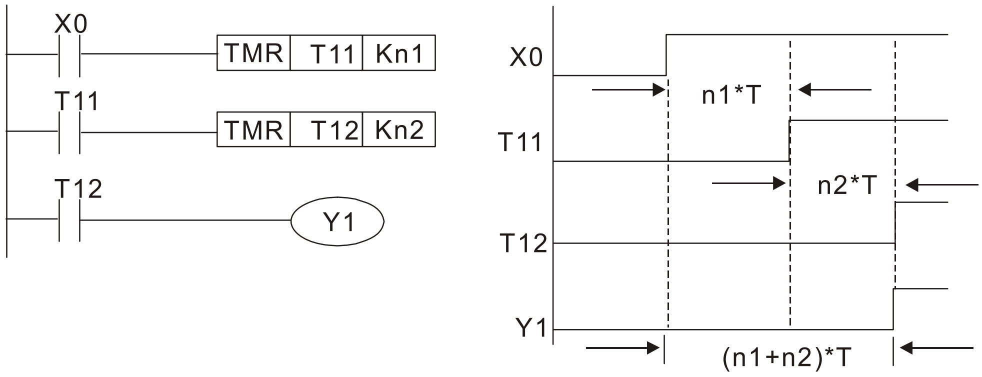


Example 11: The open / close delay circuit is composed of two timers; output Y4 has a delay whether the input X0 is ON or OFF.



Example 12: Extended timing circuit

In the circuit in the figure on the left, the total delay time from the moment input X0 closes to the time output Y1 is electrified is (n1 + n2) × T, where T is the clock cycle. Timers: T11, T12; clock cycle: T.



16-5 Various PLC device functions

Item	Specifications	Notes
Algorithmic control method	Program stored internally, alternating back-and-forth scanning method	
Input / output control method	When it starts again after ending (after execution to the END command), the input/output has an immediate refresh command	
Algorithmic processing speed	Basic commands (several µs);	Applications command (1-several tens of µs)
Programming language	Command + ladder diagram	
Program capacity	10000 steps	
Input / output terminal	Input (X): 10, output (Y): 3	This number of contacts constitutes CP2000 input / output contacts; other devices have different correspondences

Type	Device	Item		Range		Function
Relay bit form	X	External input relay		X0–X17, 16 points, octal number	Total 32 points	Corresponds to external input point
	Y	External output relay		Y0–Y17, 16 points, octal number		Corresponds to external output point
	M	Auxiliary Relay	General Use	M0–M799, 800 points	Total 880 points	Contact can switch ON / OFF within the program
			Special purpose	M1000–M1079, 80 points		
	T	Timer	100ms timer	T0–T159, 160 points	Total 160 points	Timers referred to by the TMR command; contact of the T with the same number will go On when the time is reached
	C	Counter	16-bit counter, general use	C0–C79, 80 points	Total 80 points	Counter referred to by the CNT command; contact of the C with the same number will go ON when the count is reached
Register word data	T	Current timer value		T0–T159, 160 points		The contact will be ON when the time is reached
	C	Current counter value		C0–C79, 16-bit counter 80 points		The counter contact will come ON when the count is reached
	D	Data Register	Used to maintain power OFF	D0–D399, 400 points	Total 1400 points	Used as data storage memory area
			Special purpose	D1000–D1199, 200 points D2000–D2799, 800 points		
Constant	K	Decimal	Single-byte	Setting Range: K-32,768–K32,767		
			Double-byte	Setting Range: K-2,147,483,648–K2,147,483,647		
	H	Hexadecimal	Single-byte	Setting Range:H0000–HFFFF		
			Double-byte	Setting Range: H00000000–HFFFFFFFF		
Serial communications port (program write/read)				RS-485/keypad port		
Input/output				Built-in three analog inputs and two analog outputs		
Function expansion module			Optional Accessories	EMC-D42A; EMC-R6AA; EMC-D611A		
Communication Expansion Module			Optional Accessories	EMC-COP01 (CANopen)		

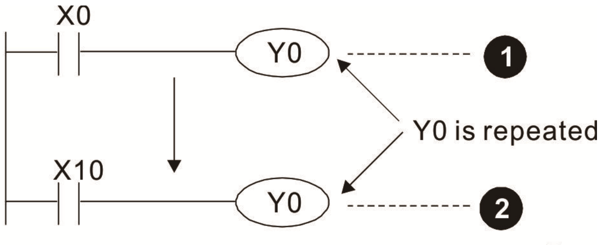
16-5-1 Introduction to device functions

Input/output contact functions

Input contact X functions: Input contact X is connected with an input device, and reads input signals entering the PLC. The number of times that contact a or b of input contact X used in the program is not subject to restrictions. The ON / OFF state of input contact X will change as the input device switches ON and OFF; a peripheral device (WPLSoft) cannot be used to force contact X On or Off.

Output contact Y functions

The job of output contact Y is to send an ON / OFF signal to drive the load connected with output contact Y. Output contacts consist of two types: relays and transistors. While number of times that contact a or b of each output contact Y used in the program is not subject to restrictions, it is recommended that the number of output coil Y be used only once in a program, otherwise the right to determine the output state when the PLC performs program scanning will be assigned to the program's final output Y circuit.



The output of Y0 will be decided by circuit ❷ , i.e. decided by On/Off of X10.

Numerical value, constant [K]/ [H]

Constant	Single-byte	K	Decimal	K-32,768–K32,767
	Double-byte			K-2,147,483,648–K2,147,483,647
	Single-byte	H	Hexadecimal	H0000–HFFFF
	Double-byte			H00000000–HFFFFFFFF

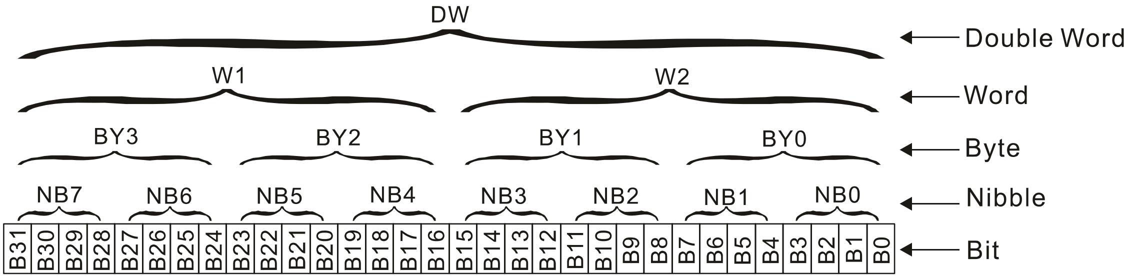
The PLC can use five types of numerical values to implement calculations based on its control tasks; the following is an explanation of the missions and functions of different numerical values.

Binary Number, BIN

The PLC's numerical operations and memory employ binary numbers. Binary nibbles and relevant terms are explained as follows:

bit	bits are the fundamental units of binary values, and have a state of either 1 or 0
Nibble	Comprised of a series of 4 bits (such as b3–b0); can be used to express a one-nibble decimal number 0–9 or hexadecimal number: 0–F.
Byte	Comprised of a series of two nibbles (i.e. 8 bits, b7–b0); can express a hexadecimal number: 00–FF.
Word	Comprised of a series of two bytes (i.e. 16 bits, b15–b0); can express a hexadecimal number with four nibbles: 0000–FFFF.
Double Word	Comprised of a series of two words (i.e. 32 bits, b31–b0); can express a hexadecimal number with eight nibbles: 00000000–FFFFFFFF

Relationship between bits, digits, nibbles, words, and double words in a binary system (see figure below):



Octal Number, OCT

The external input and output terminals of a DVP-PLC are numbered using octal numbers

Example: External input: X0–X7, X10–X17… (Device number table);

External output: Y0–Y7, Y10–Y17… (Device number table)

Decimal Number, DEC

Decimal numbers are used for the following purposes in a PLC system:

☑ The setting values of timer T or counter C, such as TMR C0 K50. (K constant)
☑ The numbers of devices including M, T, C, or D, such as M10 or T30. (device number)
☑ Used as an operand in an application command, such as MOV K123 D0. (K constant)

Binary Code Decimal, BCD

Uses one nibble or 4 bits to express the data in a decimal number; a series of 16 bits can therefore express a decimal number with 4 nibbles. Chiefly used to read the input value of a fingerwheel numerical switch input or output a numerical value to a seven-segment display driver.

Hexadecimal Number, HEX

Applications of hexadecimal numbers in a PLC system: Used as operands in application commands, such as MOV H1A2B D0. (H constant)

Constant K

Decimal numbers are usually prefixed with a "K" in a PLC system, such as K100. This indicates that it is a decimal number with a numerical value of 100.

Exceptions: K can be combined with bit device X, Y, M, or S to produce data in the form of a nibble, byte, word, or double word, such as in the case of K2Y10 or K4M100. Here K1 represents a 4-bit combination, and K2-K4 variously represent 8-, 12-, and 16-bit combinations.

Constant H

Hexadecimal numbers are usually prefixed with the letter "H" in a PLC system, such as in the case of H100, which indicates a hexadecimal number with a numerical value of 100.

Functions of auxiliary relays

Like an output relay Y, an auxiliary relay M has an output coil and contacts a and b, and the number of times they can be used in a program is unrestricted. Users can use an auxiliary relay M to configure the control circuit, but cannot use it to directly drive an external load. Auxiliary relays have the following two types of characteristics:

Ordinary auxiliary relays: Ordinary auxiliary relays will all revert to the OFF state if a power outage occurs while the PLC is running, and will remain in the OFF state if power is again turned down.

Special purpose auxiliary relays: Each special purpose auxiliary relay has its own specific use. Do not use any undefined special purpose auxiliary relays.

Timer functions

Timers take 100 ms as their timing units. When the timing method is an upper time limit, when the current timer value = set value, power will be sent to the output coil. Timer setting values consist of decimal K values, and the data register D can also serve as a setting value.

Actual timer setting time = timing units × set value

Counter features

Item	16-bit counter
Type	General Type
CT Direction:	Score:
Setting	0–32,767
Designation of set value	Constant K or data register D
Change in current value	When the count reaches the set value, there is no longer a count
Output contact	When the count reaches the set value, the contact comes On and stays On
Reset	The current value reverts to 0 when an RST command is executed, and the contact reverts to Off
Contact actuation	All are actuated after the end of scanning

Counter functions

When a counter's counting pulse input signal goes OFF→ON, if the counter's current value is equal to the set value, the output coil will become ON. The setting value will be a decimal K values, and the data register D can also serve as a setting value.

16-bit counter C0–C79:

☑ 16-bit counter setting range: K0–K32,767. (when K0 and K1 are identical, the output contact will immediately be ON during the first count.)

☑ The current counter value will be cleared from an ordinary counter when power is shut off to the PLC.

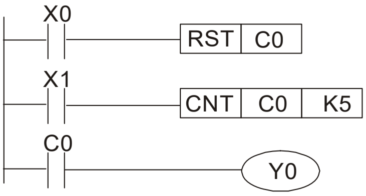
☑ If the MOV command or WPLSoft is used to transmit a value greater than the set value to the C0 current value register, when the next X1 goes from OFF→ON, the C0 counter contact will change to On, and the current value will change to the set value.

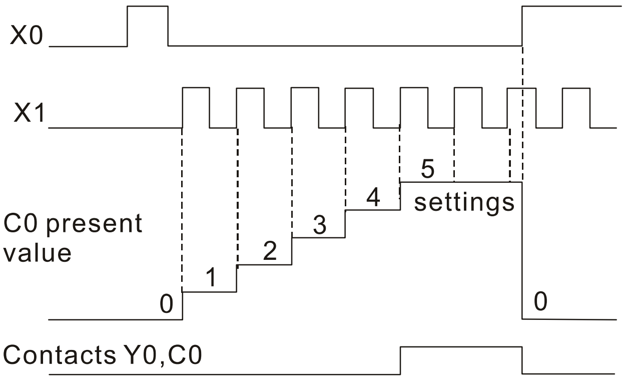
☑ A counter's setting value may be directly set using a constant K or indirectly set using the value in register D (not including special data registers D1000–D1199 or D2000–D2799).

☑ If the set value employs a constant K, it may only be a positive number; the set value may be either a positive or a negative number if the value in data register D is used. The current counter value will change from 32,767 to -32,768 as the count continues to accumulate.

Example

```
 LD      X0
RST      C0
 LD      X1
CNT    C0  K5
 LD      C0
OUT      Y0
```





1. When X0 = ON and the RST command is executed, the current value of C0 will revert to 0, and the output contact will revert to OFF.
2. When X1 changes from OFF→ON, the current value of the counter will execute an increase (add one).
3. When the count of counter C0 reaches the set value K5, the contact C0 will come ON, and the current value of C0 = set value = K5. Afterwards, signal C0 triggered by X1 cannot be received, and the current value of C0 will remain K5.

16-5-2 Introduction to special relay functions (special M)

R/W items: RO: read only function; RW: read and write function

Special M	Description of Function	R/W *
M1000	Operates monitor N.O. contact (contact a). N.O. while RUN, contact a. This contact is ON while in the RUN state.	RO
M1001	Operates monitor N.C. contact (contact b). N.C. while RUN, contact b. This contact is OFF while in the RUN state.	RO
M1002	Initiates a forward (the instant RUN is ON) pulse. Initial pulse, contact a. Produces a forward pulse the moment RUN begins; its width = scan cycle	RO
M1003	Initiates a reverse (the instant RUN is OFF) pulse. Initial pulse, contact a. Produces a reverse pulse the moment RUN ends; the pulse width = scan cycle	RO
M1004	Reserved	RO
M1005	Driver malfunction instructions	RO
M1006	Converter has no output	RO
M1007	Driver direction FWD(0)/REV(1)	RO
M1008 | M1010	--	--
M1011	10 ms clock pulse, 5ms ON / 5ms OFF	RO
M1012	100 ms clock pulse, 50ms On / 50ms Off	RO
M1013	1 sec. clock pulse, 0.5s On / 0.5s Off	RO
M1014	1 min. clock pulse, 30s On / 30s Off	RO
M1015	Frequency attained (when used together with M1025)	RO
M1016	Parameter read/write error	RO
M1017	Parameter write successful	RO
M1018	--	--
M1019	Motor drive warning indicator	RO
M1020	Zero flag	RO
M1021	Borrow flag	RO
M1022	Carry flag	RO
M1023	Divisor is 0	RO
M1024	--	--
M1025	Driver frequency = set frequency (ON) Driver frequency = 0(OFF)	RW
M1026	Driver operating direction FWD(OFF) / REV(ON)	RW
M1027	Driver Reset	RW
M1028	--	--
M1029	--	--
M1030	--	--
M1031	Compulsory setting of the current PID integral value equal to D1019 (0 change, 1 valid)	RW
M1032	Compulsory definition of FREQ command after PID control	RW
M1033	--	--
M1034	Initiates CANopen real-time control	RW
M1035	Initiates internal communications control	RW
M1036	Ignore calendar error	RW
M1037	--	--
M1038	--	--
M1039	--	--
M1040	Excitation (Servo ON)	RW
M1041	--	--
M1042	Quick stop	RW
M1043	--	--
M1044	Pause (Halt)	RW

Special M	Description of Function	R/W *
M1045 | M1047	--	--
M1048	--	--
M1049	--	--
M1050	--	--
M1051	--	--
M1052	Lock frequency (lock, frequency locked at the current operating frequency)	RW
M1053	--	--
M1054	--	--
M1055	--	--
M1056	Excitation ready (Servo ON Ready)	RO
M1057	--	--
M1058	On Quick Stopping	RO
M1059	CANopen Master setting complete	RO
M1060	CANopen Currently initializing slave station	RO
M1061	CANopen Slave station initialization failure	RO
M1062	--	--
M1063	--	--
M1064	--	--
M1065	Read/write CANOpen data time out	RO
M1066	Read/write CANopen data complete	RO
M1067	Read/write CANopen data successful	RO
M1068	Calendar calculation error	RO
M1069	--	--
M1070	--	--
M1071	--	--
M1072 | M1075	--	--
M1076	Calendar time error or refresh time out	RO
M1077	485 Read/write complete	RO
M1078	485 Read-write error	RO
M1079	485 Communications time out	RO
M1090	OFF (refer to parameter descriptions for Pr.00-29)	RO
M1091	HAND (refer to parameter descriptions for Pr.00-29)	RO
M1092	AUTO (refer to parameter descriptions for Pr.00-29)	RO
M1100	LOCAL (refer to parameter descriptions for Pr.00-29)	RO
M1101	REMOTE (refer to parameter descriptions for Pr.00-29)	RO
M1168	SMOV BCD and BIN mode switch	RW
M1260	PLC PID1 Enable	RW
M1262	PLC PID1 Positive integral value limit	RW
M1270	PLC PID2 Enable	RW
M1272	PLC PID2 Positive integral value limit	RW

16-5-3 Introduction to special register functions (special D)

Special D	Description of Function	R/W *
D1000	--	--
D1001	Device system program version	RO
D1002	Program capacity	RO
D1003	Total program memory content	RO
D1004 | D1009	--	--
D1010	Current scan time (units: 0.1 ms)	RO
D1011	Minimum scan time (units: 0.1 ms)	RO
D1012	Maximum scan time (units: 0.1 ms)	RO
D1013 | D1017	--	--
D1018	Current integral value	RO
D1019	Compulsory setting of PID I integral	RW
D1020	Output frequency (0.00–600.00Hz)	RO
D1021	Output current (####.#A)	RO
D1022	AI AO DI DO Expansion card number 0: No extension card 4: AC input card (6 in) (EMC-D611A) 5: Digital I/O Card (4 in 2 out) (EMC-D42A) 6: Relay card(6 out) (EMC-R6AA) 11: Analog I/O card (2 in 2 out) (EMC-A22A)	RO
D1023	Communication expansion card number 0: No extension card 1: DeviceNet Slave (CMC-DN01) 2: Profibus-DP Slave (CMC-PD01) 3: CANopen Slave (EMC-COP01) 4: Modbus-TCP Slave 5: EtherNet/IP Slave (CMC-EIP01) 12: PROFINET Slave (CMC-PN01)	RO
D1024 | D1026	--	--
D1027	PID calculation frequency command (frequency command after PID calculation)	RO
D1028	AVI1value (0.00–100.00%)	RO
D1029	ACI value (0.0–100.00%)	RO
D1030	AVI2 value (0.00–100.00%)	RO
D1031	C series: extension card AI10 (0.0–100.0%)	RO
D1032	C series: extension card AI11 (0.0–100.0%)	RO
D1033 | D1035	--	--
D1036	Servo fault bit	RO
D1037	Driver output frequency	RO
D1038	DC bus voltage	RO
D1039	Output voltage	RO
D1040	Analog output value AFM1 (-100.00–100.00%)	RW
D1041	C series: extension card AO10 (0.0–100.0%)	RW
D1042	C series: extension card AO11 (0.0–100.0%)	RW
D1043	Can be user-defined (will be displayed on panel when Pr.00-04 is set as 28; display method is C xxx)	RW
D1044	--	-
D1045	Analog output value AFM2 (-100.00–100.00%)	RW

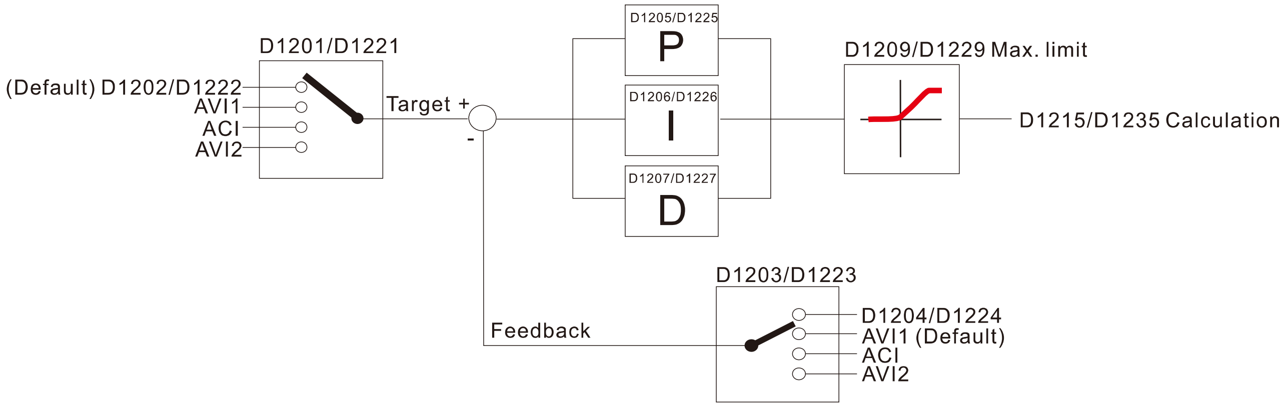
Special D	Description of Function	R/W *
D1046 | D1049	--	--
D1050	Actual Operation Mode 0: Speed	RO
D1051	--	--
D1052	--	--
D1053	--	--
D1054	--	--
D1055	--	--
D1056	--	--
D1057	--	--
D1058	--	--
D1059	--	--
D1060	Operation Mode setting 0: Speed	RW
D1061	485 COM1 communications time out time (ms)	RW
D1062	Torque command (torque limit in speed mode)	RW
D1063	Year (Western calendar) (display range 2000-2099) (must use KPC-CC01)	RO
D1064	Week (display range 1-7) (must use KPC-CC01)	RO
D1065	Month (display range 1-12) (must use KPC-CC01)	RO
D1066	Day (display range 1-31) (must use KPC-CC01)	RO
D1067	Hour (display range 0-23) (must use KPC-CC01)	RO
D1068	Minute (display range 0-59) (must use KPC-CC01)	RO
D1069	Second (display range 0-59) (must use KPC-CC01)	RO
D1100	Target frequency	RO
D1101	Target frequency (must be operating)	RO
D1102	Reference frequency	RO
D1103	--	--
D1104	--	--
D1105	--	--
D1106	--	--
D1107	π(Pi) Low word	RO
D1108	π(Pi) High word	RO
D1109	Random number	RO
D1110	Internal node communications number (set number of slave stations to be controlled)	RW
D1111	--	--
D1112	--	--
D1113	--	--
D1114	Numbering of the operating motors: 1: Motor 1 2: Motor 2	RO
D1115	Internal node synchronizing cycle (ms)	RO
D1116	Internal node error (bit0 = Node 0, bit1 = Node 1,…bit7 = Node 7)	RO
D1117	Internal node online correspondence (bit0 = Node 0, bit1 = Node 1,…bit7 = Node 7)	RO
D1118	--	--
D1119	--	--
D1120	Internal node 0 control command	RW
D1121	Internal node 0 mode	RW
D1122	Internal node 0 reference command L	RW
D1123	Internal node 0 reference command H	RW
D1124	--	--
D1125	--	--

Special D	Description of Function	R/W *
D1126	Internal node 0 status	RO
D1127	Internal node 0 reference status L	RO
D1128	Internal node 0 reference status H	RO
D1129	--	--
D1130	Internal node 1 control command	RW
D1131	Internal node 1 mode	RW
D1132	Internal node 1 reference command L	RW
D1133	Internal node 1 reference command H	RW
D1134	--	--
D1135	--	--
D1136	Internal node 1 status	RO
D1137	Internal node 1 reference status L	RO
D1138	Internal node 1 reference status H	RO
D1139	--	--
D1140	Internal node 2 control command	RW
D1141	Internal node 2 mode	RW
D1142	Internal node 2 reference command L	RW
D1143	Internal node 2 reference command H	RW
D1144	--	--
D1145	--	--
D1146	Internal node 2 status	RO
D1147	Internal node 2 reference status L	RO
D1148	Internal node 2 reference status H	RO
D1149	--	--
D1150	Internal node 3 control command	RW
D1151	Internal node 3 mode	RW
D1152	Internal node 3 reference command L	RW
D1153	Internal node 3 reference command H	RW
D1154	--	--
D1155	--	--
D1156	Internal node 3 status	RO
D1157	Internal node 3 reference status L	RO
D1158	Internal node 3 reference status H	RO
D1159	--	--
D1160	Internal node 4 control command	RW
D1161	Internal node 4 mode	RW
D1162	Internal node 4 reference command L	RW
D1163	Internal node 4 reference command H	RW
D1164	--	--
D1165	--	--
D1166	Internal node 4 status	RO
D1167	Internal node 4 reference status L	RO
D1168	Internal node 4 reference status H	RO
D1169	--	--
D1170	Internal node 5 control command	RW
D1171	Internal node 5 mode	RW
D1172	Internal node 5 reference command L	RW
D1173	Internal node 5 reference command H	RW
D1174	--	RW
D1175	--	--
D1176	Internal node 5 status	--
D1177	Internal node 5 reference status L	RO
D1178	Internal node 5 reference status H	RO
D1179	--	--
D1180	Internal node 6 control command	RW

Special D	Description of Function	R/W *
D1181	Internal node 6 mode	RW
D1182	Internal node 6 reference command L	RW
D1183	Internal node 6 reference command H	RW
D1184	--	--
D1185	--	--
D1186	Internal node 6 status	RO
D1187	Internal node 6 reference status L	RO
D1188	Internal node 6 reference status H	RO
D1189	--	--
D1190	Internal node 7 control command	RW
D1191	Internal node 7 mode	RW
D1192	Internal node 7 reference command L	RW
D1193	Internal node 7 reference command H	RW
D1194	--	--
D1195	--	--
D1196	Internal node 7 status	RO
D1197	Internal node 7 reference status L	RO
D1198	Internal node 7 reference status H	RO
D1199	--	--
D1560	Motor drive warning code	RO

Special D	Description of Function	Default	R/W*
D1200	PID1 mode: 0: Basic mode	0	RW
D1201	PID1 target selection: 0: Refer to D1202 1: AVI1 2: ACI 3: AVI2	0	RW
D1202	PID1 target value (0.00%–100.00%)	5000	RW
D1203	PID1 feedback selection 0: Refer to D1204 1: AVI1 2: ACI 3: AVI2	1	RW
D1204	PID1 feedback value (0.00%–100.00%)	0	RW
D1205	PID1 P value (decimal point 2)	10	RW
D1206	PID1 I value (decimal point 2)	1000	RW
D1207	PID1 D value (decimal point 2)	0	RW
D1209	Max. limit of PID1	10000	RW
D1215	Counting value of PID1 (decimal point 2)	0	RO
D1220	PID2 mode: 0: Basic mode	0	RW
D1221	PID2 target selection: 0: Refer to D1202 1: AVI1 2: ACI 3: AVI2	0	RW
D1222	PID2 target value (0.00%–100.00%)	5000	RW
D1223	PID2 feedback selection 0: Refer to D1204 1: AVI1 2: ACI 3: AVI2	1	RW

Special D	Description of Function	Default	R/W*
D1224	PID2 feedback value (0.00%–100.00%)	0	RW
D1225	PID1 P value (decimal point 2)	10	RW
D1226	PID2 I value (decimal point 2)	1000	RW
D1227	PID2 D value (decimal point 2)	0	RW
D1229	Max. limit of PID2	10000	RW
D1235	Counting value of PID2 (decimal point 2)	0	RO



The following is CANopen Master's special D (can be written in only with PLC in Stop state)

※ CP2000 does not have torque and position mode. As CANopen master, however, CP2000 can issue torque and position commands to CANopen slaves.

n=0–7

Special D	Description of Function	PDO Map	Power off Memory	Default:	R/W
D1070	Channel opened by CANopen initialization (bit0=Machine code0 …….)	NO	NO	0	R
D1071	Error channel occurring in CANopen initialization process (bit0=Machine code0 …….)	NO	NO	0	R
D1072	Reserved	-	-		-
D1073	CANopen break channel (bit0=Machine code0 …….)	NO	NO		R
D1074	Error code of master error 0: No error 1: Slave station setting error 2: Synchronizing cycle setting error (too small)	NO	NO	0	R
D1075	Reserved	-	-		-
D1076	SDO error message (main index value)	NO	NO		R
D1077	SDO error message (secondary index value)	NO	NO		R
D1078	SDO error message (error code)	NO	NO		R
D1079	SDO error message (error code)	NO	NO		R
D1080	Reserved	-	-		-
D1081 | D1086	Reserved	-	-		-
D1087 | D1089	Reserved	-	-		-
D1090	Synchronizing cycle setting	NO	YES	4	RW
D1091	Sets slave station On or Off (bit0–bit7 correspond to slave stations number 0–7)	NO	YES	FFFFH	RW
D1092	Delay before start of initialization	NO	YES	0	RW
D1093	Break time detection	NO	YES	1000ms	RW
D1094	Break number detection	NO	YES	3	RW
D1095 | D1096	Reserved	-	-		-

Special D	Description of Function	PDO Map	Power off Memory	Default:	R/W
D1097	Corresponding real-time transmission type (PDO) Setting range: 1–240	NO	YES	1	RW
D1098	Corresponding real-time receiving type (PDO) Setting range: 1–240	NO	YES	1	RW
D1099	Initialization completion delay time Setting range: 1 to 60000 sec	NO	YES	15 sec.	RW
D2000+100*n	Station number n of slave station Setting range: 0–127 0: No CANopen function	NO	YES	0	RW

The CP2000 supports 8 slave stations under the CANopen protocol; each slave station occupies 100 special D locations; stations are numbered 1–8, total of 8 stations.

Explanation of slave station number

Slave station no. 1	D2000	Node ID
	D2001	Slave station no. 1 torque restrictions
	|	|
	D2099	Address 4(H) corresponding to receiving channel 4
Slave station no. 2	D2100	Node ID
	D2101	Slave station no. 2 torque restrictions
	|	|
	D2199	Address 4(H) corresponding to receiving channel 4
Slave station no. 3	D2200	Node ID
	D2201	Slave station no. 3 torque restrictions
	|	|
	D2299	Address 4(H) corresponding to receiving channel 4
	⇩	
Slave station no. 8	D2700	Node ID
	D2701	Slave station no. 8 torque restrictions
	|	|
	D2799	Address 4(H) corresponding to receiving channel 4

1. The range of n is 0–7
2. ●Indicates PDOTX, ▲Indicates PDORX; unmarked special D can be refreshed using the CANFLS command

Special D	Description of Function	Default:	R/W
D2000+100*n	Station number n of slave station Setting range: 0–127 0: No CANopen function	0	RW
D2002+100*n	Manufacturer code of slave station number n (L)	0	R
D2003+100*n	Manufacturer code of slave station number n (H)	0	R
D2004+100*n	Manufacturer's product code of slave station number n (L)	0	R
D2005+100*n	Manufacturer's product code of slave station number n (H)	0	R

Basic definitions

Special D	Description of Function	Default:	PDO Mapping	PDO Default:				R/W
				1	2	3	4	
D2006+100*n	Communications break handling method of slave station number n	0	6007H-0010H					RW
D2007+100*n	Error code of slave station number n error	0	603FH-0010H					R
D2008+100*n	Control word of slave station number n	0	6040H-0010H	●		●	●	RW
D2009+100*n	Status word of slave station number n	0	6041H-0010H	▲		▲	▲	R
D2010+100*n	Control mode of slave station number n	2	6060H-0008H					RW
D2011+100*n	Actual mode of slave station number n	2	6061H-0008H					R

Velocity Control

Slave station number n=0–7

Special D	Description of Function	Default:	PDO Mapping	PDO Default:				R/W
				1	2	3	4	
D2001+100*n	Torque restriction on slave station number n	0	6072H-0010H					RW
D2012+100*n	Target speed of slave station number n	0	6042H-0010H	●				RW
D2013+100*n	Actual speed of slave station number n	0	6043H-0010H	▲				R
D2014+100*n	Error speed of slave station number n	0	6044H-0010H					R
D2015+100*n	Acceleration time of slave station number n	1000	604FH-0020H					R
D2016+100*n	Deceleration time of slave station number n	1000	6050H-0020H					RW

20XXH correspondences: MI / MO / AI / AO

Slave station number n=0–7

Special D	Description of Function	Default:	PDO Mapping	PDO Default:				R/W
				1	2	3	4	
D2026+100*n	MI status of slave station number n	0	2026H-0110H		▲			RW
D2027+100*n	MO setting of slave station number n	0	2026H-4110H		●			RW
D2028+100*n	AI1 status of slave station number n	0	2026H-6110H		▲			RW
D2029+100*n	AI2 status of slave station number n	0	2026H-6210H		▲			RW
D2030+100*n	AI3 status of slave station number n	0	2026H-6310H		▲			RW
D2031+100*n	AO1 status of slave station number n	0	2026H-A110H		●			RW
D2032+100*n	AO2 status of slave station number n	0	2026H-A210H		●			RW
D2033+100*n	AO3 status of slave station number n	0	2026H-A310H		●			RW

PDO reflection length setting:

Special D	Description of Function	Default:	R/W
D2034+100*n	Real-time transmission setting of slave station number n	000AH	RW
D2067+100*n	Real-time reception setting of slave station number n	0000H	RW

16-5-4 PLC Communication address

Device	Range	Type	Address (Hex)
X	00–37 (Octal)	bit	0400–041F
Y	00–37 (Octal)	bit	0500–051F
T	00–159	bit/word	0600–069F
M	000–799	bit	0800–0B1F
M	1000–1079	bit	0BE8–0C37
C	0–79	bit/word	0E00–0E47
D	00–399	word	1000–118F
D	1000–1198	word	13E8–144B
D	2000–2799	word	17D0–1AEF

Command code that can be used

Function Code	Description of Function	Function target
01	Coil status read	Y, M, T, C
02	Input status read	X,Y,M,T,C
03	Read single unit of data	T,C,D
05	Compulsory single coil status change	Y,M,T,C
06	Write single unit of data	T,C,D
0F	Compulsory multiple coil status change	Y,M,T,C
10	Write multiple units of data	T,C,D

NOTE

When PLC functions have been activated, the CP2000 can match PLC and driver parameters; this method employs different addresses, drivers (default station number is 1, PLC sets station number as 2)

16-6 Introduction to the Command Window

16-6-1 Overview of basic commands

Ordinary commands

Command code	Function	OPERAND	Execution speed (us)
LD	Load contact a	X、Y、M、T、C	0.8
LDI	Load contact b	X、Y、M、T、C	0.8
AND	Connect contact a in series	X、Y、M、T、C	0.8
ANI	Connect contact b in series	X、Y、M、T、C	0.8
OR	Connect contact a in parallel	X、Y、M、T、C	0.8
ORI	Connect contact b in parallel	X、Y、M、T、C	0.8
ANB	Series circuit block	N/A	0.3
ORB	Parallel circuit block	N/A	0.3
MPS	Save to stack	N/A	0.3
MRD	Stack read (pointer does not change)	N/A	0.3
MPP	Read stack	N/A	0.3

Output command

Command code	Function	OPERAND	Execution speed (us)
OUT	Drive coil	Y、M	1
SET	Action continues (ON)	Y、M	1
RST	Clear contact or register	Y、M、T、C、D	1.2

Timer, counter

Command code	Function	OPERAND	Execution speed (us)
TMR	16-bit timer	T-K or T-D commands	1.1
CNT	16-bit counter	C-K or C-D (16-bit)	0.5

Main control command

Command code	Function	OPERAND	Execution speed (us)
MC	Common series contact connection	N0~N7	0.4
MCR	Common series contact release	N0~N7	0.4

Contact rising edge/falling edge detection command

Command code	Function	OPERAND	Execution speed (us)
LDP	Start of forward edge detection action	X、Y、M、T、C	1.1
LDF	Start of reverse edge detection action	X、Y、M、T、C	1.1
ANDP	Forward edge detection series connection	X、Y、M、T、C	1.1
ANDF	Reverse edge detection series connection	X、Y、M、T、C	1.1
ORP	Forward edge detection parallel connection	X、Y、M、T、C	1.1
ORF	Reverse edge detection parallel connection	X、Y、M、T、C	1.1

Upper/lower differential output commands

Command code	Function	OPERAND	Execution speed (us)
PLS	Upper differential output	Y、M	1.2
PLF	Lower differential output	Y、M	1.2

Stop command

Command code	Function	OPERAND	Execution speed (us)
END	Program conclusion	N/A	0.2

Other commands

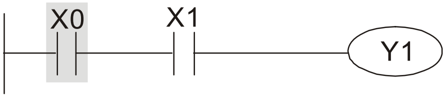
Command code	Function	OPERAND	Execution speed (us)
NOP	No action	N/A	0.2
INV	Inverse of operation results	N/A	0.2
P	Index	P	0.3

16-6-2 Detailed explanation of basic commands

Command	Function					
LD	Load contact a					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation The LD command is used for contact a starting at the left busbar or contact a starting at a contact circuit block; its function is to save current content and save the acquired contact status in the cumulative register.

Example Ladder diagram:

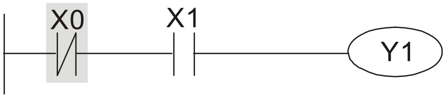


Command code:		Description:
LD	**X0**	Load Contact a of X0
AND	X1	Create series connection to contact a of X1
OUT	Y1	Drive Y1 coil

Command	Function					
LDI	Load contact b					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation The LDI command is used for contact b starting at the left busbar or contact b starting at a contact circuit block; its function is to save current content and save the acquired contact status in the cumulative register.

Example Ladder diagram:



Command code:		Description:
LDI	**X0**	Load Contact b of X0
AND	X1	Create series connection to contact a of X1
OUT	Y1	Drive Y1 coil

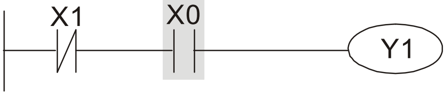
Command	Function					
AND	Connect contact a in series					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The AND command is used to create a series connection to contact a; first reads current status of the designated series contact and logical operation results before contact in order to perform "AND" operation; saves results in cumulative register.

Example

Ladder diagram:



Command code:		Description:
LDI	X1	Load Contact b of X1
AND	**X0**	Create series connection to contact a of X0
OUT	Y1	Drive Y1 coil

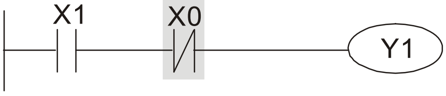
Command	Function					
ANI	Connect contact b in series					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The ANI command is used to create a series connection to contact b; its function is to first read current status of the designated series contact and logical operation results before contact in order to perform "AND" operation; saves results in cumulative register.

Example

Ladder diagram:



Command code:		Description:
LD	X1	Load Contact a of X1
ANI	**X0**	Create series connection to contact b of X0
OUT	Y1	Drive Y1 coil

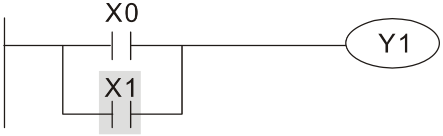
Command	Function					
OR	Connect contact a in parallel					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The OR command is used to establish a parallel connection to contact a; its function is to first read current status of the designated series contact and logical operation results before contact in order to perform "OR" operation; saves results in cumulative register.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
OR	**X1**	Create series connection to contact a of X1
OUT	Y1	Drive Y1 coil

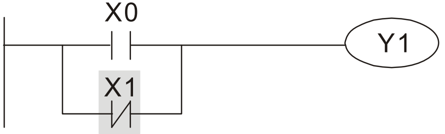
Command	Function					
ORI	Connect contact b in parallel					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The ORI command is used to establish a parallel connection to contact b; its function is to first read current status of the designated series contact and logical operation results before contact in order to perform "OR" operation; saves results in cumulative register.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
ORI	**X1**	Create series connection to contact b of X1
OUT	Y1	Drive Y1 coil

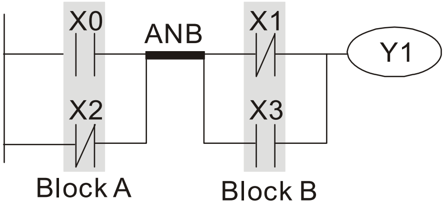
Command	Function
ANB	Series circuit block
Operand	N/A

Explanation

ANB performs an "AND" operation on the previous saved logic results and the current cumulative register content.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
ORI	X2	Establish parallel connection to contact b of X2
LDI	X1	Load Contact b of X1
OR	X3	Establish parallel connection to contact a of X3
ANB		Series circuit block
OUT	Y1	Drive Y1 coil

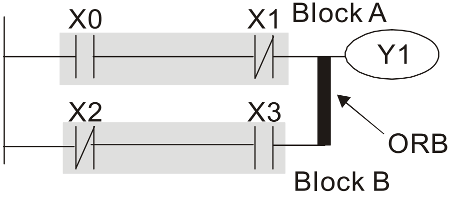
Command	Function
ORB	Parallel circuit block
Operand	N/A

Explanation

ORB performs an "OR" operation on the previous saved logic results and the current cumulative register content.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
ANI	X1	Establish parallel connection to contact b of X1
LDI	X2	Load Contact b of X2
AND	X3	Establish parallel connection to contact a of X3
ORB		Parallel circuit block
OUT	Y1	Drive Y1 coil

Command	Function
MPS	Save to stack
Operand	N/A

Explanation Save current content of cumulative register to the stack. (Add one to stack pointer)

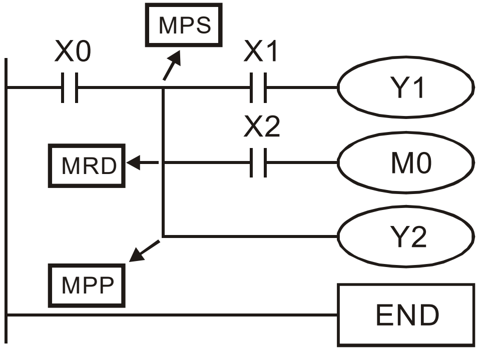
Command	Function
MRD	Read stack (pointer does not change)
Operand	N/A

Explanation Reads stack content and saves to cumulative register. (Stack pointer does not change)

Command	Function
MPP	Read stack
Operand	N/A

Explanation Retrieves result of previously-save logical operation from the stack, and saves to cumulative register. (Subtract one from stack pointer)

Example Ladder diagram:



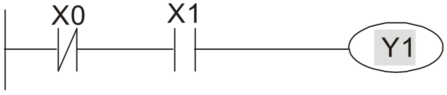
Command code:		Description:
LD	X0	Load Contact a of X0
MPS		Save to stack
AND	X1	Create series connection to contact a of X1
OUT	Y1	Drive Y1 coil
MRD		Read stack (pointer does not change)
AND	X2	Create series connection to contact a of X2
OUT	M0	Drive M0 coil
MPP		Read stack
OUT	Y2	Drive Y2 coil
END		Program conclusion

Command	Function					
OUT	Drive coil					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	—	✓	✓	—	—	—

Explanation Outputs result of logical operation before OUT command to the designated element.
Coil contact action:

Result:	Out command		
	Coil	Access Point:	
		Contact a (N.O.)	Contact b (N.C.)
FALSE	OFF	Not conducting	Conducting
TRUE	ON	Conducting	Not conducting

Example Ladder diagram:



Command code:		Description:
LD	X0	Load Contact b of X0
AND	X1	Establish parallel connection to contact a of X1
OUT	**Y1**	Drive Y1 coil

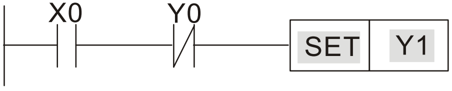
Command	Function					
SET	Action continues (ON)					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	—	✓	✓	—	—	—

Explanation

When the SET command is driven, the designated element will be set as ON, and will be maintained in an ON state, regardless of whether the SET command is still driven. The RST command can be used to set the element as OFF.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
ANI	Y0	Establish parallel connection to contact b of Y0
SET	**Y1**	Action continues (ON)

Command	Function					
RST	Clear contact or register					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	—	✓	✓	✓	✓	✓

Explanation

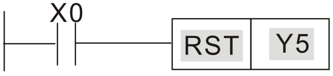
When the RST command is driven, the action of the designated element will be as follows:

Element	Mode
Y, M	Both coil and contact will be set as OFF.
T, C	The current timing or count value will be set as 0, and both the coil and contact will be set as OFF.
D	The content value will be set as 0.

If the RST command has not been executed, the status of the designated element will remain unchanged.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
RST	**Y5**	Clear contact or register

Command	Function	
TMR	16-bit timer	
Operand	T-K	T0–T159, K0–K32,767
	T-D	T0–T159, D0–D399

Explanation

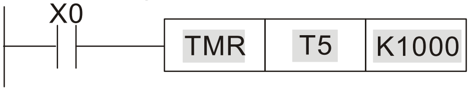
When the TMR command is executed, the designated timer coil will be electrified, and the timer will begin timing. The contact's action will be as follows when the timing value reaches the designated set value (timing value ≥ set value):

N.O. (Normally Open) contact	Closed
N.C. (Normally Close) contact	Open

If the RST command has not been executed, the status of the designated element will remain unchanged.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
TMR	T5 K1000	T5 timer Set value as K1000

Command	Function	
CNT	16-bit counter	
Operand	C-K	C0–C79, K0–K32,767
	C-D	C0–C79, D0–D399

Explanation

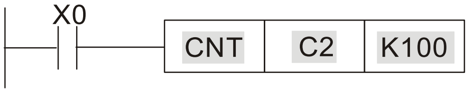
When the CNT command is executed from OFF→ON, this indicates that the designated counter coil goes from no power → electrified, and 1 will be added to the counter's count value; when the count reaches the designated value (count value = set value), the contact will have the following action:

N.O. (Normally Open) contact	Closed
N.C. (Normally Close) contact	Open

After the count value has been reached, the contact and count value will both remain unchanged even if there is continued count pulse input. Use the RST command if you wish to restart or clear the count.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
CNT	**C2 K100**	C2counter Set value as K100

Command	Function
MC/MCR	Connect/release a common series contact
Operand	N0–N7

Explanation

MC is the main control initiation command, and any commands between MC and MCR will be executed normally. When the MC command is OFF, any commands between MC and MCR will act as follows:

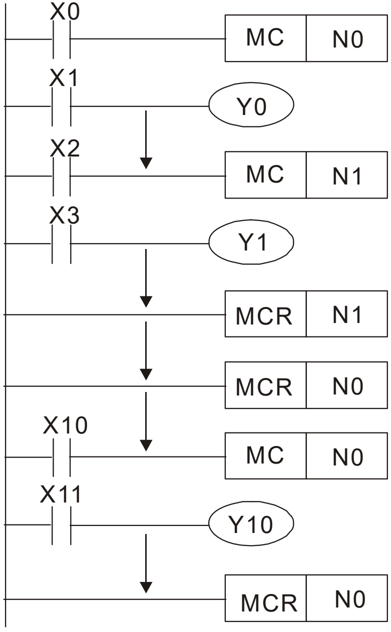
Determination of commands	Description
Ordinary timer	The timing value will revert to 0, the coil will lose power, and the contact will not operate
Counter	The coil will lose power, and the count value and contact will stay in their current state
Coil driven by OUT command	None receive power
Elements driven by SET, RST commands	Will remain in their current state
Applications commands	None are actuated

MCR is the main control stop command, and is placed at the end of the main control program. There may not be any contact commands before the MCR command.

The MC-MCR main control program commands support a nested program structure with a maximum only 8 levels; use in the order N0-N7, please refer to the following program:

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
MC	**N0**	Connection of N0 common series contact
LD	X1	Load Contact a of X1
OUT	Y0	Drive Y0 coil
:		
LD	X2	Load Contact a of X2
MC	**N1**	Connection of N1 common series contact
LD	X3	Load Contact a of X3
OUT	Y1	Drive Y1 coil
:		
MCR	**N1**	Release N1 common series contact
:		
MCR	**N0**	Release N0 common series contact
:		
LD	X10	Load Contact a of X10
MC	**N0**	Connection of N0 common series contact
LD	X11	Load Contact a of X11
OUT	Y10	Drive Y10 coil
:		
MCR	**N0**	Release N0 common series contact

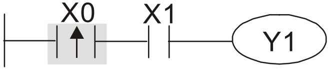
Command	Function					
LDP	Start of forward edge detection action					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The LDP command has the same usage as LD, but its action is different; its function is to save current content, while also saving the detected state of the rising edge of the contact to the cumulative register.

Example

Ladder diagram:



Command code:		Description:
LDP	**X0**	Start of X0 forward edge detection action
AND	X1	Create series connection to contact a of X1
OUT	Y1	Drive Y1 coil

Remark

Please refer to the function specifications table for each device in series for the scope of usage of each operand.

A rising edge contact will be TRUE after power is turned on if the rising edge contact is On before power is turned on to the PLC.

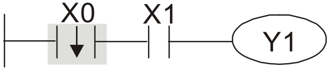
Command	Function					
LDF	Start of reverse edge detection action					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The LDF command has the same usage as LD, but its action is different; its function is to save current content while also saving the detected state of the falling edge of the contact to the cumulative register.

Example

Ladder diagram:



Command code:		Description:
LDF	**X0**	Start of X0 reverse edge detection action
AND	X1	Create series connection to contact a of X1
OUT	Y1	Drive Y1 coil

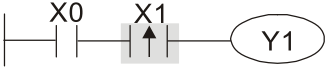
Command	Function					
ANDP	Forward edge detection series connection					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation

The ANDP command used for a contact rising edge detection series connection.

Example

Ladder diagram:



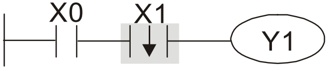
Command code:		Description:
LD	X0	Load Contact a of X0
ANDP	**X1**	X1 Forward edge detection series connection
OUT	Y1	Drive Y1 coil

Command	Function					
ANDF	Reverse edge detection series connection					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation The ANDF command is used for a contact falling edge detection series connection.

Example

Ladder diagram:



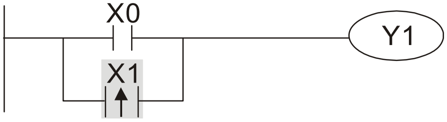
Command code:		Description:
LD	X0	Load Contact a of X0
ANDF	**X1**	X1 Reverse edge detection series connection
OUT	Y1	Drive Y1 coil

Command	Function					
ORP	Forward edge detection parallel connection					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation The ORP command is used for a contact rising edge detection parallel connection.

Example

Ladder diagram:



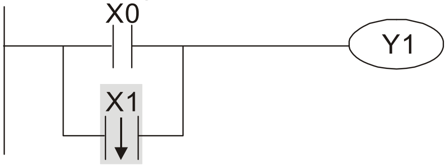
Command code:		Description:
LD	X0	Load Contact a of X0
ORP	**X1**	X1 Forward edge detection parallel connection
OUT	Y1	Drive Y1 coil

Command	Function					
ORF	Reverse edge detection parallel connection					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	✓	✓	✓	✓	✓	—

Explanation The ORF command is used for contact falling edge detection parallel connection.

Example

Ladder diagram:

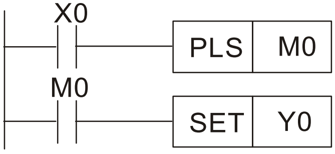


Command code:		Description:
LD	X0	Load Contact a of X0
ORF	**X1**	X1 Reverse edge detection parallel connection
OUT	Y1	Drive Y1 coil

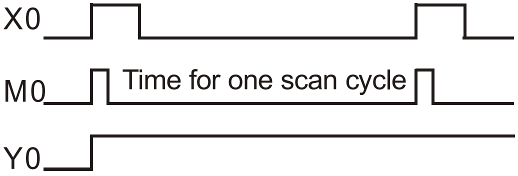
Command	Function					
PLS	Upper differential output					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	–	✓	✓	–	–	–

Explanation Upper differential output commands. When X0 = OFF→ON (positive edge-triggered), the PLS command will be executed, and M0 will send one pulse, with a pulse length consisting of one scanning period.

Example Ladder diagram:



Time sequence diagram:

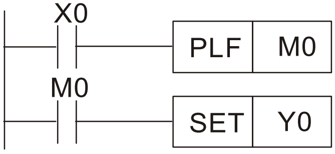


Command code:		Description:
LD	X0	Load Contact a of X0
PLS	**M0**	M0 Upper differential output
LD	M0	Load Contact a of M0
SET	Y0	Y0 Action continues (ON)

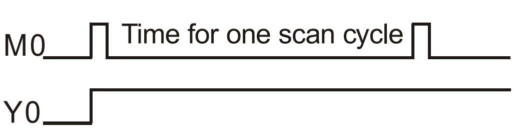
Command	Function					
PLF	Lower differential output					
Operand	X0–X17	Y0–Y17	M0–M799	T0–159	C0–C79	D0–D399
	–	✓	✓	–	–	–

Explanation Lower differential output command. When X0 = ON→OFF (negative edge-triggered), the PLF command will be executed, and M0 will send one pulse, with pulse length consisting of one scanning period.

Example Ladder diagram:



Time sequence diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
PLF	**M0**	M0 Lower differential output
LD	M0	Load Contact a of M0
SET	Y0	Y0 Action continues (ON)

Command	Function
END	Program conclusion
Operand	N/A

Explanation An END command must be added to the end of a ladder diagram program or command program. The PLC will scan from address 0 to the END command, and will return to address 0 and begins scanning again after execution.

Command	Function
NOP	No action
Operand	N/A

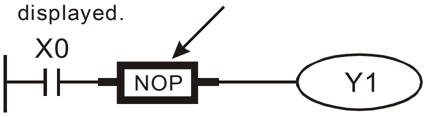
Explanation

The command NOP does not perform any operation in the program. Because execution of this command will retain the original logical operation results, it can be used in the following situation: the NOP command can be used to replace a command that is deleted without changing the program length.

Example

Ladder diagram:

NOP command will be simplified and not displayed when the ladder diagram is displayed.



Command code:		Description:
LD	X0	Load Contact b of X0
NOP		No action
OUT	Y1	Drive Y1 coil

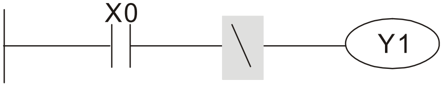
Command	Function
INV	Inverse of operation results
Operand	N/A

Explanation

Saves the result of the logic inversion operation prior to the INV command in the cumulative register.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
INV		Inverse of operation results
OUT	Y1	Drive Y1 coil

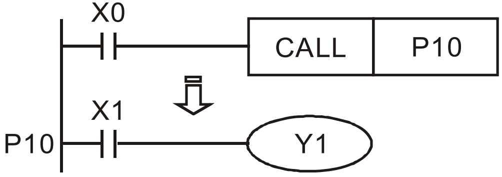
Command	Function
P	Index
Operand	P0–P255

Explanation

Pointer P is used to subprogram call command API 01 CALL. Use does not require starting from zero, but the number cannot be used repeatedly, otherwise an unpredictable error will occur.

Example

Ladder diagram:



Command code:		Description:
LD	X0	Load Contact a of X0
CALL	P10	Call command CALL to P10
:		
P10		Pointer P10
LD	X1	Load Contact a of X1
OUT	Y1	Drive Y1 coil

16-6-3 Overview of application commands

Classification	API	Command code		P command	Function	STEPS	
		16 bit	32 bit			16bit	32bit
Circuit control	01	CALL	–	✓	Call subprogram	3	–
	02	SRET	–	–	Conclusion of subprogram	1	–
	06	FEND	–	–	Conclusion of main program	1	–
Send comparison	10	CMP	DCMP	✓	Compares set output	7	13
	11	ZCP	DZCP	✓	Range comparison	9	17
	12	MOV	DMOV	✓	Data movement	5	9
	13	SMOV	DSMOV	✓	Nibble movement	11	21
	15	BMOV	–	✓	Send all	7	–
Four logical operations	18	BCD	DBCD	✓	BIN to BCD transformation	5	9
	19	BIN	DBIN	✓	BCD to BIN transformation	5	9
	20	ADD	DADD	✓	BIN addition	7	13
	21	SUB	DSUB	✓	BIN subtraction	7	13
	22	MUL	DMUL	✓	BIN multiplication	7	13
	23	DIV	DDIV	✓	BIN division	7	13
	24	INC	DINC	✓	BIN add one	3	5
	25	DEC	DDEC	✓	BIN subtract one	3	5
Rotational displacement	30	ROR	DROR	✓	Right rotation	5	–
	31	ROL	DROL	✓	Left rotation	5	–
Data Process	40	ZRST	–	✓	Clear range	5	-
	41	DECO	DDECO	✓	Decoder	7	13
	42	ENCO	DENCO	✓	Encoder	7	13
	43	SUM	DSUM	✓	ON bit number	5	9
	44	BON	DBON	✓	ON bit judgement	7	13
	49	–	DFLT	✓	BIN whole number → binary floating point number transformation	–	9
Floating point operation	110	–	DECMP	✓	Comparison of binary floating point numbers	–	13
	111	–	DEZCP	✓	Comparison of binary floating point number range	–	17
	116	–	DRAD	✓	Angle → Radian	–	9
	117	–	DDEG	✓	Radian → Angle	–	9
	120	–	DEADD	✓	Binary floating point number addition	–	13
	121	–	DESUB	✓	Binary floating point number subtraction	–	13
	122	–	DEMUL	✓	Binary floating point number multiplication	–	13
	123	–	DEDIV	✓	Binary floating point number division	–	13
	124	–	DEXP	✓	Binary floating point number obtain exponent	–	9
	125	–	DLN	✓	Binary floating point number obtain logarithm	–	9
	127	–	DESQR	✓	Binary floating point number find square root	–	9
	129	INT	DINT	✓	Binary floating point number → BIN whole number transformation	–	9
	130	–	DSIN	✓	Binary floating point number SIN operation	–	9
	131	–	DCOS	✓	Binary floating point number COS operation	–	9
	132	–	DTAN	✓	Binary floating point number TAN operation	–	9

Classification	API	Command code		P command	Function	STEPS	
		16 bit	32 bit			16bit	32bit
	133	–	DASIN	✓	Binary floating point number ASIN operation	–	9
	134	–	DACOS	✓	Binary floating point number ACOS operation	–	9
	135	–	DATAN	✓	Binary floating point number ATAN operation	–	9
Floating point operation	136	–	DSINH	✓	Binary floating point number SINH operation	–	9
	137	–	DCOSH	✓	Binary floating point number COSH operation	–	9
	138	–	DTANH	✓	Binary floating point number TANH operation	–	9
Other	147	SWAP	DSWAP	✓	Exchange the up/down 8 bits	3	5
Communication	150	MODRW	–	✓	Modbus read/write	7	–
Calendar	160	TCMP	–	✓	Compare calendar data	11	–
	161	TZCP	–	✓	Compare calendar data range	9	–
	162	TADD	–	✓	Calendar data addition	7	–
	163	TSUB	–	✓	Calendar data subtraction	7	–
	166	TRD	–	✓	Calendar data read	3	–
GRAY code	170	GRY	DGRY	✓	BIN→GRY code transformation	5	9
	171	GBIN	DGBIN	✓	GRY code →BIN transformation	5	9
Contact form logical operation	215	LD&	DLD&	–	Contact form logical operation LD#	5	9
	216	LD|	DLD|	–	Contact form logical operation LD#	5	9
	217	LD^	DLD^	–	Contact form logical operation LD#	5	9
	218	AND&	DAND&	–	Contact form logical operation AND#	5	9
	219	ANDI	DANDI	–	Contact form logical operation AND#	5	9
	220	AND^	DAND^	–	Contact form logical operation AND#	5	9
	221	OR&	DOR&	–	Contact form logical operation OR#	5	9
	222	OR|	DOR|	–	Contact form logical operation OR#	5	9
	223	OR^	DOR^	–	Contact form logical operation OR#	5	9
Contact form compare command	224	LD＝	DLD＝	–	Contact form compare LD※	5	9
	225	LD＞	DLD＞	–	Contact form compare LD※	5	9
	226	LD＜	DLD＜	–	Contact form compare LD※	5	9
	228	LD＜＞	DLD＜＞	–	Contact form compare LD※	5	9
	229	LD＜＝	DLD＜＝	–	Contact form compare LD※	5	9
	230	LD＞＝	DLD＞＝	–	Contact form compare LD※	5	9
	232	AND＝	DAND＝	–	Contact form compare AND※	5	9
	233	AND＞	DAND＞	–	Contact form compare AND※	5	9
	234	AND＜	DAND＜	–	Contact form compare AND※	5	9
	236	AND＜＞	DAND＜＞	–	Contact form compare AND※	5	9
	237	AND＜＝	DAND＜＝	–	Contact form compare AND※	5	9
	238	AND＞＝	DAND＞＝	–	Contact form compare AND※	5	9
	240	OR＝	DOR＝	–	Contact form compare OR※	5	9
	241	OR＞	DOR＞	–	Contact form compare OR※	5	9
	242	OR＜	DOR＜	–	Contact form compare OR※	5	9
	244	OR＜＞	DOR＜＞	–	Contact form compare OR※	5	9
	245	OR＜＝	DOR＜＝	–	Contact form compare OR※	5	9
	246	OR＞＝	DOR＞＝	–	Contact form compare OR※	5	9

Classification	API	Command code		P command	Function	STEPS	
		16 bit	32 bit			16bit	32bit
Floating point contact form	275	–	FLD＝	–	Floating point number contact form compare LD※	–	9
	276	–	FLD＞	–	Floating point number contact form compare LD※	–	9
	277	–	FLD＜	–	Floating point number contact form compare LD※	–	9
Compare command	278	–	FLD＜＞	–	Floating point number contact form compare LD※	–	9
	279	–	FLD＜＝	–	Floating point number contact form compare LD※	–	9
	280	–	FLD＞＝	–	Floating point number contact form compare LD※	–	9
	281	–	FAND＝	–	Floating point number contact form compare AND※	–	9
	282	–	FAND＞	–	Floating point number contact form compare AND※	–	9
	283	–	FAND＜	–	Floating point number contact form compare AND※	–	9
	284	–	FAND＜＞	–	Floating point number contact form compare AND※	–	9
	285	–	FAND＜＝	–	Floating point number contact form compare AND※	–	9
	286	–	FAND＞＝	–	Floating point number contact form compare AND※	–	9
	287	–	FOR＝	–	Floating point number contact form compare OR※	–	9
	288	–	FOR＞	–	Floating point number contact form compare OR※	–	9
	289	–	FOR＜	–	Floating point number contact form compare OR※	–	9
	290	–	FOR＜＞	–	Floating point number contact form compare OR※	–	9
	291	–	FOR＜＝	–	Floating point number contact form compare OR※	–	9
	292	–	FOR＞＝	–	Floating point number contact form compare OR※	–	9
Driver special command	139	RPR	–	✓	Read servo parameter	5	–
	140	WPR	–	✓	Write servo parameter	5	–
	141	FPID	–	✓	Driver PID control mode	9	–
	142	FREQ	–	✓	Driver torque control mode	7	–
	261	CANRX	–	✓	Read CANopen slave station data	9	–
	264	CANTX	–	✓	Write CANopen slave station data	9	–
	265	CANFLS	–	✓	Refresh special D corresponding to CANopen	3	–
	320	ICOMR	DICOMR	✓	Internal communications read	9	17
	321	ICOMW	DICOMW	✓	Internal communications write	9	17
	323	WPRA	–	–	RAM write in drive parameters	5	–

16-6-4 Detailed explanation of applications commands

API				
01	**CALL**	**P**	S	Call subprogram

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D

Notes on operand usage:
The S operand can designate P
CP2000 series device: The S operand can designate P0-P63

16-bit command (3 STEP)

CALL	Continuous execution type	CALLP	Pulse execution type

32-bit command

—	—	—	—

Flag signal: none

Explanation

- **S**：Call subprogram pointer.
- Write the subprogram after the FEND command.
- The subprogram must end after the SRET command.
- Refer to the FEND command explanation and sample content for detailed command functions.

API				
02	**SRET**	**P**	–	Conclusion of subprogram

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D

Notes on operand usage:
No operand
A contact-driven command is not needed

16-bit command (1 STEP)

FEND	Continuous execution type	—	—

32-bit command

—	—	—	—

Flag signal: none

Explanation

- A contact-driven command is not needed. Automatically returns next command after CALL command
- Indicates end of subprogram. After end of subprogram, SRET returns to main program, and executes next command after the original call subprogram CALL command.
- Refer to the FEND command explanation and sample content for detailed command functions.

API				
06	**FEND**		–	Conclusion a main program

	Bit device				Word device						
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D

Notes on operand usage:

No operand

A contact-driven command is not needed

16-bit command (1 STEP)

FEND	Continuous execution type	–	–

32-bit command

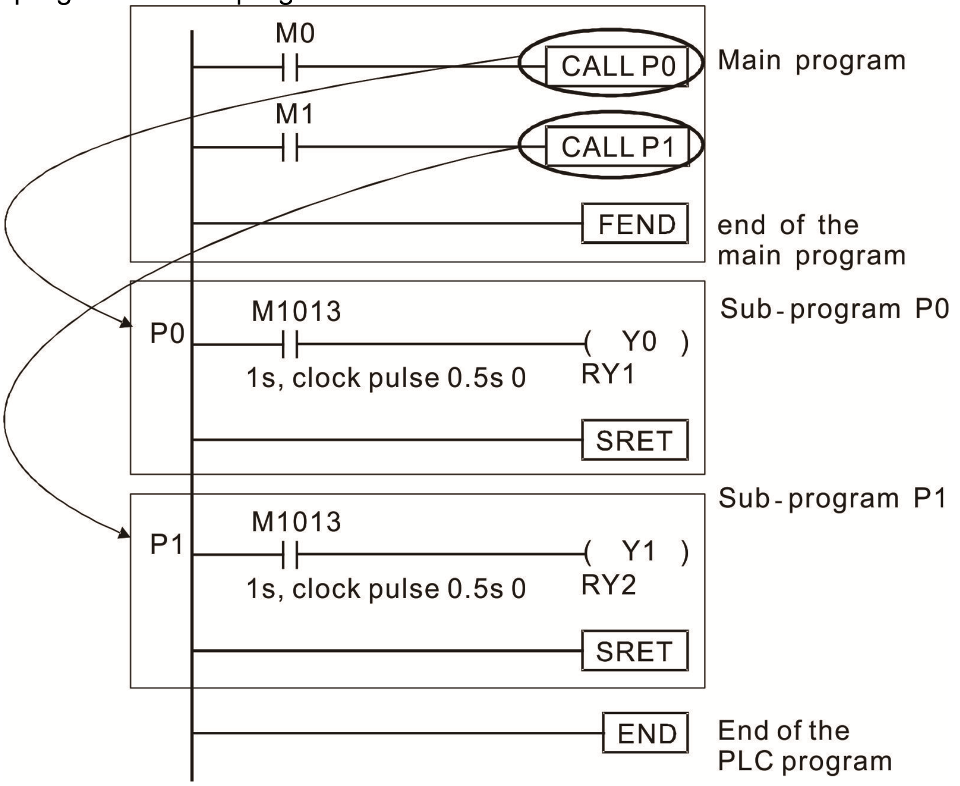
–	–	–	–

Flag signal: none

Explanation

- This command indicates the end of the main program. It is the same as the END command when the PLC executes this command.
- The CALL command program must be written after the FEND command, and the SRET command added to the end of the subprogram.
- When using the FEND command, an END command is also needed. However, the END command must be placed at the end, after the main program and subprogram.

CALL command process



API 10	D	CMP	P	S1 S2 D	Compares set output

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
D		*	*								

Notes on operand usage:
The operand D occupies three consecutive points

16-bit command (7 STEP)

CMP	Continuous execution type	CMPP	Pulse execution type

32-bit command (13 STEP)

DCMP	Continuous execution type	DCMPP	Pulse execution type

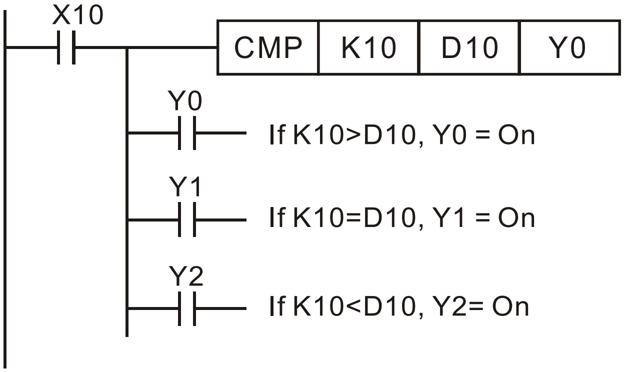
Flag signal: none

Explanation

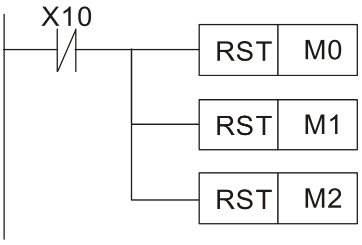
- S1: Compare value 1. S2: Compare value 2. D: Results of comparison.
- Compares the size of the content of operand S1 and S2; the results of comparison are expressed in D.
- Size comparison is performed algebraically. All data is compared in the form of numerical binary values. Because this is a 16-bit command, when b15 is 1, this indicates a negative number.

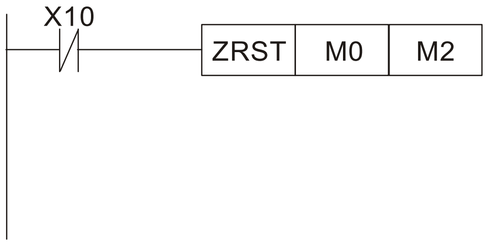
Example

- When the designated device is Y0, it automatically occupies Y0, Y1 and Y2.
- When X10 = ON, the CMP command executes, and Y0, Y1 or Y2 will be ON. When X10 = OFF, the CMP command will not execute, and the state of Y0, Y1 and Y2 will remain in the state prior to X10 = OFF.
- If ≥, ≤, or ≠ results are needed, they can be obtained via series/parallel connections of Y0-Y2.



- To clear results of comparison, use the RST or ZRST command.





API					
11	D	**ZCP**	P	S1 S2 S D	Range comparison

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
S				*	*	*	*	*	*	*	*
D		*	*								

Notes on operand usage:
The content value of operand S1 is less than the content value of S2 operand
The operand D occupies three consecutive points

16-bit command (9 STEP)

ZCP	Continuous execution type	ZCPP	Pulse execution type

32-bit command (17 STEP)

DZCP	Continuous execution type	DZCPP	Pulse execution type

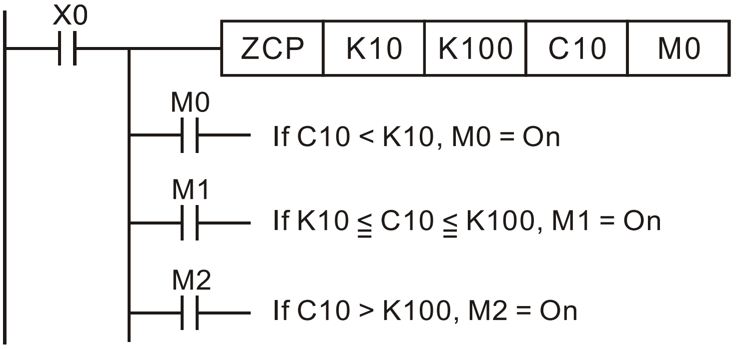
Flag signal: none

Explanation

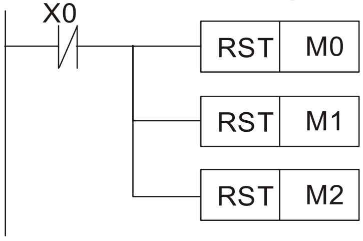
- S1: Lower limit of range comparison. S2: Upper limit of range comparison. S : Comparative value. D: Results of comparison.
- When the comparative value S is compared with the lower limit S1 and upper limit S2, the results of comparison are expressed in D.
- When lower limit S1 > upper limit S2, the command will use the lower limit S1 to perform comparison with the upper and lower limit.
- Size comparison is performed algebraically. All data is compared in the form of numerical binary values. Because this is a 16-bit command, when b15 is 1, this indicates a negative number.

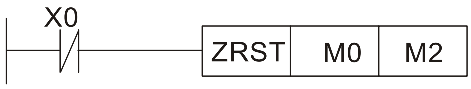
Example

- When the designated device is M0, it automatically occupies M0, M1 and M2.
- When X0 = ON, the ZCP command executes, and M0, M1 or M2 will be ON. When X0 = OFF, the ZCP command will not execute, and the state of M0, M1 or M2 will remain in the state prior to X0 = OFF.
- If ≥, ≤, or ≠ results are needed, they can be obtained via series/parallel connections of M0-M2.



- To clear results of comparison, use the RST or ZRST command.





API					
12	**D**	**MOV**	**P**	Ⓢ Ⓓ	Data movement

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (5 STEP)

MOV	Continuous execution type	MOVP	Pulse execution type

32-bit command (9 STEP)

DMOV	Continuous execution type	DMOVP	Pulse execution type

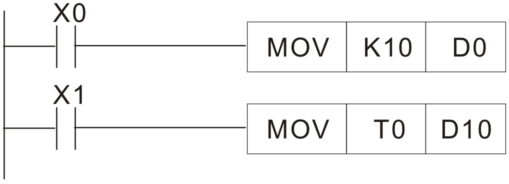
Flag signal:

Explanation

- Ⓢ: Data source. Ⓓ: Destination of data movement.
- When this command is executed, the content of Ⓢ content will be directly moved to Ⓓ. When the command is not executed, the content of Ⓓ will not change.

Example

- When X0 = OFF, the content of D10 will not change; if X0 = ON, the value K10 will be sent to data register D10.
- When X1 = OFF, the content of D10 will not change; if X1 = ON, the current value of T0 will be sent to data register D10.



API 13	D	**SMOV**	P	S m1 m2 D n	Nibble movement

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (11 STEP)

MOV	Continuous execution type	SMOVP	Pulse execution type

32-bit command (21 STEP)

DSMOV	Continuous execution type	DSMOVP	Pulse execution type

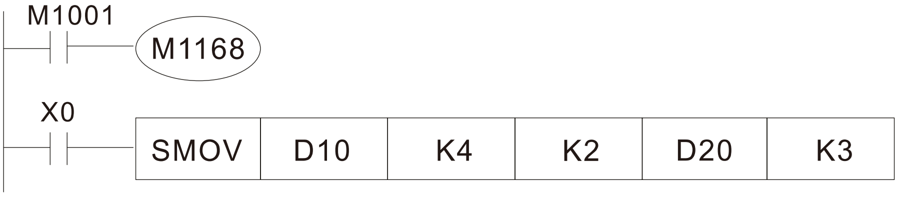
Flag signal: M1168

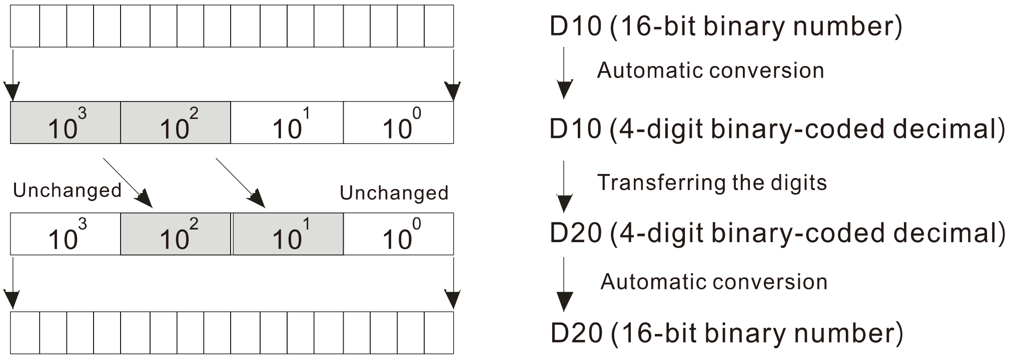
Explanation

- S: Data source. m1: The data source transfers starting bit number. m2 : The data source transfers individual bit number. D: Transfer destination. n Transferring starting bit number of the destination.
- BCD mode (M1168 = OFF):
  SMOV enables and operates BCD under this mode, the operation is similar to the way SMOV operates decimal numbers. The command copies specific bit number of arithmetic element S (S is a 4-figure decimal number), and sends the bit number to arithmetic element D (D is also a 4-figure decimal number). The current data on the target register will be covered.
- m_1 range: 1–4
- m_2 range: 1–m_1 (m_2 cannot be larger than m_1)
- n range: m_2–4 (n cannot be smaller than m_2)

Example 1

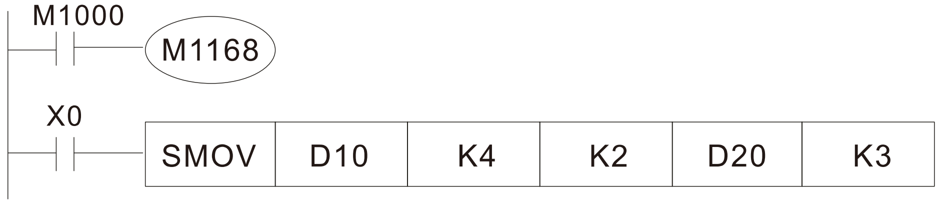
- When M1168 = OFF (BCD mode), X0 is ON, the instruction transfers two digits of the decimal number starting from the fourth digit of the decimal number (the digit in the thousands place of the decimal number) in D10 to the two digits of the decimal number starting from the third digit of the decimal number (the digit in the hundreds place of the decimal number) in D20. After the instruction is executed, the digits in the thousands place of the decimal number (10^3) and the ones place of the decimal number (10^0) in D20 are unchanged.

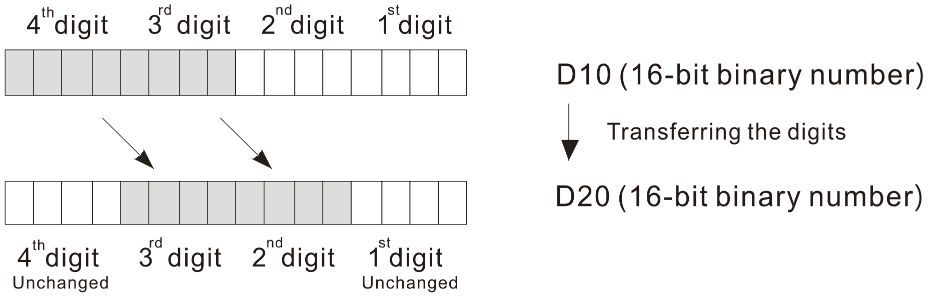



D10 (16-bit binary number)
Automatic conversion
10^3
10^2
10^1
10^0
D10 (4-digit binary-coded decimal)
Unchanged
Unchanged
Transferring the digits
10^3
10^2
10^1
10^0
D20 (4-digit binary-coded decimal)
Automatic conversion
D20 (16-bit binary number)

Example 2

- When M1168 is ON (BIN mode), and the SMOV command is executed, D10 and D20 do not change in BCD mode, but send 4 digits as a unit in BIN mode.





API				
15	**BMOV**	P	S D n	Send all

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S						*	*	*	*	*	*
D							*	*	*	*	*
n				*	*				*	*	

Notes on operand usage:
n operand scope n ＝ 1 to 512

16-bit command (7 STEP)

BMOV	Continuous execution type	BMOVP	Pulse execution type

32-bit command

–	–	–	–

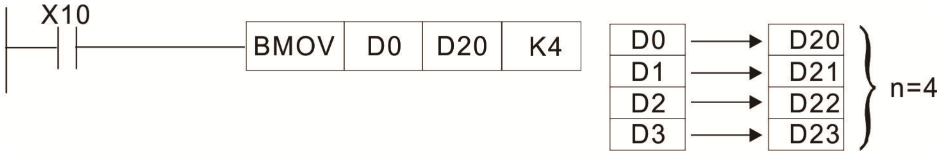
Flag signal: none

Explanation

- S: Initiate source device. D: Initiate destination device. n: Send block length.
- The content of n registers starting from the initial number of the device designated by S will be sent to the n registers starting from the initial number of the device designated by n; if the number of points referred to n exceeds the range used by that device, only points within the valid range will be sent.

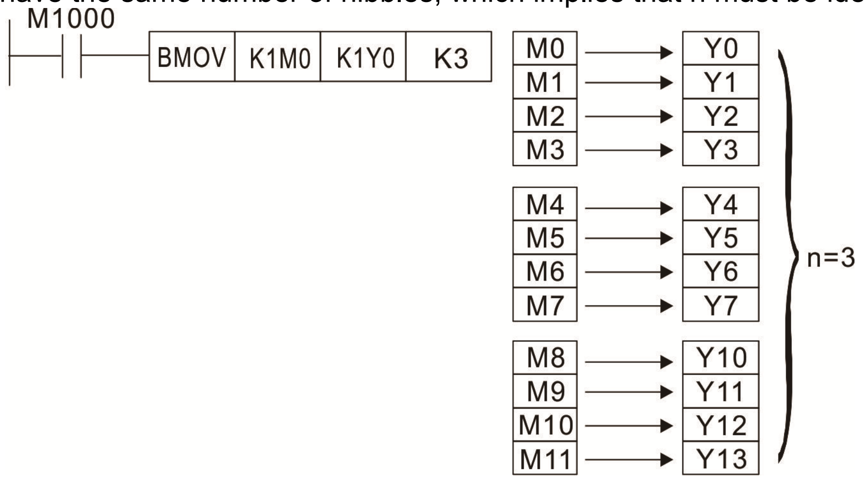
Example 1

- When X10 = ON, the content of registers D0–D3 will be sent to the four registers D20 to D23.



Example 2

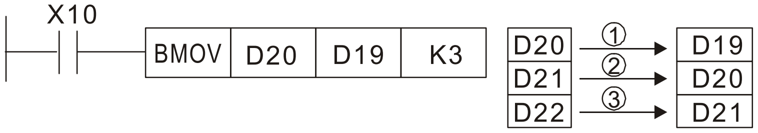
- If the designated bit devices KnX, KnY, and KnM are sent, S and D must have the same number of nibbles, which implies that n must be identical.



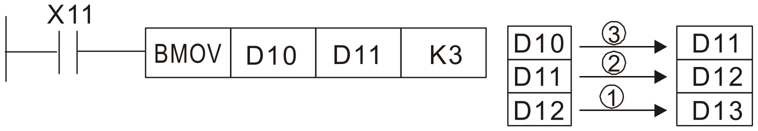
Example 3

- In order to prevent overlap between the transmission addresses of two operands, which would cause confusion, make sure that the addresses designated by the two operands have different sizes, as shown below:

When S > D, send in the order ①→② →③.



When S < D, send in the order ③→② →①.



API 18	D	**BCD**	P	S D	BIN to BCD transformation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S						*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (5 STEP)

BCD	Continuous execution type	BCDP	Pulse execution type

32-bit command (9 STEP)

DBCD	Continuous execution type	DBCDP	Pulse execution type

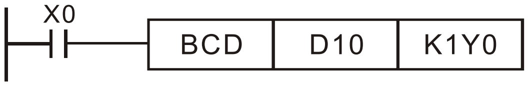
Flag signal: none

Explanation

- S: Data source. D: Destination of data movement.
- The content of data source S (BIN value, 0–9999) executes BCD transformation and saves in D.
- Arithmetic elements S and D use the F device, it can only use 16-bit command.

Example

- When X0 is ON, and the BIN value of D10 is transformed to BCD value, the digit is saved in 4-bit element of K1Y0 (Y0–Y3).



- If D10 = 001E (Hex) = 0030 (Decimal), the executed result will be Y0–Y3=0000 (BIN).

API					
19	D	**BIN**	P	(S) (D)	BCD to BIN transformation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S						*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (5 STEP)

BIN	Continuous execution type	BINP	Pulse execution type

32-bit command (9 STEP)

DBIN	Continuous execution type	DBINP	Pulse execution type

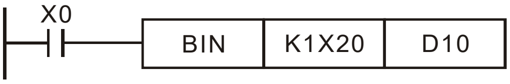
Flag signal: none

Explanation

- (S): Data source. (D): Transformation result.
- The content of data source (S) (BCD: 0–9,999) executes BIN transformation and saves in (D).
- Valid number range of the data source S: BCD (0–9,999), DBCD (0–99,999,999).

Example

- When X0 is ON, and the BCD value of K1X20 is transformed to BIN value, the result saves in D10.



Remark

- When PLC reads a BCD type switch-off from the outside, it has to use the BIN command to transform the read data to BIN value, then saves the value into PLC.

API					
20	D	ADD	P	S1 S2 D	BIN addition

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (7 STEP)

ADD	Continuous execution type	ADDP	Pulse execution type

32-bit command (13 STEP)

DADD	Continuous execution type	DADDP	Pulse execution type

Flag signal: M1020 Zero flag
M1021 Borrow flag
M1022 Carry flag
Please refer to the following supplementary explanation

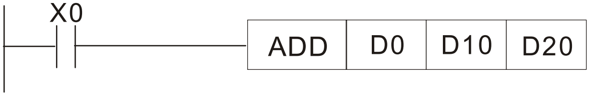
Explanation

- S1: Augend. S2: Addend. D: Sum.
- Using two data sources: The result of adding S1 and S2 using the BIN method will be stored in D.
- The highest bit of any data is symbolized as bit 0 indicating (positive) 1 indicating (negative), enabling the use of algebraic addition operations. (for instance: 3+(-9) = -6)
- Flag changes connected with the addition.

1. When calculation results are 0, the zero flag M1020 will be ON.
2. When calculation results are less than –32,768, the borrow flag M1021 will be ON.
3. When calculation results are greater than 32,767, the carry flag M1022 will be ON.

Example

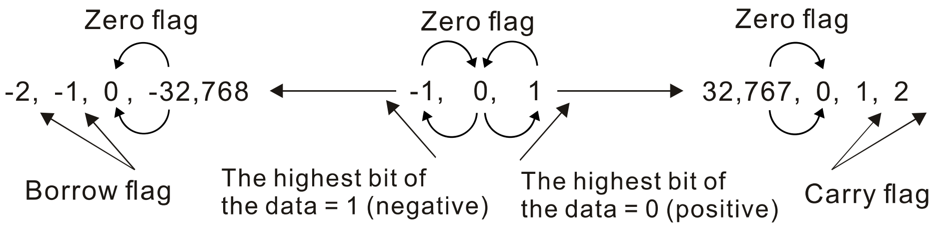
- 16-bit BIN addition: When X0 = ON, the result of the content of addend D0 plus the content of augend D10 will exist in the content of D20.



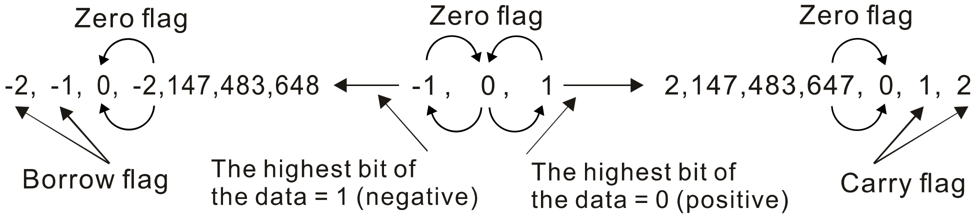
Remark

- Relationship between flag actions and negative/positive numbers:

16-bit:



32-bit:



API 21	D	SUB	P	S1 S2 D	BIN subtraction

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (7 STEP)

SUB	Continuous execution type	SUBP	Pulse execution type

32-bit command (13 STEP)

DSUB	Continuous execution type	DSUBP	Pulse execution type

Flag signal: M1020 Zero flag
M1021 Borrow flag
M1022 Carry flag
Please refer to the following supplementary explanation

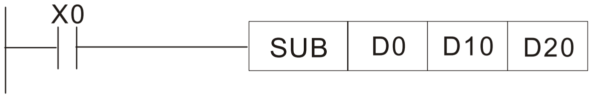
Explanation

- S1: Minuend. S2: Subtrahend. D: Difference.
- Using two data sources: The result of subtraction of S1 and S2 using the BIN method is stored in D.
- The highest bit of any data is symbolized as bit 0 indicating (positive) 1 indicating (negative), enabling the use of algebraic subtraction operations.
- Flag changes connected with subtraction.

1. When calculation results are 0, the zero flag M1020 will be ON.
2. When calculation results are less than –32,768, the borrow flag M1021 will be ON.
3. When calculation results are greater than 32,767, the carry flag M1022 will be ON.

Example

- 16-bit BIN subtraction: When X0 = ON, the content of D10 is subtracted from the content of D0, and the difference is stored in D20.



API					
22	D	**MUL**	P	S1 S2 D	BIN multiplication

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage:
The 16-bit command operand D will occupy 2 consecutive points

16-bit command (7 STEP)			
MUL	Continuous execution type	MULP	Pulse execution type

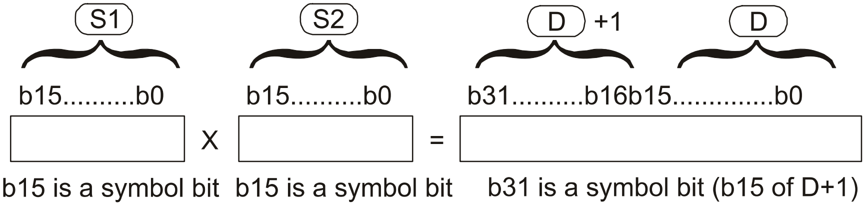
32-bit command (13 STEP)			
DMUL	Continuous execution type	DMULP	Pulse execution type

Flag signal: none

Explanation

- S1: Multiplicand. S2: Multiplier. D: Product.
- Using two data sources: When S1 and S2 are multiplied using the BIN method, the product is stored in D.

16-bit BIN multiplication operation:

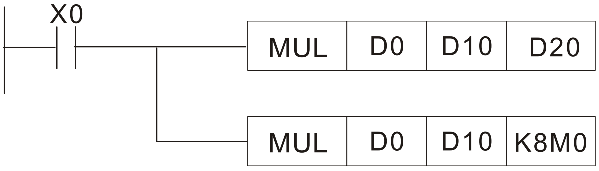


Symbol bit = 0 refers to a positive value
Symbol bit = 1 refers to a negative vlalue

When D is a bit device, K1~K4 can be designated as a hexadecimal number, which will occupy 2 consecutive units.

Example

- When 16-bit DO is multiplied by 16-bit D10, the result will be a 32-bit product; the upper 16 bits will be stored in D21, and the lower 16 bits will be stored in D20. Whether the bit at the farthest left is OFF or ON will indicate the sign of the result.



API 23	D	DIV	P	S1 S2 D	BIN division

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage:
The 16-bit command operand D will occupy 2 consecutive points

16-bit command (7 STEP)

DIV	Continuous execution type	DIVP	Pulse execution type

32-bit command (13 STEP)

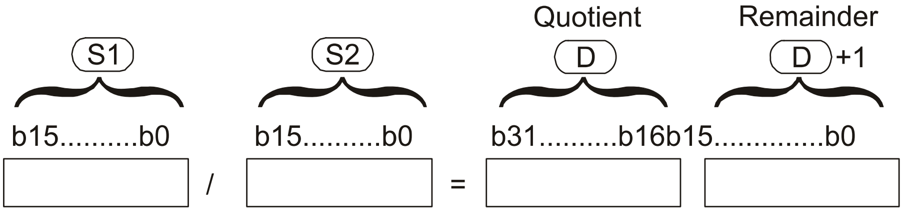
DDIV	Continuous execution type	DDIVP	Pulse execution type

Flag signal: none

Explanation

- S1: Dividend. S2: Divisor. D: Quotient and remainder.
- Using two data sources: The quotient and remainder will be stored in D when S1 and S2 are subjected to division using the BIN method. The sign bit for S1, S2 and D must be kept in mind when performing a 16-bit operation.

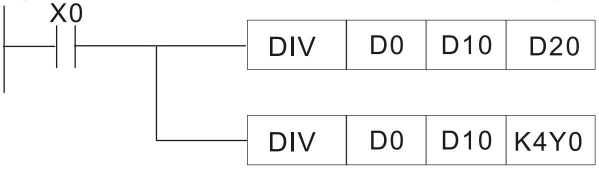
16-bit BIN division:



If D is a bit device, K1–K4 can be designated 16 bits, which will occupy 2 consecutive units and yield the quotient and remainder.

Example

- When X0 = ON, the quotient resulting from division of dividend D0 by divisor D10 will be placed in D20, and the remainder will be placed in D21. Whether the highest bit is OFF or ON will indicate the sign of the result.



API					
24	D	INC	P	D	BIN add one

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D							*	*	*	*	*

Notes on operand usage: none

16-bit command (3 STEP)

INC	Continuous execution type	INCP	Pulse execution type

32-bit command (5 STEP)

DINC	Continuous execution type	DINCP	Pulse execution type

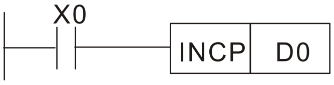
Flag signal: none

Explanation

- D: Destination device.
- If a command is not the pulse execution type, when the command is executed, the program will add 1 to the content of device D for each scanning cycle.
- This command is ordinarily used as a pulse execution type command (INCP).
- During 16-bit operation, 32,767 +1 will change the value to -32,768. During 32 bit operation, 2,147,483,647 +1 will change the value to -2,147,483,648.

Example

- When X0 = OFF→ON, 1 is automatically added to the content of D0.



API					
25	D	**DEC**	P	D	BIN subtract one

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D							*	*			

Notes on operand usage: none

16-bit command (3 STEP)

DEC	Continuous execution type	DECP	Pulse execution type

32-bit command (5 STEP)

DDEC	Continuous execution type	DDECP	Pulse execution type

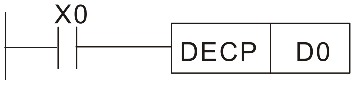
Flag signal: none

Explanation

- D: Destination device.
- If a command is not the pulse execution type, when the command is executed, the program will add 1 to the content of device D for each scanning cycle.
- This command is ordinarily used as a pulse execution type command (DECP).
- During 16-bit operation, -32,768 -1 will change the value to 32,767. During 32 bit operation, -2,147,483,648 -1 will change the value to 2,147,483,647.

Example

- When X0 = OFF→ON, 1 is automatically subtracted from the content of D0.



API					
30	D	ROR	P	D n	Right rotation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D							*	*	*	*	*
n				*	*						

Notes on operand usage:
Only K4 (16-bit) will be valid if the operand D is designated as KnY or KnM.
n operand n=K1-K16 (16-bit)

16-bit command (5 STEP)			
ROR	Continuous execution type	RORP	Pulse execution type

32-bit command (9 STEP)			
DROR	Continuous execution type	DRORP	Pulse execution type

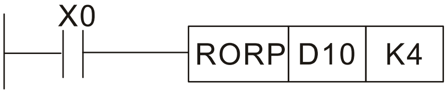
Flag signal: M1022 Carry flag

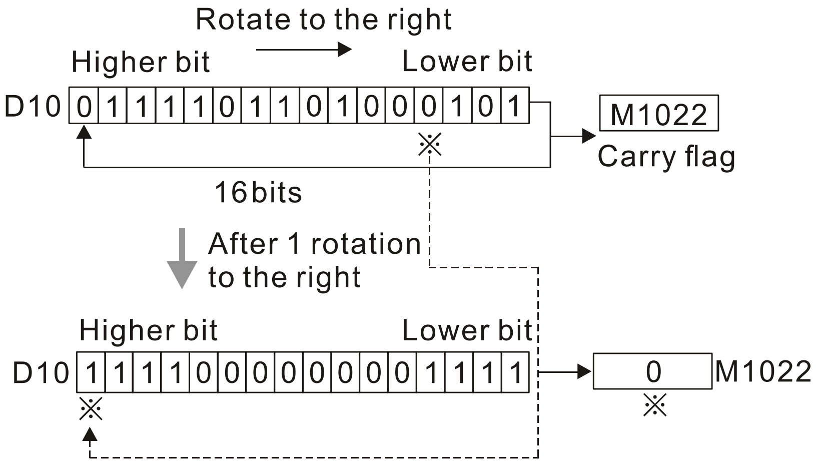
Explanation

- D: Device to be rotated. n: Number of bits for one rotation.
- Rotate the device designated by D to the right n bits.
- This command is ordinarily used as a pulse execution type command (RORP).

Example

- When X0 = OFF→ON, 4 of the 16 bits in D10 specify a right rotation; the content of the bit indicated with * (see figure below) will be sent to the carry flag signal M1022.





API					
31	D	**ROL**	P	(D) (n)	Left rotation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D							*	*	*	*	*
n				*	*						

Notes on operand usage:
Only K4 (16-bit) will be valid if the operand D is designated as KnY or KnM.
n operand n=1 to 16 (16-bit)

16-bit command (5 STEP)

ROL	Continuous execution type	ROLP	Pulse execution type

32-bit command (9 STEP)

DROL	Continuous execution type	DROLP	Pulse execution type

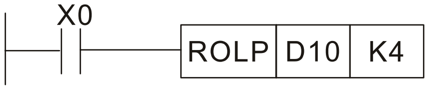
Flag signal: M1022 Carry flag

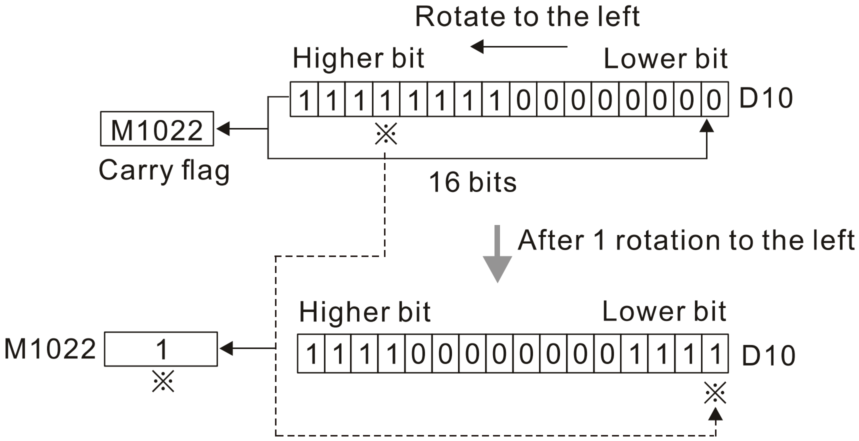
Explanation

- (D): Device to be rotated. (n): Number of bits for one rotation.
- Rotates the device designated by (D) to the left (n) bits.
- This command is ordinarily used as a pulse execution type command (ROLP).

Example

- When X0 = OFF→ON, 4 of the 16 bits in D10 specify a left rotation; the content of the bit indicated with * (see figure below) will be sent to the carry flag signal M1022.





API		ZRST		D1 D2	Clear range
40			P		

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D1		*	*						*	*	*
D2		*	*						*	*	*

Notes on operand usage:
Number of operand D_1 operand ≤ number of operand D_2
Operands D_1, D_2 must designate the same type of device
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

ZRST	Continuous execution type	ZRSTP	Pulse execution type

32-bit command

–	–	–	–

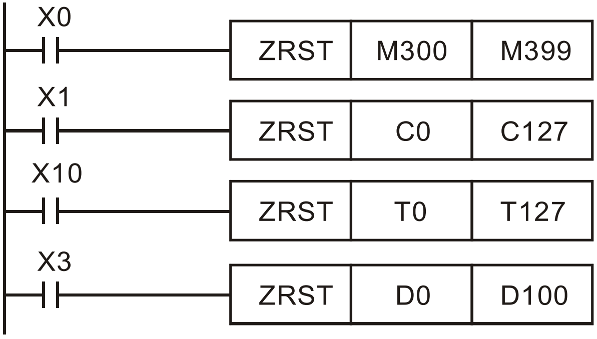
Flag signal: none

Explanation

- **D_1**: Clear range's initial device. **D_2**: Clear range's final device.
- When the number of operand D_1 > number of operand D_2, only the operand designated by D_2 will be cleared.

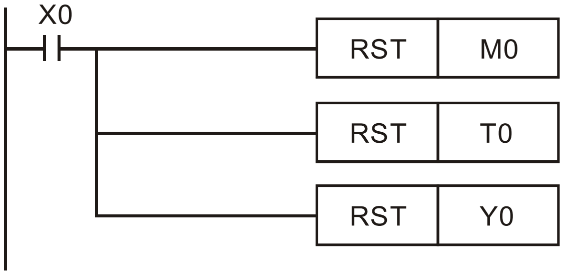
Example

- When X0 is ON, auxiliary relays M300–M399 will be cleared and changed to Off.
- When X1 is ON, 16-bit counters C0–C127 will all be cleared. (Writes 0, and clears and changes contact and coil to OFF).
- When X10 is ON, timer T0–T127 will all be cleared. (Writes 0, and clears and changes contact and coil to OFF).
- When X3 is ON, the data in data registers D0–D100 will be cleared and set as 0.



Remark

- Devices can independently use the clear command (RST), such as bit device Y, M and word device T, C, D.



API					
41	D	**DECO**	P	Ⓢ Ⓓ ⓝ	Decoder

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S	*	*	*	*	*				*	*	*
D		*	*				*	*	*	*	*
n				*	*						

Notes on operand usage: none

16-bit command (7 STEP)

DECO	Continuous execution type	DECOP	Pulse execution type

32-bit command (13 STEP)

DDECO	Continuous execution type	DDECOP	Pulse execution type

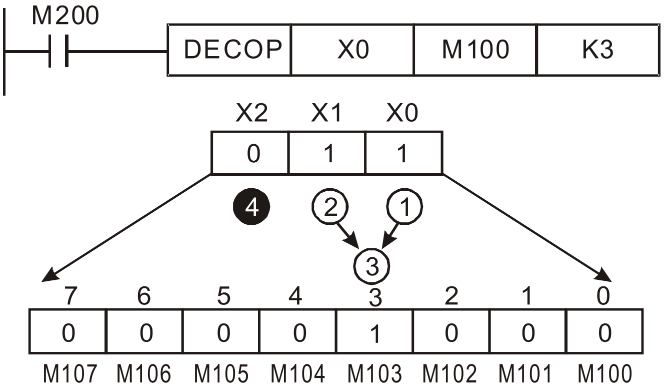
Flag signal: none

Explanation

- Ⓢ: Decoding source device. Ⓓ: Device that saves the decoding result. ⓝ: Length of decoding bit.
- Decodes with the lower "n" bit, and saves the length of "2^n" bit in D.
- This command usually uses pulse execution type command (DECOP).
- When D is the bit device, n = 1–8, when D is the word device, n = 1–4.

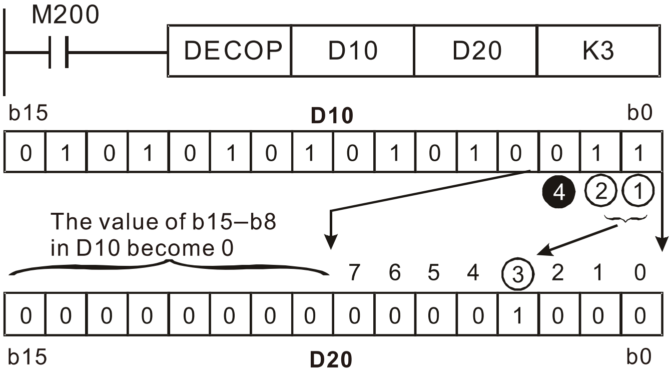
Example 1

- When Dis the bit device, the valid range of n is 0< **n** ≤ 8. If n = 0 or n > 8, a fault will occur.
- When n = 8, the maximum decoding will be 2^8 = 256 points.
- When M200 switches from Off to On, the content of X0–X2 is decoded to M100–M107.
- If S = 3, M103 (the third digit starting from M100) = ON.
- When the command is executed, M200 turns to OFF. The ones that are decoded and outputted act as usual.



Example 2

- When D is word device, the valid range of n is 0< **n** ≦4. If n = 0 or n > 4, the fault occurs.
- When n = 4, the maximum decoding will be 2^4 = 16 points.
- When M200 switches from OFF to ON, the content of D10 (b2–b0) is decoded to D20 (b7–b0). The unused digits (b15–b8) of D20 become 0.
- The lower 3 digits of D10 are decoded and saved in the lower 8 digits of D20, the upper 8 digits are 0.
- When the command is executed, M200 turns to OFF. The ones that are decoded and outputted act as usual.



API					
42	D	ENCO	P	S D n	Encoder

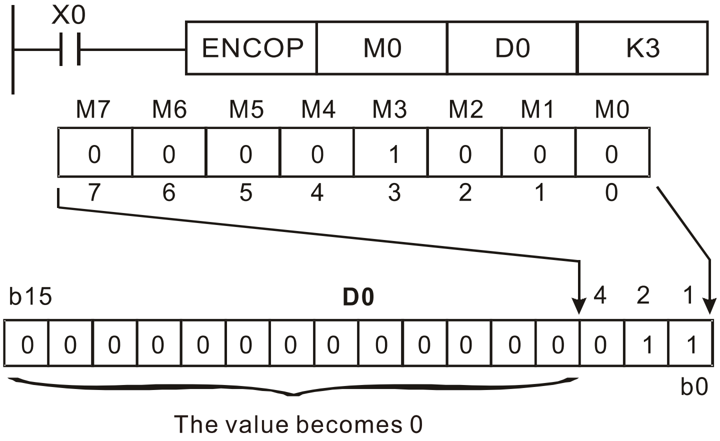
	Bit device			Word device								16-bit command (7 STEP)
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D	ENCO: Continuous execution type; ENCOP: Pulse execution type
S	*	*	*						*	*	*	32-bit command (13 STEP)
D							*	*	*	*	*	DENCO: Continuous execution type; DENCOP: Pulse execution type
n				*	*							
Notes on operand usage: none												Flag signal: none

Explanation

- S: Encoding source device. D: Device that saves the encoding result. n: Length of encoding bit.
- Encodes the data of lower “2^n” bit length from encoding source device S, and saves the encoding result in D.
- If multiple digits of encoding source device are 1, the command will process the first digit starting from high digit.
- This command usually uses pulse execution type command (ENCOP).
- When S is the bit device, n = 1–8, when S is the word device, n = 1–4.

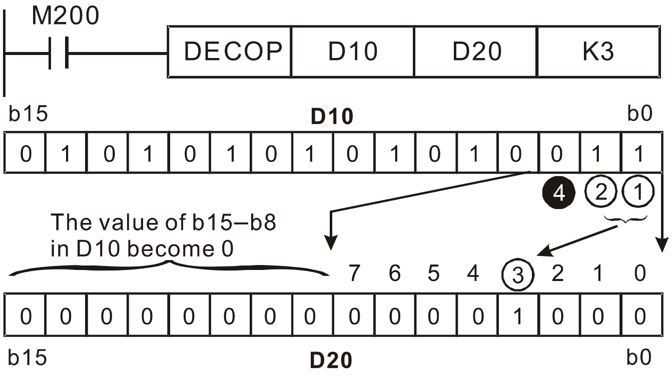
Example 1

- When S is the bit device, the valid range of n is 0< **n** ≤ 8. If n = 0 or n > 8, a fault will occur.
- When n = 8, the maximum decoding will be 2^8 = 256 points.
- When X0 switches from OFF to ON, the content of 2^3 digit (M0–M7) is encoded and saved in the lower 3 digits (b2–b0). The unused digits (b15–b3) in D0 become 0.
- When the command is executed, X0 turns to OFF. The data in D is unchanged.



Example 2

- When S is word device, the valid range of n is 0< **n** ≤ 4. If n = 0 or n > 4, the fault occurs.
- When n = 4, the maximum decoding will be 2^4 = 16 points.
- When X0 switches from OFF to ON, 2^3 digit data of D10 (b0–b7) is encoded and saved in the lower 3 digits (b2–b0) of D20. The unused digits (b15–b3) of D20 become 0. (b8–b15 in D10 are invalid data)
- When the command is executed, X0 turns to OFF. The data in D is unchanged.



API 43	D	SUM	P	(S) (D)	ON bit number

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*	*	*	*	*	*	*
D									*	*	*

Notes on operand usage: none

16-bit command (5 STEP)			
SUM	Continuous execution type	SUMP	Pulse execution type

32-bit command (9 STEP)			
DSUM	Continuous execution type	DSUMP	Pulse execution type

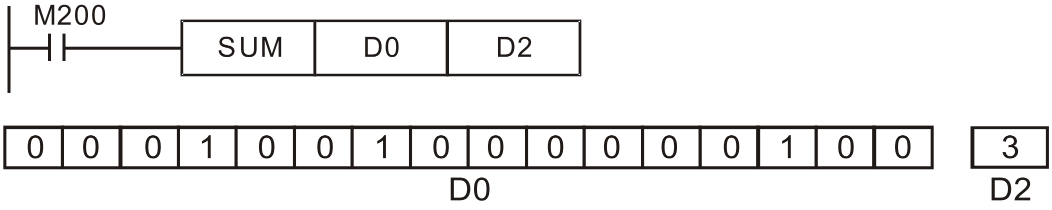
Flag signal: M1020

Explanation

- (S): Source device. (D): Destination of saving counter values.
- The total amount of all digits that is “1” in S will be saved in D.
- D will use 2 registers when use the 32-bit command.
- Arithmetic elements S and D use F device, and can only use 16-bit command.
- If there is no bit is ON, the flag signal M1020 will be ON.

Example

- When M200 = ON, the total amount of content “1” digit in D0’s 16-bit command will be saved in D2.



API 44	D	**BON**	P	S D n	ON bit judgement

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				∗	∗	∗	∗	∗	∗	∗	∗
D		∗	∗						∗	∗	∗
n				∗	∗						

Notes on operand usage: none

16-bit command (7 STEP)

BON	Continuous execution type	BONP	Pulse execution type

32-bit command (9 STEP)

DBON	Continuous execution type	DBONP	Pulse execution type

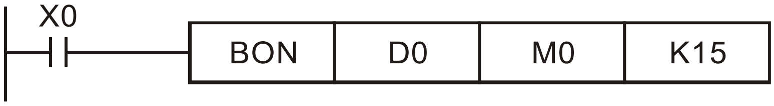
Flag signal: none

Explanation

- S: Source device. D: Destination of saving judging result. n: assign judged digit (numbering from 0)
- The status of specific digit from source device is shown on target position.
- Arithmetic element S uses F device, and can only use the 16-bit command.
- The valid range of arithmetic element n: n = 0–15 (16-bit), n = 0–31 (32-bit).

Example

- When X0 = ON, if the 15th digit of D0 is “1”, M0 is ON. If it is “0”, M0 is OFF.
- When X0 turns to OFF, M0 remains previous status.



b15															b0	
0	0	0	1	0	0	1	0	0	0	0	0	0	1	0	0	M0=Off

D0

b15															b0	
1	0	0	1	0	0	1	0	0	0	0	0	0	1	0	0	M0=On

D0

API 49	D	FLT	P	S D	BIN whole number → binary decimal transformation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S		*	*						*	*	*
D		*	*						*	*	*

Notes on operand usage: Please refer to the function specifications table for each device in series for the scope of device usage
The operand D will occupy 2 consecutive points

16-bit command

FLT	Continuous execution type	FLTP	Pulse execution type

32-bit command (9steps)

DFLT	Continuous execution type	DFLTP	Pulse execution type

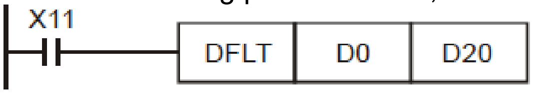
Flag signal: none

Explanation

- **S**: Transformation source device. **D**: Device storing transformation results.
- Transforms BIN whole number into a binary decimal value.

Example

- When X11 is ON, converts the whole number of values corresponding to D0 and D1 into floating point numbers, which are placed in D20 and D21.



API 110	D	ECMP	P	S1 S2 D	Comparison of binary floating point numbers

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
D											*

Notes on operand usage:
The operand D occupies three consecutive points
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (13 STEP)

DECMP	Continuous execution type	DECMP P	Pulse execution type

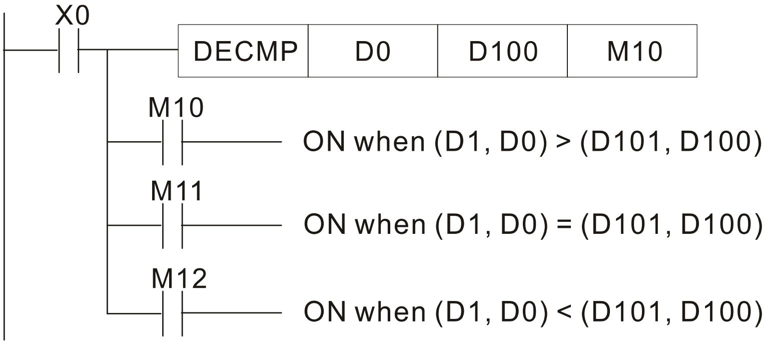
Flag signal: none

Explanation

- **S$_1$**: Comparison of binary floating point numbers value 1. **S$_2$**: Comparison of binary floating point numbers value 2. **D**: Results of comparison, occupies 3 consecutive points.
- When binary floating point number 1 is compared with comparative binary floating point number 2, the result of comparison (>, =, <) will be expressed in **D**.
- **If the source operand S$_1$** or **S$_2$** designates a constant K or H, the command will transform the constant to a binary floating-point number for the purpose of comparison.

Example

- When the designated device is M10, it will automatically occupy M10–M12.
- When X0 = ON, the DECMP command executes, and one of M10–M12 will be ON. When X0 = OFF, the DECMP command will not execute, and M10–M12 will remain in the X0 = OFF state.
- If results in the form of ≥, ≤, or ≠ are needed, they can be obtained by series and parallel connection of M10–M12.
- Please use the RST or ZRST command to clear the result.


X0
DECMP
D0
D100
M10
M10
ON when (D1, D0) > (D101, D100)
M11
ON when (D1, D0) = (D101, D100)
M12
ON when (D1, D0) < (D101, D100)

API 111	D	EZCP	P	S1 S2 S D	Comparison of binary floating point number range

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
S				*	*						*
D		*	*								

Notes on operand usage:
The operand D occupies three consecutive points
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (17 STEP)

DEZCP	Continuous execution type	DEZCP P	Pulse execution type

Flag signal: none

Explanation

- **S_1**: Lower limit of binary floating point number in range comparison. **S_2**: Upper limit of binary floating point number in range comparison. **S**: Comparison of binary floating point numerical values. **D**: Results of comparison, occupies 3 consecutive points.

- Comparison of binary floating point numerical value **S** with binary floating point number lower limit value **S_1** and binary floating point number upper limit value **S_2**; the results of comparison are expressed in **D**.

- **If the source operand S_1** or **S_2** designates a constant K or H, the command will transform the constant to a binary floating-point number for the purpose of comparison.

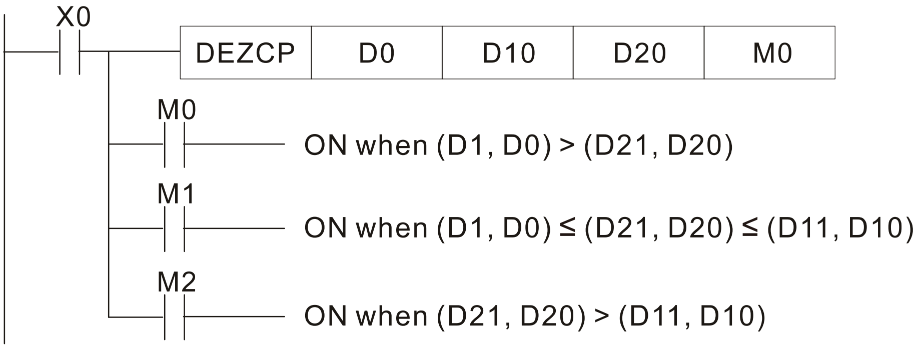
- When the lower limit binary floating point number **S_1** is greater than the upper limit binary floating point number **S_2**, a command will be issued to perform comparison with the upper and lower limits using the binary floating point number lower limit value **S_1**.

Example

- When the designated device is M0, it will automatically occupy M0–M2.

- When X0 = ON, the DEZCP command will be executed, and one of M0–M2 will be ON. When X0 = OFF, the EZCP command will not execute, and M0–M2 will continue in the X0 = OFF state.

- Please use the RST or ZRST command to clear the result.


X0
DEZCP
D0
D10
D20
M0
M0
ON when (D1, D0) > (D21, D20)
M1
ON when (D1, D0) ≤ (D21, D20) ≤ (D11, D10)
M2
ON when (D21, D20) > (D11, D10)

API 116	D	RAD	P	S D	Angle → Radian

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

—	—	—	—

32-bit command (9 STEP)

DRAD	Continuous execution type	DRADP	Pulse execution type

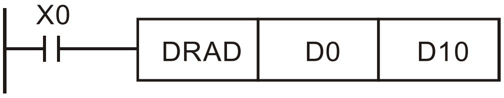
Flag signal: none

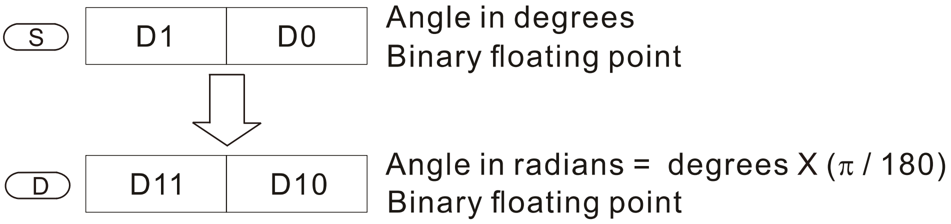
Explanation

- **S**: data source (angle). **D**: result of transformation (radian).
- Uses the following formula to convert angles to radians.
- Radian = Angle × (π/180)

Example

- When X0 = ON, the angle of the designated binary floating point number (D1, D0) will be converted to radians and stored in (D11, D10), with the content consisting of a binary floating point number.





API					
117	D	**DEG**	P	Ⓢ Ⓓ	Radian → Angle

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DDEG	Continuous execution type	DDEGP	Pulse execution type

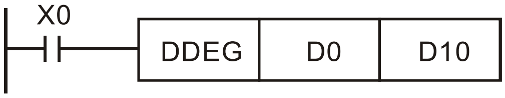
Flag signal: none

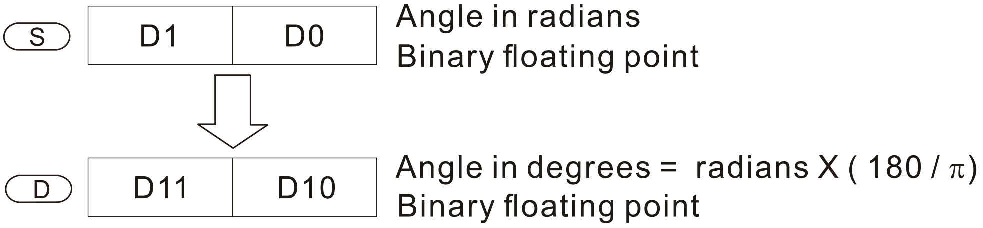
Explanation

- **S**: data source (radian). **D**: results of transformation (angle).
- Uses the following formula to convert radians to an angle.
- Angle = Radian × (180/π)

Example

- When X0 = ON, angle of the designated binary floating point number (D1, D0) in radians will be converted to an angle and stored in (D11, D10), with the content consisting of a binary floating point number.





API					
120	D	**EADD**	P	(S1) (S2) (D)	Adding binary floating point numbers

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DEADD	Continuous execution type	DEADDP	Pulse execution type

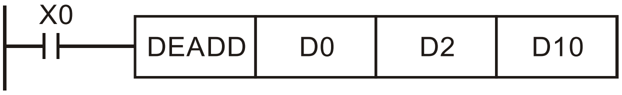
Flag signal: none

Explanation

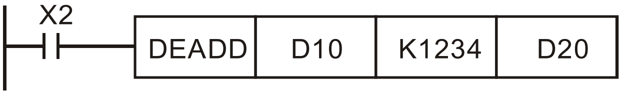
- **S**$_1$: augend. **S**$_2$: addend. **D**: sum.
- When the content of the register designated by **S**$_2$ is added to the content of the register designated by **S**$_1$, and the result is stored in the register designated by **D**. Addition is performed entirely using binary floating-point numbers.
- **If the source operand S**$_1$ or **S**$_2$ designates a constant K or H, the command will transform that constant into a binary floating point number for use in addition.
- **In the situation when S**$_1$ and **S**$_2$ designate identical register numbers, if a "continuous execution" command is employed, when conditional contact is ON, the register will perform addition once during each scan. Pulse execution type commands (DEADDP) are generally used under ordinary circumstances.

Example

- When X0 = ON, a binary floating point number (D1, D0) will be added to a binary floating point number (D3, D2), and the results stored in (D11, D10).



- When X2 = ON, a binary floating point number (D11, D10) will be added to K1234 (which has been automatically converted to a binary floating-point number), and the results stored in (D21, D20).



API 121	D	ESUB	P	S_1 S_2 D	Subtraction of binary floating point numbers

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

—	—	—	—

32-bit command (13 STEP)

DESUB	Continuous execution type	DESUBP	Pulse execution type

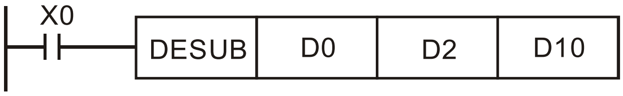
Flag signal: none

Explanation

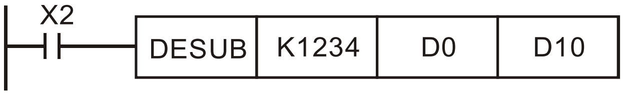
- S_1: minuend. S_2: subtrahend. **D**: difference.
- When the content of the register designated by S_2 is subtracted from the content of the register designated by S_1, the difference will be stored in the register designated by **D**; subtraction is performed entirely using binary floating-point numbers.
- **If the source operand** S_1 or S_2 designates a constant K or H, the command will transform that constant into a binary floating point number for use in subtraction.
- **In the situation when** S_1 and S_2 designate identical register numbers, if a "continuous execution" command is employed, when conditional contact is ON, the register will perform addition once during each scan. Pulse execution type commands (DESUBP) are generally used under ordinary circumstances.

Example

- When X0 = ON, a binary floating point number (D1, D0) will be subtracted to a binary floating point number (D3, D2), and the results stored in (D11, D10).



- When X2 = ON, the binary floating point number (D1, D0) will be subtracted from K1234 (which has been automatically converted to a binary floating-point number), and the results stored in (D11, D10).



API					
122	D	EMUL	P	S1 S2 D	Multiplication of binary floating point numbers

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (13 STEP)

DEMUL	Continuous execution type	DEMULP	Pulse execution type

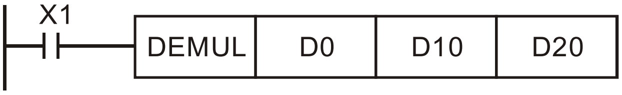
Flag signal: none

Explanation

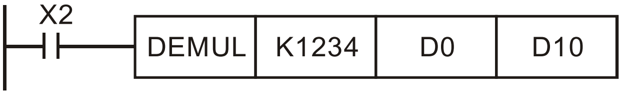
- S_1: multiplicand. S_2: multiplier. **D**: product.
- When the content of the register designated by S_1 is multiplied by the content of the register designated by S_2, the product will be stored in the register designated by **D**; multiplication is performed entirely using binary floating-point numbers.
- **If the source operand S_1** or S_2 designates a constant K or H, the command will transform that constant into a binary floating point number for use in multiplication.
- **In the situation when S_1** and S_2 designate identical register numbers, if a "continuous execution" command is employed, when conditional contact is On, the register will perform multiplication once during each scan. Pulse execution type commands (DEMULP) are generally used under ordinary circumstances.

Example

- When X1 = ON, the binary floating point number (D1, D0) will be multiplied by the binary floating point number (D11, D10), and the product will be stored in the register designated by (D21, D20).



- When X2 = ON, the binary floating point number (D1, D0) will be multiplied from K1234 (which has been automatically converted to a binary floating-point number), and the results stored in (D11, D10).



API 123	D	EDIV	P	S1 S2 D	Division of binary floating point numbers

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

—	—	—	—

32-bit command (13 STEP)

DEDIV	Continuous execution type	DEDIVP	Pulse execution type

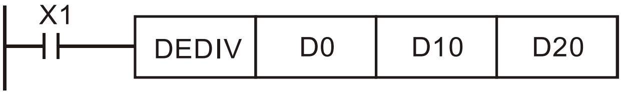
Flag signal: none

Explanation

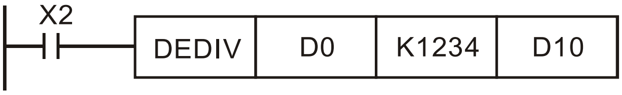
- **S_1**: dividend. **S_2**: divisor. **D**: quotient and remainder.
- When the content of the register designated by **S_1** is divided by the content of the register designated by **S_2**, the quotient will be stored in the register designated by **D**; division is performed entirely using binary floating-point numbers.
- **If the source operand S_1** or **S_2** designates a constant K or H, the command will transform that constant into a binary floating point number for use in division.

Example

- When X1 = ON, the binary floating point number (D1, D0) will be divided by the binary floating point number (D11, D10), and the quotient stored in the register designated by (D21, D20).



- When X2 = ON, the binary floating point number (D1, D0) will be divided by K1,234 (which has been automatically converted to a binary floating-point number), and the results stored in (D11, D10).



API 124	D	EXP	P	S D	Binary floating point number obtain exponent

	Bit device			Word device						
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DEXP	Continuous execution type	DEXPP	Pulse execution type

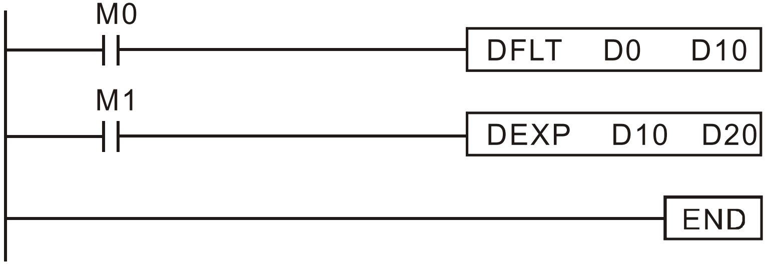
Flag signal: none

Explanation

- **S**: operation source device. **D**: operation results device.
- Taking e = 2.71828 as a base, **S** is the exponent in the EXP operation.
- [**D** +1，**D**] = EXP[**S +1**，**S**]
- Valid regardless of whether the content of **S** has a positive or negative value. The designated register D must have a 32-bit data format. This operation is performed using floating-point numbers, and **S** must therefore be converted to a floating point number.
- Content of operand **D** = e^{S} ; e = 2.71828, **S** is the designated source data

Example

- When M0 is ON, the value of (D1, D0) will be converted to a binary floating point number, which will be stored in register (D11, D10).
- When M1 is ON, the EXP operation is performed on the exponent of (D11, D10); its value is a binary floating point number stored in register (D21, D20).



API 125	D	LN	P	Ⓢ Ⓓ	Binary floating point number obtain logarithm

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

—	—	—	—

32-bit command (9 STEP)

DLN	Continuous execution type	DLNP	Pulse execution type

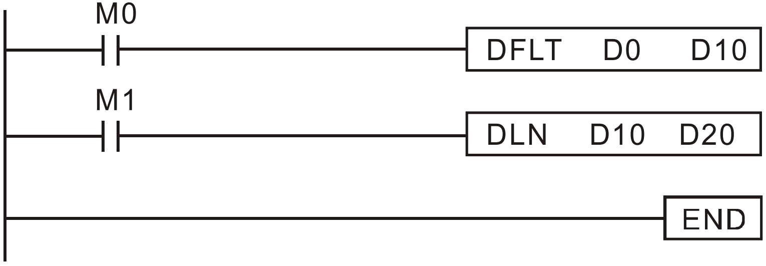
Flag signal: none

Explanation

- **S**: operation source device. **D**: operation results device.
- Taking e = 2.71828 as a base, **S** is the exponent in the EXP operation.
- [**D** +1，**D**] = EXP[**S +1**，**S**]
- Valid regardless of whether the content of **S** has a positive or negative value. The designated register D must have a 32-bit data format. This operation is performed using floating-point numbers, and **S** must therefore be converted to a floating point number.
- Content of operand **D** = e^{S} ; e = 2.71828，**S** is the designated source data

Example

- When M0 is ON, the value of (D1, D0) will be converted to a binary floating point number, which will be stored in register (D11, D10).
- When M1 is ON, the EXP operation is performed on the exponent of (D11, D10); its value is a binary floating point number stored in register (D21, D20).



API					
127	D	**ESQR**	P	(S) (D)	Binary floating point number find square root

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DESQR	Continuous execution type	DESQRP	Pulse execution type

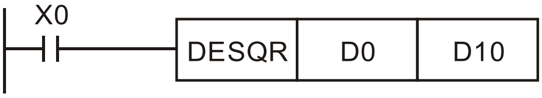
Flag signal: none

Explanation

- **S**: source device for which square root is desired **D**: result of finding square root.
- When the square root is taken of the content of the register designated by **S**, the result is temporarily stored in the register designated by **D**. Taking square roots is performed entirely using binary floating-point numbers.
- If the source operand **S** refers to a constant K or H, the command will transform that constant into a binary floating point number for use in the operation.

Example

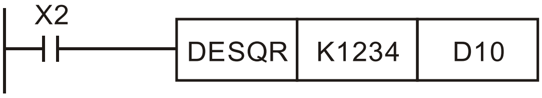
- When X0 = ON, the square root is taken of the binary floating point number (D1, D0), and the result is stored in the register designated by (D11, D10).



$$\sqrt{(D1 \cdot D0)} \longrightarrow (D11 \cdot D10)$$

Binary floating point   Binary floating point

- When X2 = ON, the square root is taken of K1,234 (which has been automatically converted to a binary floating-point number), and the results stored in (D11, D10).



API					
129	D	INT	P	S D	Binary floating point number → BIN whole number transformation

	Bit device			Word device								16-bit command			
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D	INT	Continuous execution type	INTP	Pulse execution type
S											*	32-bit command (9 STEP)			
D											*	DINT	Continuous execution type	DINTP	Pulse execution type

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

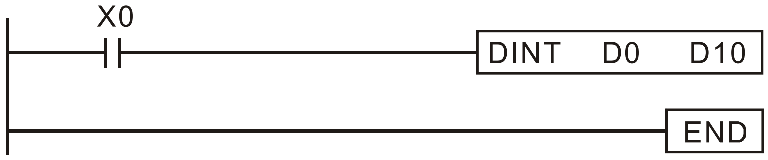
Flag signal: none

Explanation

- **S**: the source device to be transformed. **D**: results of transformation.
- The content of the register designated by **S** is transformed from a binary floating point number format into a BIN whole number, and is temporarily stored in **D**. The BIN whole number floating point number will be discarded.
- The action of this command is the opposite of that of command API 49 (FLT).

Example

- When X0 = ON, the binary floating point number (D1, D0) is transformed into a BIN whole number, and the result is stored in (D10); the BIN whole number floating point number will be discarded.



API					
130	**D**	**SIN**	**P**	S D	Binary floating point number SIN operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

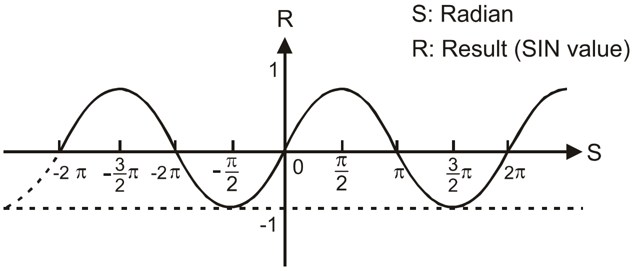
16-bit command			
–	–	–	–
32-bit command (9 STEP)			
DSIN	Continuous execution type	DSINP	Pulse execution type

Flag signal: none

Explanation

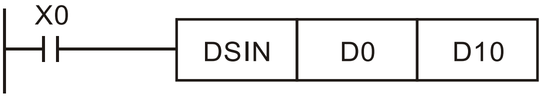
- **S**: the designated source value. **D**: the SIN value result.
- **S** is the designated source in radians.
- The value in radians (RAD) is equal to (angle ×π/180).
- The SIN obtained from the source value designated by **S** is stored in **D**.

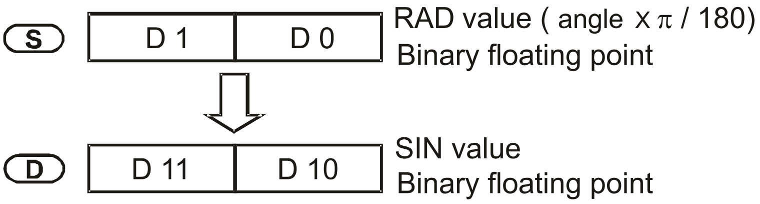
The following figure displays the relationship between the arc and SIN results:



Example

- When X0 = ON, the SIN value of the designated binary floating point number (D1, D0) in radians (RAD) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API					
131	D	**COS**	P	S D	Binary floating point number COS operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

—	—	—	—

32-bit command (9 STEP)

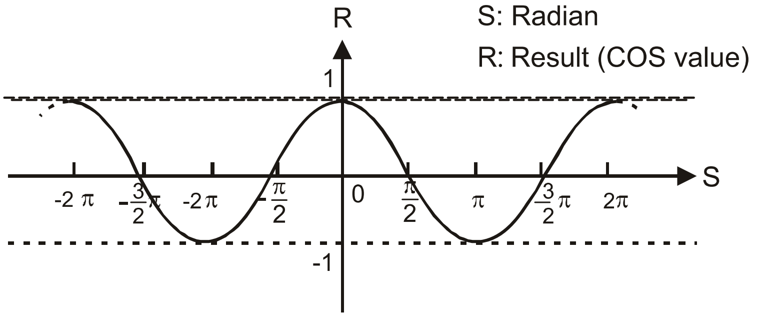
DCOS	Continuous execution type	DCOSP	Pulse execution type

Flag signal: none

Explanation

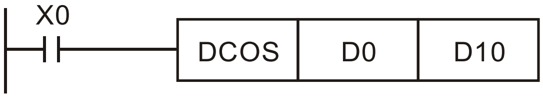
- **S**: the designated source value. **D**: the COS value result.
- The source designated by S can be given as radians or an angle; this is decided by flag M1018.
- When M1018 = OFF, the operation is in radians mode, where the radians (RAD) value is equal to (angle × π/180).
- When M1018 = ON, the operation is in the angle mode, where the angular range is 0° ≤ angle < 360°.
- When calculation results yield 0, M1020 = ON.
- The COS obtained from the source value designated by **S** is stored in **D**.

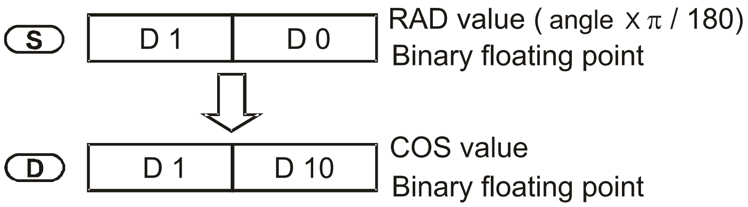
The following figure displays the relationship between the arc and SIN results:



Example

- When X0 = ON, the COS value of the designated binary floating point number (D1, D0) in radians will be stored in (D11, D10), with the content consisting of a binary floating point number.





API					
132	D	TAN	P	S D	Binary floating point number TAN operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

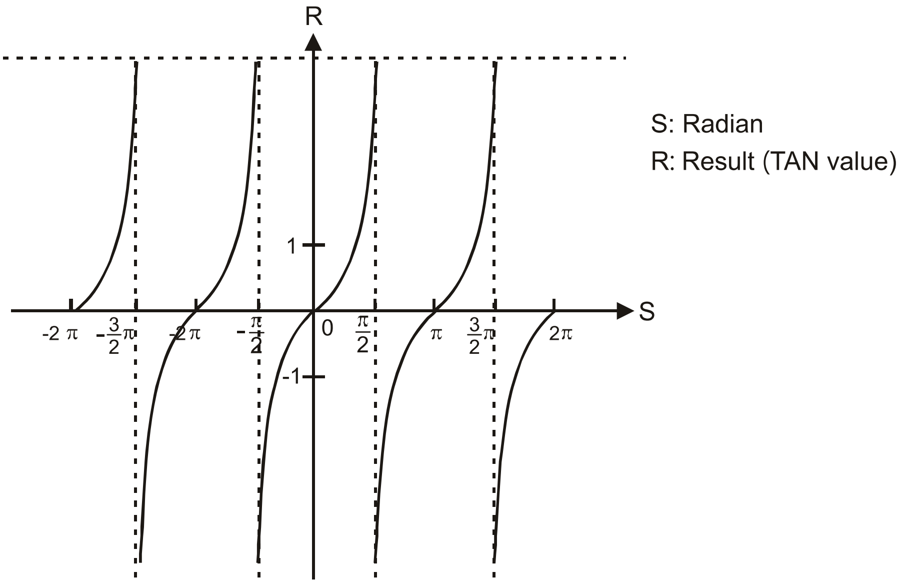
DTAN	Continuous execution type	DTANP	Pulse execution type

Flag signal: none

Explanation

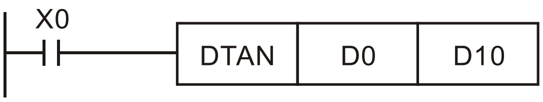
- **S**: the designated source value. **D**: the TAN value result.
- The source designated by **S** can be given as radians or an angle; this is decided by flag M1018.
- When M1018 = OFF, the operation is in radians mode, where the radians (RAD) value is equal to (angle ×π/180).
- When M1018 = ON, the operation is in the angle mode, where the angular range is 0° ≤ angle < 360°.
- When calculation results yield 0, M1020 = ON.
- The TAN obtained from the source value designated by **S** is stored in **D**.

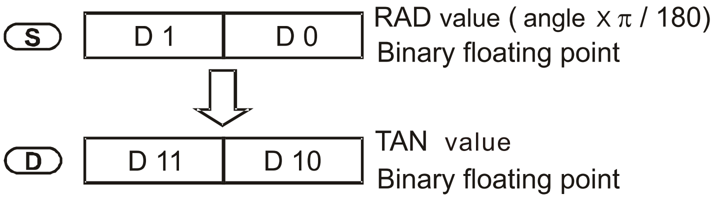
The following figure displays the relationship between the arc and SIN results:



Example

- When X0 = ON, the TAN value of the designated binary floating point number (D1, D0) in radians (RAD) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API 133	D	ASIN	P	S D	Binary floating point number ASIN operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command			
–	–	–	–

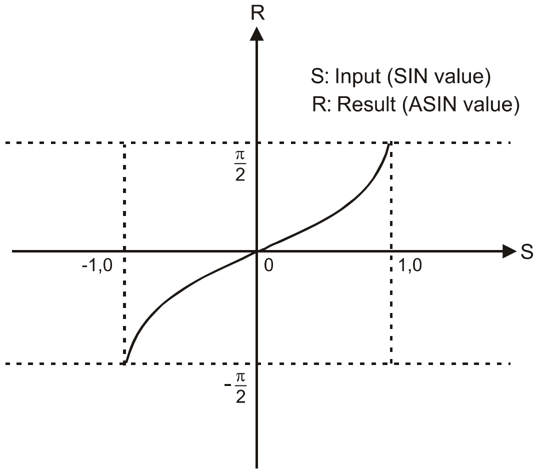
32-bit command (9 STEP)			
DASIN	Continuous execution type	DASINP	Pulse execution type

Flag signal: none

Explanation

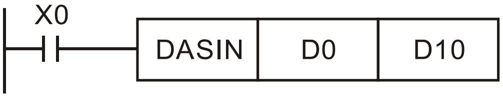
- **S**: the designated source (binary floating point number). **D**: the ASIN value result.
- ASIN value = $\sin^{-1}$

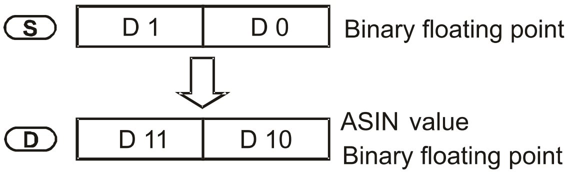
The figure below shows the relationship between input data and result:



Example

- When X0 = ON, the ASIN value obtained from the designated binary floating point number (D1, D0) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API 134	D	ACOS	P	S D	Binary floating point number ACOS operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

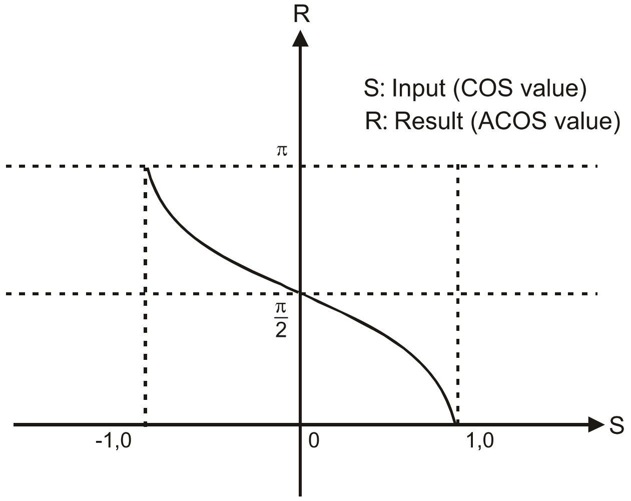
DACOS	Continuous execution type	DACOSP	Pulse execution type

Flag signal: none

Explanation

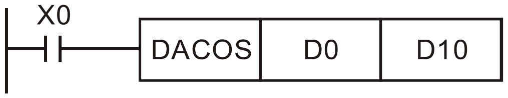
- **S**: the designated source (binary floating point number). **D**: the ACOS value result.
- ACOS value = $\cos^{-1}$

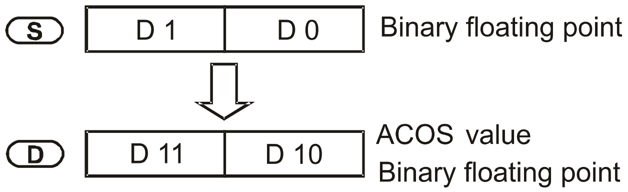
The figure below shows the relationship between input data and result:



Example

- When X0 = ON, the ACOS value obtained from the designated binary floating point number (D1, D0) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API					
135	D	ATAN	P	S D	Binary floating point number ATAN operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

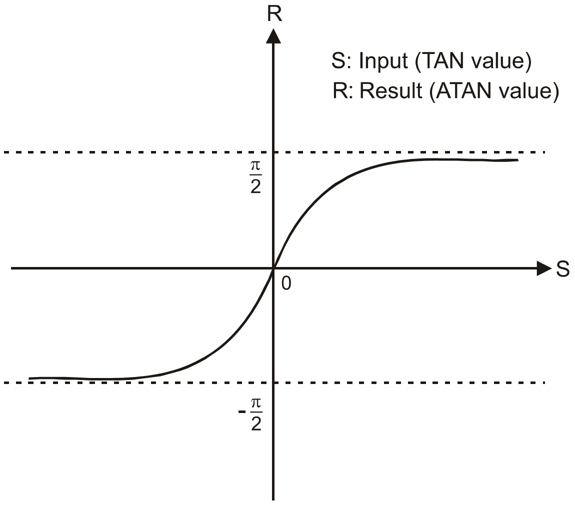
DATAN	Continuous execution type	DATANP	Pulse execution type

Flag signal: none

Explanation

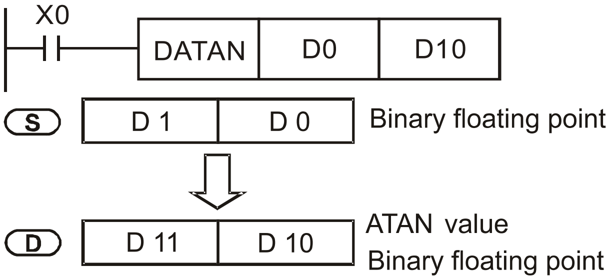
- **S**: the designated source (binary floating point number). **D**: the ATAN value result.
- ATAN value = $\tan^{-1}$

The figure below shows the relationship between input data and result:



Example

- When X0 = ON, the TAN value obtained from the designated binary floating point number (D1, D0) will be stored in (D11, D10), with the content consisting of a binary floating point number.



API					
136	D	SINH	P	S D	Binary floating point number SINH operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DSINH	Continuous execution type	DSINHP	Pulse execution type

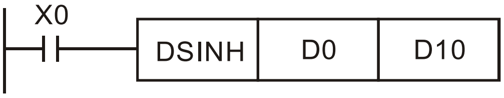
Flag signal: none

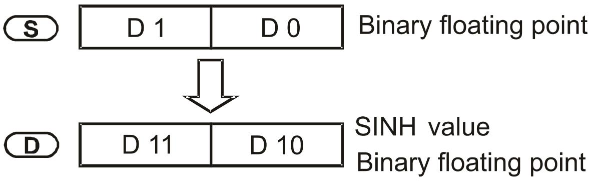
Explanation

- **S**: the designated source (binary floating point number). **D**: the SINH value result.
- SINH value = $(e^{s}-e^{-s})/2$

Example

- When X0 = ON, the SINH value obtained from the designated binary floating point number (D1, D0) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API 137	D	COSH	P	S D	Binary floating point number COSH operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DCOSH	Continuous execution type	DCOSHP	Pulse execution type

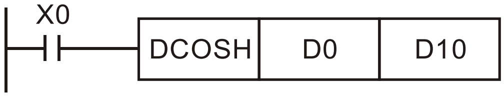
Flag signal: none

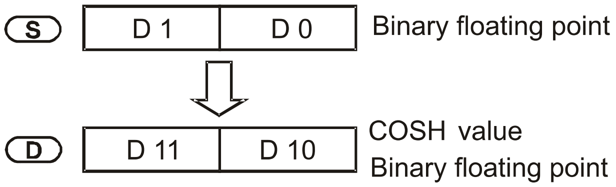
Explanation

- **S**: the designated source (binary floating point number). **D**: the COSH value result.
- COSH value = $(e^{s}+e^{-s})/2$

Example

- When X0 = ON, the COSH value obtained from the designated binary floating point number (D1, D0) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API					
138	D	TANH	P	S D	Binary floating point number TANH operation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*						*
D											*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

DTANH	Continuous execution type	DTANHP	Pulse execution type

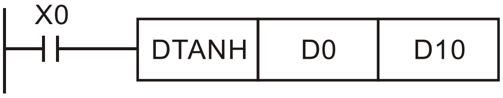
Flag signal: none

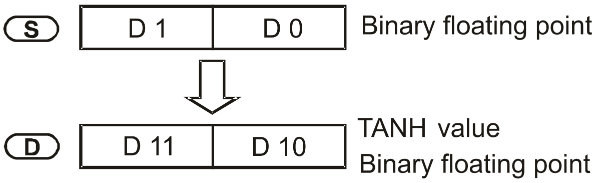
Explanation

- **S**: the designated source (binary floating point number). **D**: the TANH value result.
- tanh value = $(e^{s}-e^{-s})/(e^{s}+e^{-s})$

Example

- When X0 = ON, the TANH value obtained from the designated binary floating point number (D1, D0) will be stored in (D11, D10), with the content consisting of a binary floating point number.





API 147	D	SWAP	P	Ⓢ	Exchange the up/down 8 bits

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S						*	*	*	*	*	*

Notes on operand usage: none

16-bit command (3 STEP)

SWAP Continuous execution type SWAPP Pulse execution type

32-bit command (5 STEP)

DSWAP Continuous execution type DSWAPP Pulse execution type

Flag signal: none

Explanation

- Ⓢ: The device that going to exchange its up/down 8 bits.
- When using 16-bit command, the upper 8-bit and lower 8-bit exchange.
- When using 32-bit command, the contents of upper 8-bit and lower 8-bit of the 2 registers exchange.
- This command usually uses pulse execution type (SWAPP, DSWAPP)

API			
150	**MODRW** P	S1 S2 S3 S n	Modbus data read/write

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
S3				*	*						*
S											*
n				*	*						*

16-bit command (5 STEP)

MODRW	Continuous execution type	MODRWP	Pulse execution type

32-bit command

—	—	—	—

Flag signal: M1077 M1078 M1079

Explanation

- S1: online device address. S2: communications function code. S3: address of data to read/write. S: register for data to be read/written is stored. N: length of data to be read/written.
- COM1 must be defined as controlled by the PLC (set P9-31 = -12) before using this command, and the corresponding communications speed and format must also be set (set P09-01 and P09-04). S2: communications function code. Currently only supports the following function code; the remaining function code cannot be executed.

Function	Description
H 02	Input read
H 03	Read word
H 06	Write single word
H 0F	Write multiple coils
H10	Write single word

- After executing this command, M1077, M1078 and M1079 will be immediately changed to 0.
- As an example, when CP2000 must control another converter and PLC, if the converter has a station number of 10 and the PLC has a station number of 20, see the following example:

Control slave device converter

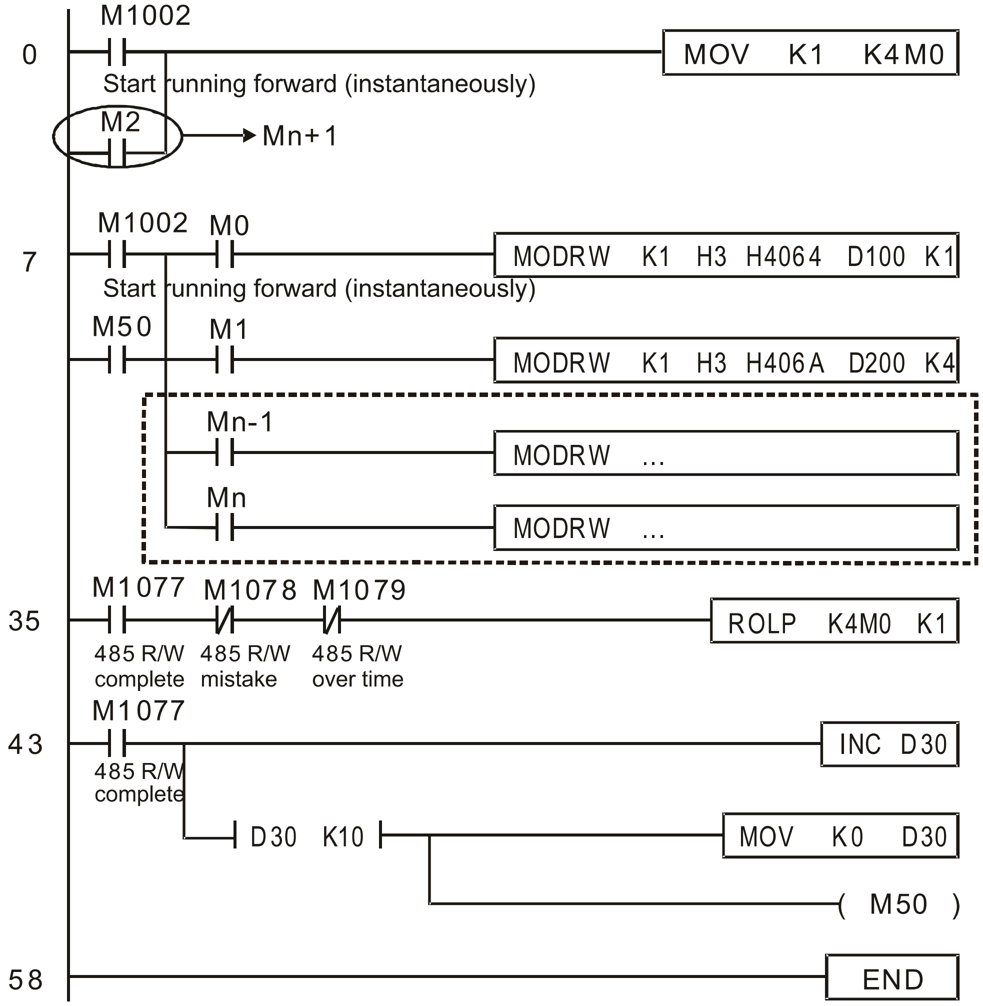
Serial No.	Example	MODRW command				
		S1	S2	S3	S4	n
		Node ID	Function code	Address	Register	Length
1	Reads 4 sets of data comprising the converter slave device parameters P01-00 to P01-03, and saves the read data in D0 to D3	K10	H3	H100	D0	K4
2	Reads 3 sets of data comprising the converter slave device addresses H2100 to H2102, and saves the read data in D5 to D7	K10	H3	H2100	D5	K3
3	Reads 3 sets of data comprising the converter slave device parameters P05-00 to P05-03, and writes the values as D10 to D12	K10	H10	H500	D10	K3
4	Writes 2 sets of data comprising the converter slave device addresses H2000 to H2001, and writes the values as D15 to D16	K10	H10	H2000	D15	K2

PLC controlling slave device

Serial No.	Example	MODRW command				
		S1	S2	S3	S4	n
		Node ID	Function code	Address	Register	Length:
1	Reads 4 sets of data comprising the PLC slave device's X0 to X3 state, and saves the read data in bits 0 to 3 of D0	K20	H2	H400	D0	K4
2	Reads 4 sets of data comprising the PLC slave device's Y0 to Y3 state, and saves the read data in bits 0 to 3 of D1	K20	H2	H500	D1	K4
3	Reads 4 sets of data comprising the PLC slave device's M0 to M3 state, and saves the read data in bits 0 to 3 of D2	K20	H2	H800	D2	K4
4	Reads 4 sets of data comprising the PLC slave device's T0 to T3 state, and saves the read data in bits 0 to 3 of D3	K20	H2	H600	D3	K4
5	Reads 4 sets of data comprising the PLC slave device's C0 to C3 state, and saves the read data in bits 0 to 3 of D4	K20	H2	HE00	D4	K4
6	Reads 4 sets of data comprising the PLC slave device's T0 to T3 count value, and saves the read data of D10 to D13	K20	H3	H600	D10	K4
7	Reads 4 sets of data comprising the PLC slave device's C0 to C3 count value, and saves the read data of D20 to D23	K20	H3	HE00	D20	K4
8	Reads 4 sets of data comprising the PLC slave device's D0 to D3 count value, and saves the read data of D30 to D33	K20	H3	H1000	D30	K4
9	Writes 4 sets of the PLC slave device's Y0 to Y3 state, and writes the values as bits 0 to 3 of D1	K20	HF	H500	D1	K4
10	Writes 4 sets of the PLC slave device's M0 to M3 state, and writes the values as bits 0 to 3 of D2	K20	HF	H800	D2	K4
11	Writes 4 sets of the PLC slave device's T0 to T3 state, and writes the values as bits 0 to 3 of D3	K20	HF	H600	D3	K4
12	Writes 4 sets of the PLC slave device's C0 to C3 state, and writes the values as bits 0 to 3 of D4	K20	HF	HE00	D4	K4
13	Writes 4 sets of the PLC slave device's T0 to T3 state, and writes the values of D10 to D13	K20	H10	H600	D10	K4
14	Writes 4 sets of the PLC slave device's C0 to C3 state, and writes the values of D20 to D23	K20	H10	HE00	D20	K4
15	Writes 4 sets of the PLC slave device's D0 to D3 state, and writes the values of D30 to D33	K20	H10	H1000	D30	K4

Example

- Will trigger M0 ON when the PLC begins to operate, and sends instruction to execute one MODRW command.
- After receiving the slave device's response, if the command is correct, it will execute one ROL command, which will cause M1 to be ON.
- After receiving the slave device's response, will trigger M50 = 1 after a delay of 10 PLC scanning cycles, and then execute one MODRW command.
- After again receiving the slave device's response, if the command is correct, it will execute one ROL command, and M2 will change to ON at this time (and M2 can be defined as a repeat of M); K4M0 will change to K1, and only M0 will remain 1. Transmission can proceed in a continuous cycle. If you wish to add a command, merely add the desired command in the empty frame, and change repeat M to Mn+1.



API					
160		**TCMP**	**P**	S1 S2 S3 S D	Comparison of calendar data

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*
S3				*	*	*	*	*	*	*	*
S									*	*	*
D		*	*								

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (11 STEP)

TCMP	Continuous execution type	TCMPP	Pulse execution type

32-bit command

–	–	–	–

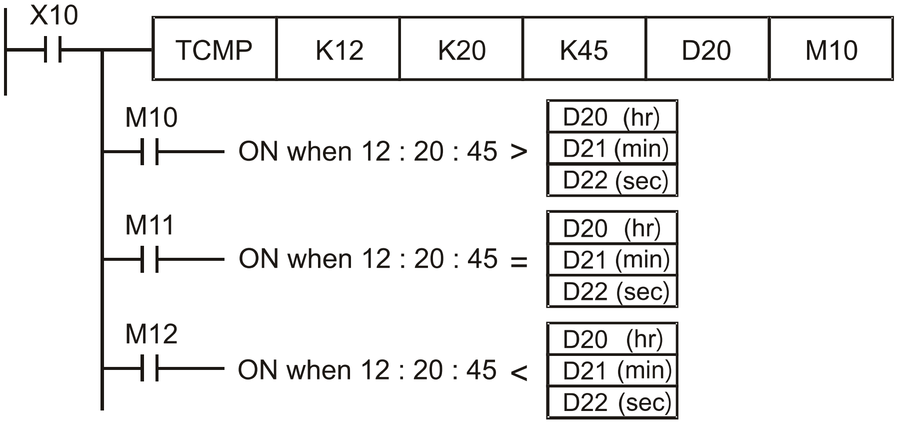
Flag signal: none

Explanation

- **S₁**: Sets the hours of the comparison time, setting range is "K0–K23." **S₂**: Sets the minutes of the comparison time, setting range is "K0–K59." **S₃**: Sets the seconds of the comparison time, setting range is "K0–K59." **S**: current calendar time. **D**: Results of comparison.
- Compares the time in hours, minutes, and seconds set in **S₁–S₃** with the current calendar time in hours, minutes, and seconds, with the results of comparison expressed in **D**.
- **S** The hour content of the current calendar time is "K0–K23." **S** +1 comprises the minutes of the current calendar time, and consists of "K0–K59." **S** +2 comprises the seconds of the current calendar time, and consists of "K0–K59."
- The current calendar time designated by **S** is usually compared using the TCMP command after using the TRD command to read the current calendar time. If the content value of **S** exceeds the range, this is considered an operating error, the command will not execute, and M1068 = ON.

Example

- When X10 = ON, the command will execute, and the current calendar time in D20–D22 will be compared with the preset value of 12:20:45; the results will be displayed in M10–M12. When X10 ON→OFF, the command will not be executed, but the ON/OFF status prior to M10–M12 will be maintained.
- If results in the form of ≥, ≤, or ≠ are needed, they can be obtained by series and parallel connection of M10–M12.



API				
161	**TZCP**	**P**	S1 S2 S D	Comparison of calendar data

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1									*	*	*
S2									*	*	*
S									*	*	*
D		*	*								

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (9 STEP)

TZCP	Continuous execution type	TZCPP	Pulse execution type

32-bit command

–	–	–	–

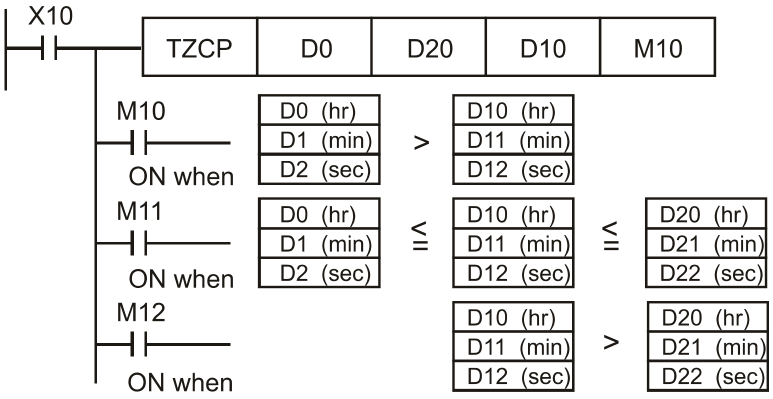
Flag signal: none

Explanation

- **S_1**: Sets the lower limit of the comparison time. **S_2**: Sets the upper limit of the comparison time. **S**: current calendar time. **D**: Results of comparison.
- Performs range comparison by comparing the hours, minutes, and seconds of the current calendar time designated by **S** with the lower limit of the comparison time set as **S_1** and the upper limit of the comparison time set as **S_2**, and expresses the results of comparison in **D**.
- **S_1** 、**S_1** +1 、**S_1** +2: Sets the hours, minutes, and seconds of the lower limit of the comparison time.
- **S_2** 、**S_2** +1 、**S_2** +2: Sets the hours, minutes, and seconds of the upper limit of the comparison time.
- **S** 、**S** +1 、**S** +2: The hours, minutes, and seconds of the current calendar time
- The D0 designated by the **S** listed in this program is usually obtained by comparison using the TZCP command after using the TRD command in advance to read the current calendar time. If the value of **S_1**, **S_2**, or **S** exceeds the range, this is considered an operating error, the command will not execute, and M1068 = ON.
- When the current time **S** is less than the lower limit value **S_1** and **S** is less than the upper limit value **S_2**, **D** will be ON. When the current time **S** is greater than the lower limit value **S_1** and **S** is greater than the upper limit value **S_2**, **D** +2 will be ON; **D** +1 will be ON under other conditions.

Example

- When X10 = ON, the TZCP command executes, and one of M10-M12 will be ON. When X10 = OFF, the TZCP command will not execute, and M10-M12 will remain in the X10 = OFF state.



API					
162		**TADD**	**P**	S1 S2 D	Calendar data addition

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1									*	*	*
S2									*	*	*
D									*	*	*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (7 STEP)

TADD	Continuous execution type	TADDP	Pulse execution type

32-bit command

–	–	–	–

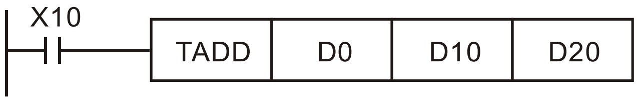
- Flag signal: M1020 Zero flag
  M1022 Carry flag
  M1068 Calendar error

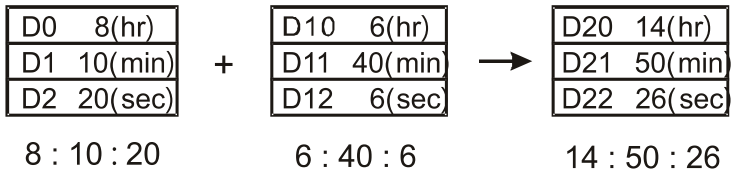
Explanation

- **S₁**: time addend. **S₂**: time augend. **D**: time sum.
- The calendar data in hours, minutes, and seconds designated by **S₂** is added to the calendar data in hours, minutes, and seconds designated by **S₁**, and the result is stored as hours, minutes, and seconds in the register designated by **D**.
- If the value of **S₁** or **S₂** exceeds the range, this is considered an operating error, the command will not execute, M1067, M1068 = ON, and D1067 will record the error code 0E1A (HEX).
- If the results of addition are greater than or equal to 24 hours, carry flag M1022 = ON, and **D** will display the results of addition minus 24 hours.
- If the results of addition are equal to 0 (0 hours, 0 minutes, 0 seconds), zero flag M1020 = ON.

Example

- When X10 = ON, the TADD command will be executed, and the calendar data in hours, minutes, and seconds designated by D0 to D2 will be added to the calendar data in hours, minutes, and seconds designated by D10 to D12, and the results are stored as a total number of hours, minutes, and seconds in the registers designated by D20 to D22.





API				
163		**TSUB** P	S1 S2 D	Calendar data subtraction

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1									*	*	*
S2									*	*	*
D									*	*	*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (7 STEP)

TSUB	Continuous execution type	TSUBP	Pulse execution type

32-bit command

–	–	–	–

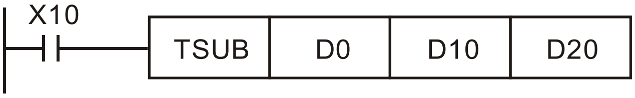
- Flag signal: M1020 Zero flag
  M1022 Carry flag
  M1068 Calendar error

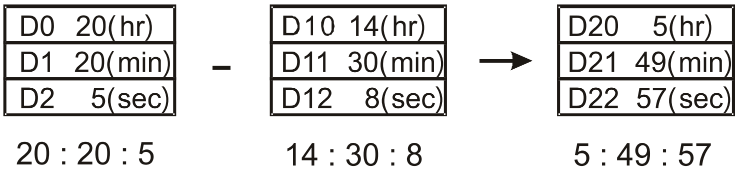
Explanation

- **S₁**: time minuend. **S₂**: time augend. **D**: time sum.
- Subtracts the calendar data in hours, minutes, and seconds designated by **S₂** from the calendar data in hours, minutes, and seconds designated by **S₁**, and the result is temporarily stored as hours, minutes, and seconds in the register designated by **D**.
- If the value of **S₁** or **S₂** exceeds the range, this is considered an operating error, the command will not execute, M1067, M1068 = ON, and D1067 will record the error code 0E1A (HEX).
- If subtraction results in a negative number, borrow flag M1021 = ON, and the result of that negative number plus 24 hours will be displayed in the register designated by **D**.
- If the results of subtraction are equal to 0 (0 hours, 0 minutes, 0 seconds), zero flag M1020 = ON.

Example

- When X10 = ON, the TADD command will be executed, and the calendar data in hours, minutes, and seconds designated by D10 to D12 will be subtracted from the calendar data in hours, minutes, and seconds designated by D0 to D2, and the results are stored as a total number of hours, minutes, and seconds in the registers designated by D20 to D22.





API		TRD			
166			P	Ⓓ	Calendar data read

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D									*	*	*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (3 STEP)

TRD	Continuous execution type	TRDP	Pulse execution type

32-bit command

–	–	–	–

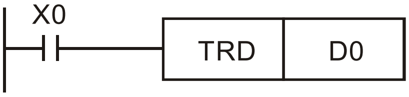
- Flag signal: none

Explanation

- **S**$_1$: time minuend. **S**$_2$: time augend. **D**: time sum.
- **D**: device used to store the current calendar time after reading.
- The EH/EH2/SV/EH3/SV2/SA/SX/SC main units have a built-in calendar clock, and the clock provides seven sets of data comprising year, week, month, day, hour, minute, and second stored in D1063 to D1069. The TRD command function allows program designers to directly read the current calendar time into the designated seven registers.
- D1063 only reads the two right digits of the Western calendar year.

Example

- When X0 = ON, the current calendar time is read into the designated registers D0 to D6.
- In D1064, 1 indicates Monday, 2 indicates Tuesday, and so on, with and 7 indicating Sunday.



Special D	Item	Content		General D	Item
D1063	Year (Western)	00–99	→	D0	Year (Western)
D1064	Weeks	1–7	→	D1	Weeks
D1065	Month	1–12	→	D2	Month
D1066	Day	1–31	→	D3	Day
D1067	Hour	0–23	→	D4	Hour
D1068	Minute	0–59	→	D5	Minute
D1069	Second	0–59	→	D6	Second

API					
170	D	**GRY**	P	Ⓢ Ⓓ	BIN→GRAY code transformation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				∗	∗	∗	∗	∗	∗	∗	∗
D							∗	∗	∗	∗	∗

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

GRY	Continuous execution type	GRYP	Pulse execution type

32-bit command (9 STEP)

DGRY	Continuous execution type	DGRYP	Pulse execution type

- Flag signal: none

Explanation

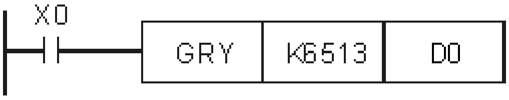
- **S**: source device. **D**: device storing GRAY code.
- Transforms the content value (BIN value) of the device designated by **S** to GRAY code, which is stored in the device designated by **D**.
- The valid range of **S** is as shown below; if this range is exceeded, it will be considered an error, and the command will not execute.

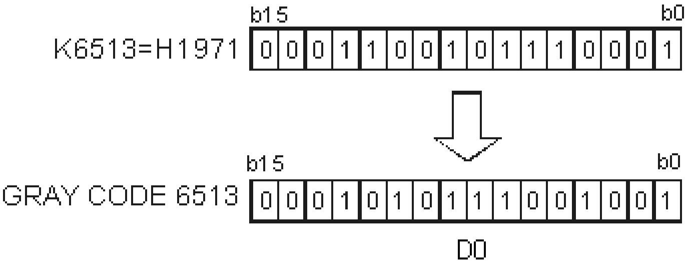
16-bit command: 0–32,767

- 32-bit command: 0–2,147,483,647

Example

- When X0 = ON, the constant K6513 will be transformed to GRAY code and stored in D0.





API 171	D	GBIN	P	Ⓢ Ⓓ	GRAY code →BIN transformation

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S				*	*	*	*	*	*	*	*
D							*	*	*	*	*

Notes on operand usage:
Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

GBIN	Continuous execution type	GBINP	Pulse execution type

32-bit command (9 STEP)

DGBIN	Continuous execution type	DGBINP	Pulse execution type

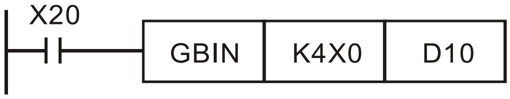
- Flag signal: none

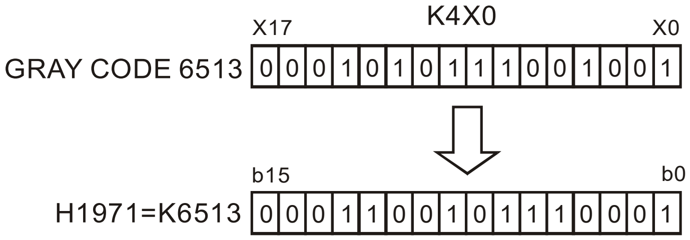
Explanation

- **S**: source device used to store GRAY code. **D**: device used to store BIN value after transformation.
- The GRAY code corresponding to the value of the device designated by **S** is transformed into a BIN value, which is stored in the device designated by **D**.
- This command will transform the value of the absolute position encoder connected with the PLC's input and (this encoder usually has an output value in the form of GRAY code) into a BIN value, which is stored in the designated register.
- The valid range of **S** is as shown below; if this range is exceeded, it will be considered an error, and the command will not execute.
- 16-bit command: 0–32,767
- 32-bit command: 0–2,147,483,647

Example

- When X20 = ON, the GRAY code of the absolute position encoder connected with input points X0 to X17 will be transformed into BIN value and stored in D10.





API 215–217	D	LD#	S1 S2	Contact form logical operation LD#

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				∗	∗	∗	∗	∗	∗	∗	∗
S2				∗	∗	∗	∗	∗	∗	∗	∗

Notes on operand usage: ＃：&、|、^

Please refer to the function specifications table for each device in series for the range of device usage

16-bit command (5 STEP)

LD#	Continuous execution type	–	–

32-bit command (9 STEP)

DLD#	Continuous execution type	–	–

Flag signal: none

Explanation

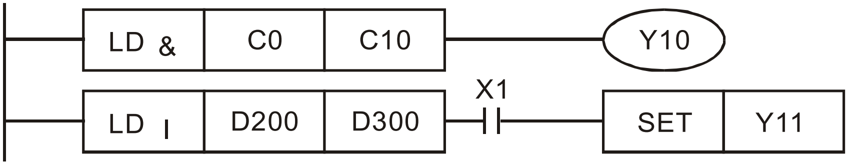
- **S_1**: data source device 1. **S_2**: data source device 2.
- This command performs comparison of the content of **S_1** and **S_2**; when the result of comparison is not 0, this command will be activated, but this command will not be activated when the result of comparison is 0.
- The LD#This command can be used while directly connected with the busbar

API No.	16-bit commands	32-bit commands	Conditions for activation	Conditions for inactivation
215	LD&	**D**LD&	**S_1** & **S_2** $\neq 0$	**S_1** & **S_2** $= 0$
216	LD|	**D**LD|	**S_1** | **S_2** $\neq 0$	**S_1** | **S_2** $= 0$
217	LD^	**D**LD^	**S_1** ^ **S_2** $\neq 0$	**S_1** ^ **S_2** $= 0$

- &: logical AND operation.
- |: logical OR operation.
- ^: logical XOR operation.

Example

- When the content of C0 and C10 is subjected to the logical AND operation, and the result is not equal to 0, Y10 = ON.
- When the content of D200 and D300 is subjected to the logical OR operation, and the result is not equal to 0, and X1 = ON, Y11 = ON and remains in that state.



API					
218–220	D	AND#		(S1) (S2)	Contact form logical operation AND#

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*

Notes on operand usage: # : & 、| 、^

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

AND#	Continuous execution type	–	–

32-bit command (9 STEP)

DAND#	Continuous execution type	–	–

Flag signal: none

Explanation

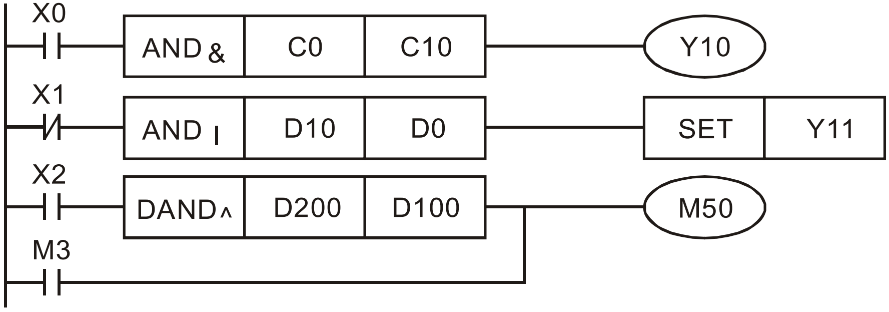
- **S₁**: data source device 1. **S₂**: data source device 2.
- This command performs comparison of the content of **S₁** and **S₂**; when the result of comparison is not 0, this command will be activated, but this command will not be activated when the result of comparison is 0.
- The AND# command is an operation command in series with the contact.

API No.	16-bit commands	32-bit commands	Conditions for activation	Conditions for inactivation
218	AND&	**D**AND&	S_1 & S_2 $\neq 0$	S_1 & S_2 $=0$
219	AND|	**D**AND|	S_1 | S_2 $\neq 0$	S_1 | S_2 $=0$
220	AND^	**D**AND^	S_1 ^ S_2 $\neq 0$	S_1 ^ S_2 $=0$

- &: logical AND operation.
- |: logical OR operation.
- ^: logical XOR operation.

Example

- When X0 = ON and the content of C0 and C10 is subjected to the logical AND operation, and the result is not equal to 0, Y10 = ON.
- When X1 = OFF and D10 and D0 is subjected to the logical OR operation, and the result is not equal to 0, Y11 = ON and remains in that state.
- When X2 = ON and the content of the 32-bit register D200 (D201) and 32-bit register D100 (D101) is subjected to the logical XOR operation, and the result is not equal to 0 or M3 = ON, M50 = ON.



API 221–223	D	**OR#**		S1 S2	Contact form logical operation OR#

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				＊	＊	＊	＊	＊	＊	＊	＊
S2				＊	＊	＊	＊	＊	＊	＊	＊

Notes on operand usage: # : &、|、^

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

OR#	Continuous execution type	–	–

32-bit command (9 STEP)

DOR#	Continuous execution type	–	–

Flag signal: none

Explanation

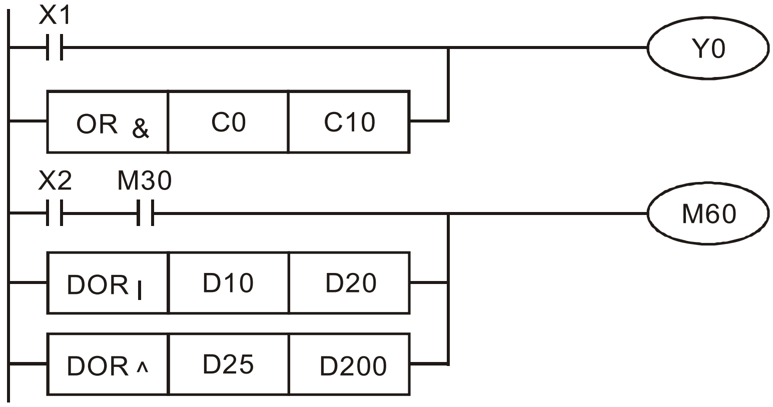
- **S₁**: data source device 1. **S₂**: data source device 2.
- This command performs comparison of the content of **S₁** and **S₂**; when the result of comparison is not 0, this command will be activated, but this command will not be activated when the result of comparison is 0.
- The OR# command is an operation command in series with the contact.

API No.	16-bit commands	32-bit commands	Conditions for activation	Conditions for inactivation
221	OR&	**D**OR&	**S₁** & **S₂** $\neq 0$	**S₁** & **S₂** $=0$
222	OR|	**D**OR|	**S₁** | **S₂** $\neq 0$	**S₁** | **S₂** $=0$
223	OR^	**D**OR^	**S₁** ^ **S₂** $\neq 0$	**S₁** ^ **S₂** $=0$

- &: logical AND operation.
- |: logical OR operation.
- ^: logical XOR operation.

Example

- When X1 = ON or the content of C0 and C10 is subjected to the logical AND operation, and the result is not equal to 0, Y0 = ON.
- When X2 and M30 are both equal to On, or the content of 32-bit register D10 (D11) and 32-bit register D20 (D21) is subjected to the logical OR operation, and the result is not equal to 0, or the content of the 32-bit counter C235 and the 32-bit register D200 (D201) is subjected to the logical XOR operation, and the result is not equal to 0, M60 = ON.



API 224–230	D	LD※		(S1) (S2)	Contact form compare LD*

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				＊	＊	＊	＊	＊	＊	＊	＊
S2				＊	＊	＊	＊	＊	＊	＊	＊

Notes on operand usage: ※ : = 、> 、< 、<> 、≦ 、≧

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

LD※	Continuous execution type	–	–

32-bit command (9 STEP)

DLD※	Continuous execution type	–	–

Flag signal: none

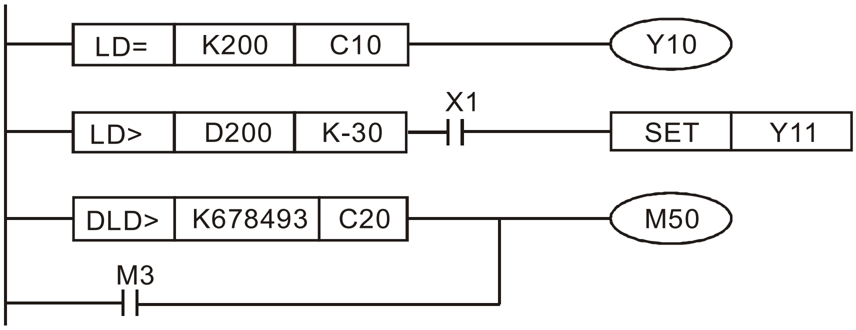
Explanation

- **S₁**: data source device 1. **S₂**: data source device 2.
- This command compares the content of **S₁** and **S₂**. Taking API 224 (LD=) as an example, this command will be activated when the result of comparison is "equal," and will not be activated when the result is "unequal."
- The LD* can be used while directly connected with the busbar

API No.	16-bit commands	32-bit commands	Conditions for activation	Conditions for inactivation
224	LD＝	**D**LD＝	$S_1 = S_2$	$S_1 \neq S_2$
225	LD＞	**D**LD＞	$S_1 > S_2$	$S_1 \leqq S_2$
226	LD＜	**D**LD＜	$S_1 < S_2$	$S_1 \geqq S_2$
228	LD＜＞	**D**LD＜＞	$S_1 \neq S_2$	$S_1 = S_2$
229	LD＜＝	**D**LD＜＝	$S_1 \leqq S_2$	$S_1 > S_2$
230	LD＞＝	**D**LD＞＝	$S_1 \geqq S_2$	$S_1 < S_2$

Example

- When the content of C10 is equal to K200, Y10 = ON.
- When the content of D200 is greater than K-30, and X1 = ON, Y11 = ON and remains in that state.



API 232–238	D	**AND※**	(S1) (S2)	Contact form compare AND*

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*

Notes on operand usage: ※ : = 、> 、< 、<> 、≦ 、≧

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)			
AND※	Continuous execution type	–	–

32-bit command (9 STEP)			
DAND※	Continuous execution type	–	–

Flag signal: none

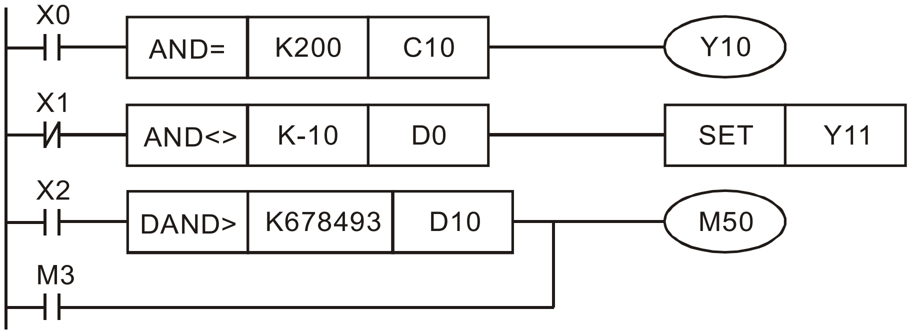
Explanation

- $\mathbf{S}_1$: data source device 1. $\mathbf{S}_2$: data source device 2.
- This command compares the content of $\mathbf{S}_1$ and $\mathbf{S}_2$. Taking API 232 (AND=) as an example, when the result of comparison is equal, this command will be activated; when the result of comparison is unequal, this command will not be activated.
- The AND* command is a comparison command in series with a contact.

API No.	16-bit commands	32-bit commands	Conditions for activation	Conditions for inactivation
232	AND＝	**D**AND＝	$\mathbf{S}_1 = \mathbf{S}_2$	$\mathbf{S}_1 \neq \mathbf{S}_2$
233	AND＞	**D**AND＞	$\mathbf{S}_1 > \mathbf{S}_2$	$\mathbf{S}_1 \leqq \mathbf{S}_2$
234	AND＜	**D**AND＜	$\mathbf{S}_1 < \mathbf{S}_2$	$\mathbf{S}_1 \geqq \mathbf{S}_2$
236	AND＜＞	**D**AND＜＞	$\mathbf{S}_1 \neq \mathbf{S}_2$	$\mathbf{S}_1 = \mathbf{S}_2$
237	AND＜＝	**D**AND＜＝	$\mathbf{S}_1 \leqq \mathbf{S}_2$	$\mathbf{S}_1 > \mathbf{S}_2$
238	AND＞＝	**D**AND＞＝	$\mathbf{S}_1 \geqq \mathbf{S}_2$	$\mathbf{S}_1 < \mathbf{S}_2$

Example

- When X0 = ON and the current value of C10 is also equal to K200, Y10 = ON.
- When X1 = OFF and the content of register D0 is not equal to K-10, Y11 = ON and remains in that state.
- When X2 = ON and the content of the 32-bit register D0 (D11) is less than 678,493, or M3 = ON, M50 = ON.



API 240– 246	D	OR※		S1 S2	Contact form compare OR*

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*	*	*	*	*	*	*
S2				*	*	*	*	*	*	*	*

Notes on operand usage: ※ : =、>、<、<>、≦、≧

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command (5 STEP)

OR※	Continuous execution type	–	–

32-bit command (9 STEP)

DOR※	Continuous execution type	–	–

Flag signal: none

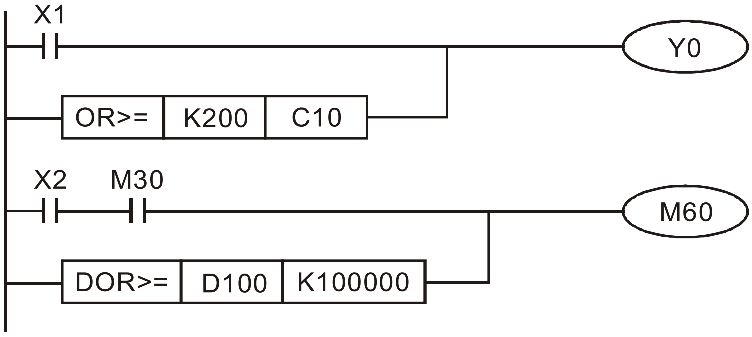
Explanation

- S_1: data source device 1. S_2: data source device 2.
- This command compares the content of S_1 and S_2. Taking API 240 (OR=) as an example, when the result of comparison is equal, this command will be activated; when the result of comparison is unequal, this command will not be activated.
- The OR* command is a compare command in parallel with a contact.

API No.	16-bit commands	32-bit commands	Conditions for activation	Conditions for inactivation
240	OR＝	**D**OR＝	$S_1 = S_2$	$S_1 \neq S_2$
241	OR＞	**D**OR＞	$S_1 > S_2$	$S_1 \leqq S_2$
242	OR＜	**D**OR＜	$S_1 < S_2$	$S_1 \geqq S_2$
244	OR＜＞	**D**OR＜＞	$S_1 \neq S_2$	$S_1 = S_2$
245	OR＜＝	**D**OR＜＝	$S_1 \leqq S_2$	$S_1 > S_2$
246	OR＞＝	**D**OR＞＝	$S_1 \geqq S_2$	$S_1 < S_2$

Example

- When X0 = ON and the current value of C10 is also equal to K200, Y10 = ON.
- When X1 = OFF and the content of register D0 is not equal to K-10, Y11 = ON and remains in that state.
- When X2 = ON and the content of the 32-bit register D0 (D11) is less than 678,493, or M3 = ON, M50 = ON.



API 275–280	**FLD※**	S1 S2	Floating point number contact form compare LD*

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1									*	*	*
S2									*	*	*

Notes on operand usage: # : & 、| 、^

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

FLD※	Continuous execution type	–	–

Flag signal: none

Explanation

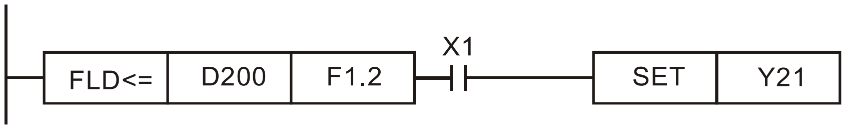
- **S_1**: data source device 1. **S_2**: data source device 2.
- This command compares the content of **S_1** and **S_2**. Taking "FLD=" as an example, if the result of comparison is "equal," this command will be activated; but it will not be activated when the result is "unequal."
- The FLD* command can directly input floating point numerical values (for instance: F1.2) to the **S_1**, **S_2** operands, or store floating-point numbers in register D for use in operations.
- This command can be used while directly connected with the busbar

API No.	32-bit commands	Conditions for activation	Conditions for inactivation
275	FLD＝	$S_1 = S_2$	$S_1 \neq S_2$
276	FLD＞	$S_1 > S_2$	$S_1 \leqq S_2$
277	FLD＜	$S_1 < S_2$	$S_1 \geqq S_2$
278	FLD＜＞	$S_1 \neq S_2$	$S_1 = S_2$
279	FLD＜＝	$S_1 \leqq S_2$	$S_1 > S_2$
280	FLD＞＝	$S_1 \geqq S_2$	$S_1 < S_2$

■

Example

- When the floating point number of register D200 (D201) is less than or equal to F1.2, and X1 activated, contact Y21 will be activated and remain in that state.



API				
281– 286	**FAND※**		(S1) (S2)	Floating point number contact form compare AND*

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1									＊	＊	＊
S2									＊	＊	＊

Notes on operand usage: ＃：&、|、^

Please refer to the function specifications table for each device in series for the scope of device usage

16-bit command

–	–	–	–

32-bit command (9 STEP)

FAND※	Continuous execution type	–	–

Flag signal: none

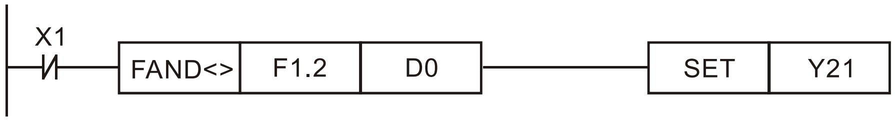
Explanation

- $\mathbf{S_1}$: data source device 1. $\mathbf{S_2}$: data source device 2.
- This command compares the content of $\mathbf{S_1}$ and $\mathbf{S_2}$. Taking "FAND=" as an example, if the result of comparison is "equal," this command will be activated; but it will not be activated when the result is "unequal."
- The FAND* command can directly input floating point numerical values (for instance: F1.2) to the $\mathbf{S_1}$, $\mathbf{S_2}$ operands, or store floating-point numbers in register D for use in operations.
- This command can be used while directly connected with the busbar

API No.	32-bit commands	Conditions for activation	Conditions for inactivation
281	FAND＝	$\mathbf{S_1} = \mathbf{S_2}$	$\mathbf{S_1} \neq \mathbf{S_2}$
282	FAND＞	$\mathbf{S_1} > \mathbf{S_2}$	$\mathbf{S_1} \leqq \mathbf{S_2}$
283	FAND＜	$\mathbf{S_1} < \mathbf{S_2}$	$\mathbf{S_1} \geqq \mathbf{S_2}$
284	FAND＜＞	$\mathbf{S_1} \neq \mathbf{S_2}$	$\mathbf{S_1} = \mathbf{S_2}$
285	FAND＜＝	$\mathbf{S_1} \leqq \mathbf{S_2}$	$\mathbf{S_1} > \mathbf{S_2}$
286	FAND＞＝	$\mathbf{S_1} \geqq \mathbf{S_2}$	$\mathbf{S_1} < \mathbf{S_2}$

Example

- When X1 = OFF, and the floating point number in register D100 (D101) is not equal to F1.2, Y21 = ON and remains in that state.



API 287–292	**FOR※**	(S1) (S2)	Floating point number contact form compare OR*

	Bit device			Word device								16-bit command
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D	– – – –
S1									＊	＊	＊	32-bit command (9 STEP)
S2									＊	＊	＊	FOR※ Continuous execution type – –

Notes on operand usage: ＃：&、|、^

Please refer to the function specifications table for each device in series for the scope of device usage

Flag signal: none

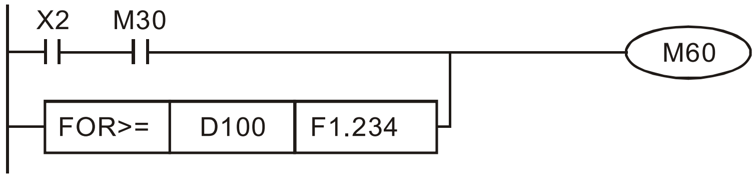
Explanation

- **S$_1$**: data source device 1. **S$_2$**: data source device 2.
- This command compares the content of **S$_1$** and **S$_2$**. Taking "FOR=" as an example, if the result of comparison is "equal," this command will be activated; but it will not be activated when the result is "unequal."
- The FOR* command can directly input floating point numerical values (for instance: F1.2) to the **S$_1$**, **S$_2$** operands, or store floating-point numbers in register D for use in operations.
- This command can be used while directly connected with the busbar

API No.	32-bit commands	Conditions for activation	Conditions for inactivation
287	FOR＝	**S$_1$ ＝ S$_2$**	**S$_1$ ≠ S$_2$**
288	FOR＞	**S$_1$ ＞ S$_2$**	**S$_1$ ≦ S$_2$**
289	FOR＜	**S$_1$ ＜ S$_2$**	**S$_1$ ≧ S$_2$**
290	FOR＜＞	**S$_1$ ≠ S$_2$**	**S$_1$ ＝ S$_2$**
291	FOR＜＝	**S$_1$ ≦ S$_2$**	**S$_1$ ＞ S$_2$**
292	FOR＞＝	**S$_1$ ≧ S$_2$**	**S$_1$ ＜ S$_2$**

Example

- When X2 and M30 are both equal to "On," or the floating point number in register D100 (D101) is greater than or equal to F1.234, M60 = ON.



16-6-5 Detailed explanation of driver special applications commands

API				
139		**RPR** P	(S1) (S2)	Read servo parameter

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2											*

Notes on operand usage: none

16-bit command (5 STEP)

RPR	Continuous execution type	RPRP	Pulse execution type

32-bit command

—	—	—	—

Flag signal: none

Explanation

- (S1): Parameter address of data to be read. (S2): Register where data to be read is stored.

API				
140		**WPR** P	(S1) (S2)	Write servo parameter

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*

Notes on operand usage: none

16-bit command (5 STEP)

WPR	Continuous execution type	WPRP	Pulse execution type

32-bit command

—	—	—	—

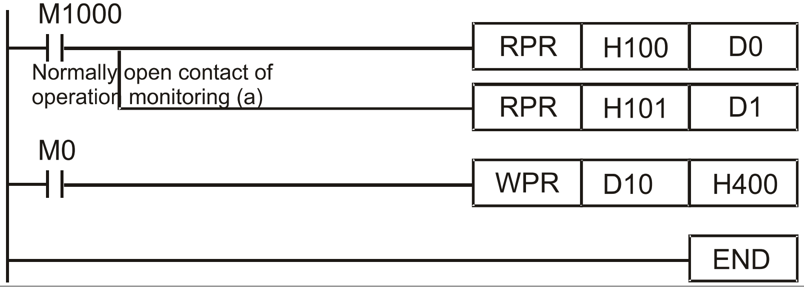
Flag signal: none

Explanation

- (S1): Data to write to specified page. (S2): Parameter address of data to be written.

Example

- When the data in the CP2000 driver's parameter H01.00 is read and written to D0, data from H01.01 will be read and written to D1.
- When M0 = ON, the content of D10 will be written to the CP2000 driver parameter 04.00 (first speed of multiple speed levels).
- When the parameter has been written successfully, M1017 = ON.
- The CP2000's WPR command does not support writing to the 20XX address, but the RPR command supports reading of 21XX, 22XX.



Recommendation Take care when using the WPR command. When writing parameters, because most parameters are recorded as they are written, these parameters may only be revised 109 times; a memory write error may occur if parameters are written more than 10^9 times.

Because the following commonly-used parameters have special processing, there are **no** restrictions on the number of times they may be written.

Pr.00-11: Speed mode selection

Pr.00-27: User-defined value

Pr.01-12: Acceleration time 1

Pr.01-13: Deceleration time 1

Pr.01-14: Acceleration time 2
Pr.01-15: Deceleration time 2
Pr.01-16: Acceleration time 3
Pr.01-17: Deceleration time 3
Pr.01-18: Acceleration time 4
Pr.01-19: Deceleration time 4

Pr.02-12: Select MI Conversion Time mode:
Pr.02-18: Select MO Conversion Time mode:

Pr.04-50–Pr.04-69: PLC register parameter 0–19

Pr.08-04: Upper limit of integral
Pr.08-05: PID output upper limit

Pr.10-17: Electronic gear A
Pr.10-18: Electronic gear B

Calculation of the number of times written is based on whether the written value is modified. For instance, writing the same value 100 times at the same time counts as writing only once.

When writing a PLC program, if unsure of usage of the WPR command, we recommend that you use the WPRP command.

API				
141	**FPID**	**P**	(S1) (S2) (S3) (S4)	Driver PID control mode

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
S3				*	*						*
S4				*	*						*

Notes on operand usage: none

16-bit command (9 STEP)

FPID	Continuous execution type	FPIDP	Pulse execution type

32-bit command

–	–	–	–

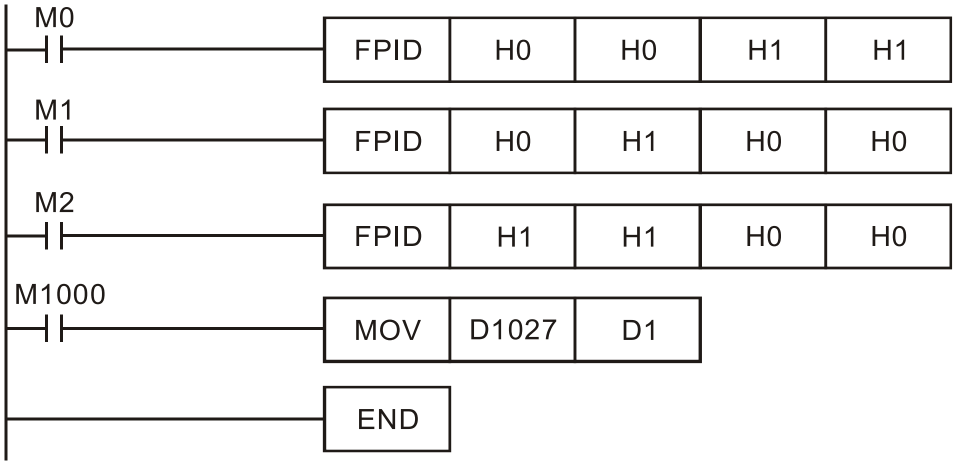
Flag signal: none

Explanation

- (S1): PID reference target value input terminal select. (S2): PID function proportional gain P. (S3): PID function integral time I. (S4): PID function differential time D.
- The FPID command can directly control the driver's feedback control of PID parameter Pr.08-00 PID reference target value input terminal selection, Pr.08-01 proposal gain P, Pr.08-02 integral time I, and Pr.08-03 differential time D.

Example

- When M0 = ON, the set PID reference target value input terminal selection is 0 (no PID function), the PID function proportional gain P is 0, the PID function integral time I is 1 (units: 0.01 sec.), and the PID function differential time D is 1 (units: 0.01 sec.).
- When M1 = ON, the set PID reference target value input terminal selection is 0 (no PID function), the PID function proportional gain P is 1 (units: 0.01), the PID function integral time I is 0, and the PID function differential time D is 0.
- When M2 = ON, the set PID reference target value input terminal selection is 1 (target frequency input is controlled from the digital keypad), the PID function proportional gain P is 1 (units: 0.01), the PID function integral time I is 0, and the PID function differential time D is 0.
- D1027: Frequency command after PID operation.



API		FREQ	P	S1 S2 S3	Driver speed control mode
142					

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				＊	＊						＊
S2				＊	＊						＊
S3				＊	＊						＊

Notes on operand usage: none

16-bit command (7 STEP)

FREQ	Continuous execution type	FREQP	Pulse execution type

32-bit command

—	—	—	—

Flag signal: M1015

Explanation

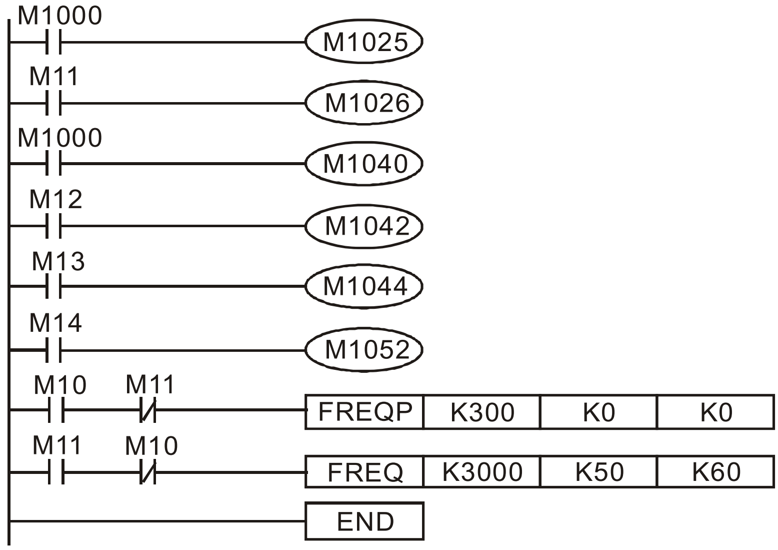
- S1: Frequency command. S2: Acceleration time. S3: Deceleration time
- S2, S3: In acceleration/deceleration time settings, the number of decimal places is determined by the definitions of Pr.01-45.

Example
When Pr.01-45=0: units of 0.01 sec.
The setting of 50 for S2 (acceleration time) in the ladder diagram below implies 0.5 sec, and the S3 (deceleration time) setting of 60 implies 0.6 sec

- The FREQ command can control driver frequency commands, and acceleration and deceleration time; it also uses special register control actions, such as:
  M1025: Control driver RUN(On)/STOP(Off) (RUN requires Servo On (M1040 On) to be effective)
  M1026: Control driver operating direction FWD(Off)/REV(On)
  M1040: Control Servo On/Servo Off.
  M1042: Trigger quick stop (ON)/does not trigger quick stop (Off).
  M1044: Pause (On)/release pause (Off)
  M1052: Lock frequency (On)/release lock frequency (Off)

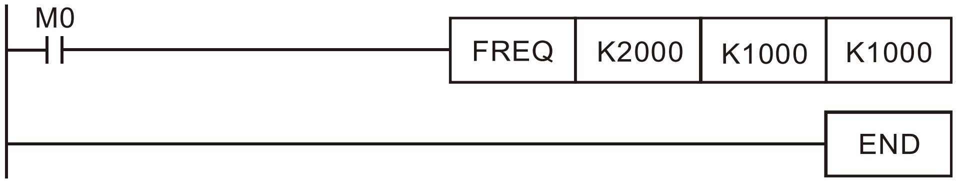
Example

- M1025: Driver RUN (On) / STOP (Off), M1026: driver operating direction FWD (Off) / REV (On). M1015: frequency reached.
- When M10 = ON, sets the driver frequency command K300 (3.00 Hz), with an acceleration/deceleration time of 0.
  When M11 =ON, sets the driver frequency command K3000 (30.00 Hz), with an acceleration time of 50 (0.5 sec.) and deceleration time of 60 (0.6 sec.). (When Pr.01-45 = 0)
- When M11 = OFF, the driver frequency command will now change to 0



- Pr.09-33 are defined on the basis of whether the reference commands have been cleared before PLC operation.
  bit0: Prior to PLC scanning procedures, whether the target frequency has been cleared is 0. (This will be written to the FREQ command when the PLC is ON).

Example: When using r to write a program



If we force M0 to be 1, the frequency command will be 20.00 Hz; but when M0 is set as 0, there will be a different situation.

Case 1: When the bit0 of Pr.09-33 is 0, and M0 is set as 0, the frequency command remains at 20.00 Hz.

Case 2: When the bit0 of Pr.09-33 is 1, and M0 is set as 0, the frequency command changes to 0.00 Hz.

The reason is that when the Pr.09-33 bit0 is 1 prior to the PLC scanning procedures, the frequency will firstly revert to 0.

When the Pr.09-33 bit0 is 0, the frequency will not revert to 0.

API				
261		**CANRX** P	(S1) (S2) (S3) (D)	Read CANopen slave station data

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						
S2				*	*						
S3				*	*						
D									*	*	*

Notes on operand usage: none

16-bit command (9 STEP)			
CANRX	Continuous execution type	CANRX P	Pulse execution type

32-bit command			
–	–	–	–

Flag signal

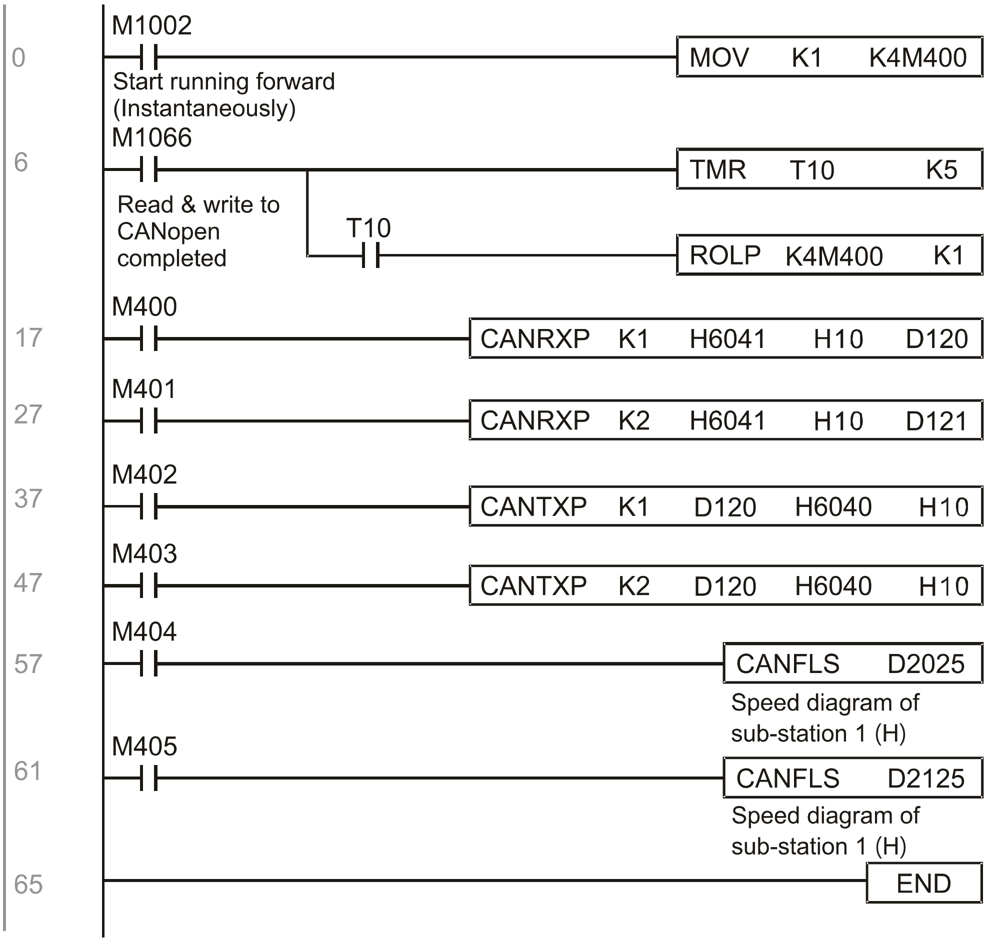
Explanation

- (S1): Slave station number. (S2): Main index. (S3): Subindex+bit length. (D): Preset address.
- The CANRX command can read the index of the corresponding slave station. When it is executed, it will send the SDO message format to the slave station. M1066 and M1067 will both be 0 at that time, and M1066 will be set as 1 after reading. If the slave station gives the correct response, it will write the value to the preset register, and set M1067 as 1. If the slave station has a response error, M1067 will be set as 0, and an error message will be recorded to D1076 to D1079.

Example

M1002: When the PLC runs, the command will be triggered once and will set K4M400 = K1

Afterwards, each time M1066 is 1, it will switch to a different message.



API 264		**CANTX**	**P**	S1 S2 S3 S4	Write CANopen slave station data

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						
S2				*	*				*	*	*
S3				*	*						
S4				*	*						

Notes on operand usage: none

16-bit command (9 STEP)

CANTX	Continuous execution type	CANTXP	Pulse execution type

32-bit command

–	–	–	–

Flag signal

Explanation

- S1: Slave station number. S2: Address to be written. S3: Main index. S4: Subindex+bit length.
- The CANTX command can write a value to the index of the corresponding slave station. When it is executed, it will send the SDO message format to the slave station. M1066 and M1067 will both be 0 at that time, and M1066 will be set as 1 after reading. If the slave station gives the correct response, it will write the value to the preset register, and set M1067 as 1. If the slave station has a response error, M1067 will be set as 0, and an error message will be recorded to D1076 to D1079.

API 265		**CANFLS**	**P**	D	Refresh special D corresponding to CANopen

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
D				*	*						

Notes on operand usage: none

16-bit command (3 STEP)

CANFLS	Continuous execution type	CANFLSP	Pulse execution type

32-bit command

–	–	–	–

Flag signal

Explanation

- D: Special D to be refreshed.
- The CANFLS command can refresh special D commands. When is a read only attribute, executing this command will send a message equivalent to that of CANRX to the slave station, and the number of the slave station will be transmitted back and refreshed to this special D. When there is a read/write attribute, executing this command will send a message equivalent to that of CANTX to the slave station, and the value of this special D will be written to the corresponding slave station.
- When M1066 and M1067 are both 0, and M1066 is set as 1 after reading, if the slave station gives a correct response, the value will be written to the designated register, and M1067 will be set as 1. If the slave station's response contains an error, then M1067 will be set as 0, and an error message will be recorded to D1076-D1079.

API 320	**D**	**ICOMR**	**P**	S1 S2 S3 D	Internal communications read

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
S3				*	*						*
D				*	*						*

Notes on operand usage: none

16-bit command (9 STEP)

ICOMR	Continuous execution type	ICOMRP	Pulse execution type

32-bit command (17 STEP)

DICOMR	Continuous execution type	DICOMRP	Pulse execution type

Flag signal: M1077 M1078 M1079

Explanation

S1: Selection of slave device. S2: Device selection (0: converter, 1: internal PLC). S3: Read address. D: Saving target.

- The ICOMR command can obtain the slave station's converter and the internal PLC's register value.

API 321	D	ICOMW	P	S1 S2 S3 D	Internal communications write

	Bit device			Word device							
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*
S3				*	*						*
D				*	*						*

Notes on operand usage: none

16-bit command (9 STEP)

ICOMW	Continuous execution type	ICOMW P	Pulse execution type

32-bit command (17 STEP)

DICOM W	Continuous execution type	DICOM WP	Pulse execution type

Flag signal: M1077 M1078 M1079

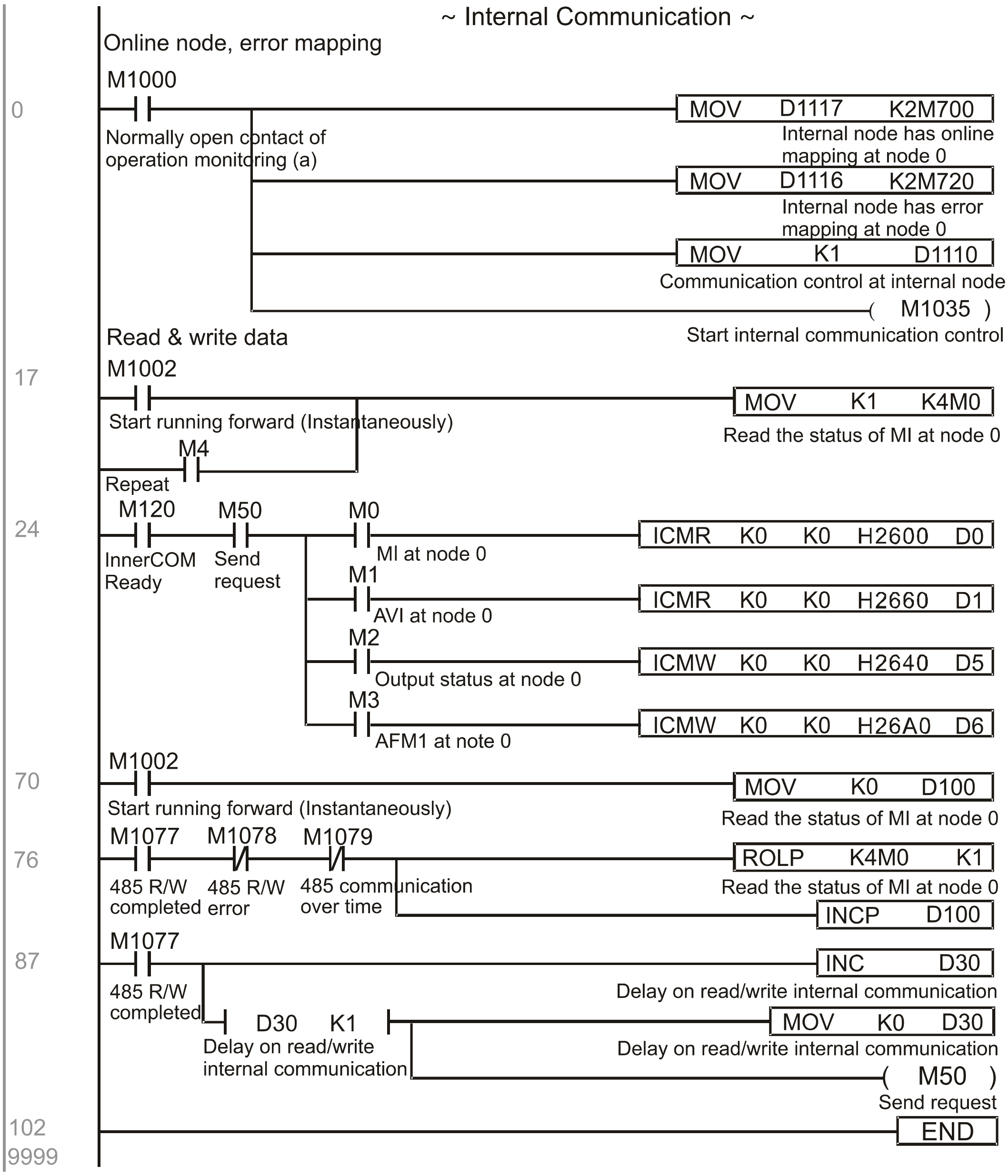
Explanation

S1: Selection of slave device. S2: Device selection (0: converter, 1: internal PLC). S3: Read address. D: Saving target.

- The ICOMW command write a value to the slave station's converter and the internal PLC's register.

Example

Please refer to the following example:


~ Internal Communication ~
Online node, error mapping
M1000
0
MOV D1117 K2M700
Normally open contact of operation monitoring (a)
Internal node has online mapping at node 0
MOV D1116 K2M720
Internal node has error mapping at node 0
MOV K1 D1110
Communication control at internal node
M1035
Start internal communication control
Read & write data
M1002
17
MOV K1 K4M0
Start running forward (Instantaneously)
Read the status of MI at node 0
M4
Repeat
M120
M50
M0
24
ICMR K0 K0 H2600 D0
InnerCOM Ready
Send request
MI at node 0
M1
ICMR K0 K0 H2660 D1
AVI at node 0
M2
ICMW K0 K0 H2640 D5
Output status at node 0
M3
ICMW K0 K0 H26A0 D6
AFM1 at note 0
M1002
70
MOV K0 D100
Start running forward (Instantaneously)
Read the status of MI at node 0
M1077 M1078 M1079
76
ROLP K4M0 K1
485 R/W completed
485 R/W error
485 communication over time
Read the status of MI at node 0
INCP D100
M1077
87
INC D30
485 R/W completed
Delay on read/write internal communication
D30 K1
MOV K0 D30
Delay on read/write internal communication
Delay on read/write internal communication
M50
Send request
102
9999
END

API 323		**WPRA**	P	S1 S2	Drive parameters write-in

	Bit device			Word device						
	X	Y	M	K	H	KnX	KnY	KnM	T	C	D
S1				*	*						*
S2				*	*						*

Notes on operand usage: none

16-bit command (5 STEP)

WORA	Continuous execution type	WORAP	Pulse execution type

32-bit command

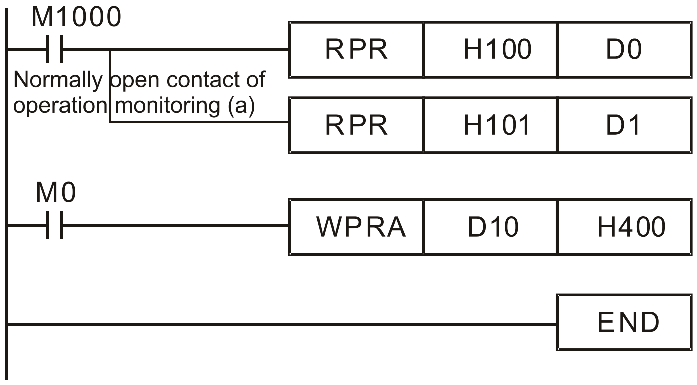
-	-	-	-

Flag signal: none

Explanation S1: Data that is going to write in S2: Parameter address of the write-in data

Example

- Read the data of CP2000 drive’s parameter H01.00 and write into D0, read data of H01.01 and write into D1.
- When M0 is ON, write the content of D10 into CP2000 drive’s Pr.04-00 (1st step speed frequency).
- When parameter writes-in successfully, M1017 is ON.
- The WPR command does not support the write-in of 20XX address, but the RPR command supports the read-out of 21XX and 22XX.



Recommendation

- When WPRA executes, the data is only written into the RAM area, and will get back to previous record when the power is off.

16-7 Error display and handling

Code	ID	Description	Recommended handling approach
PLrA	47	RTC time check	Turn power on and off when resetting the keypad time
PLrt	49	incorrect RTC mode	Turn power on and off after making sure that the keypad is securely connected
PLod	50	Data writing memory error	Check whether the program has an error and download the program again
PLSv	51	Data write memory error during program execution	Restart power and download the program again
PLdA	52	Program transmission error	Try uploading again; if the error persists, sent to the manufacturer for service
PLFn	53	Command error while downloading program	Check whether the program has an error and download the program again
PLor	54	Program exceeds memory capacity or no program	Restart power and download the program again
PLFF	55	Command error during program execution	Check whether the program has an error and download the program again
PLSn	56	Check code error	Check whether the program has an error and download the program again
PLEd	57	Program has no END stop command	Check whether the program has an error and download the program again
PLCr	58	MC command has been used continuously more than nine times	Check whether the program has an error and download the program again
PLdF	59	Download program error	Check whether the program has an error and download again
PLSF	60	PLC scan time excessively long	Check whether the program code has a writing error and download again

16-8 CANopen Master control applications

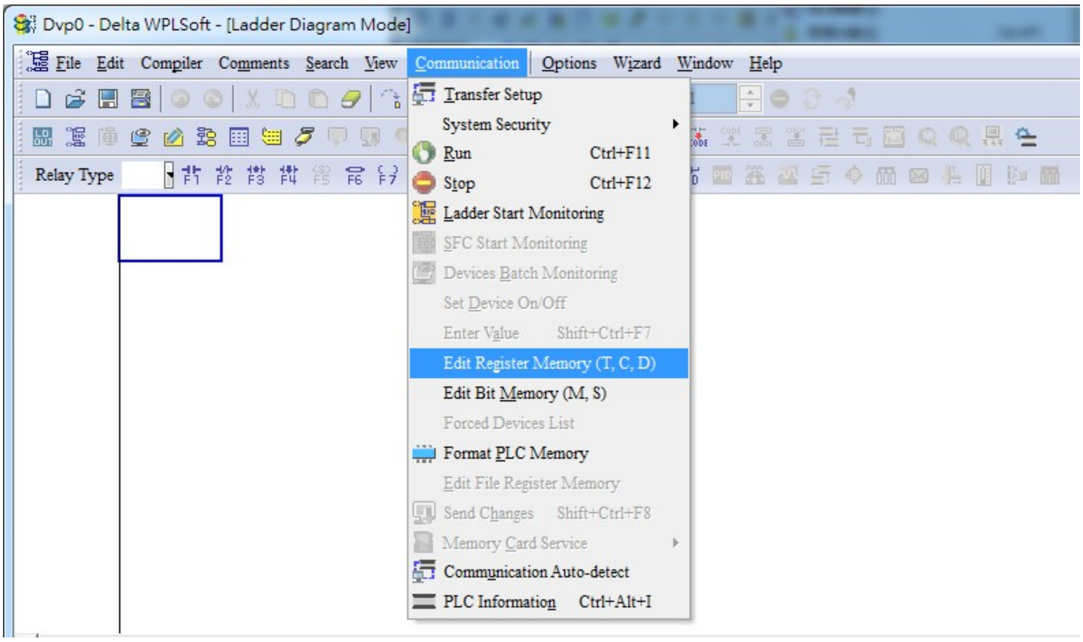
Control of a simple multi-axis application is required in certain situations. If the device supports the CANopen protocol, a CP2000 can serve as the master in implementing simple control (speed control). The setting method comprises the following seven steps:

Step 1: Activating CANopen Master functions

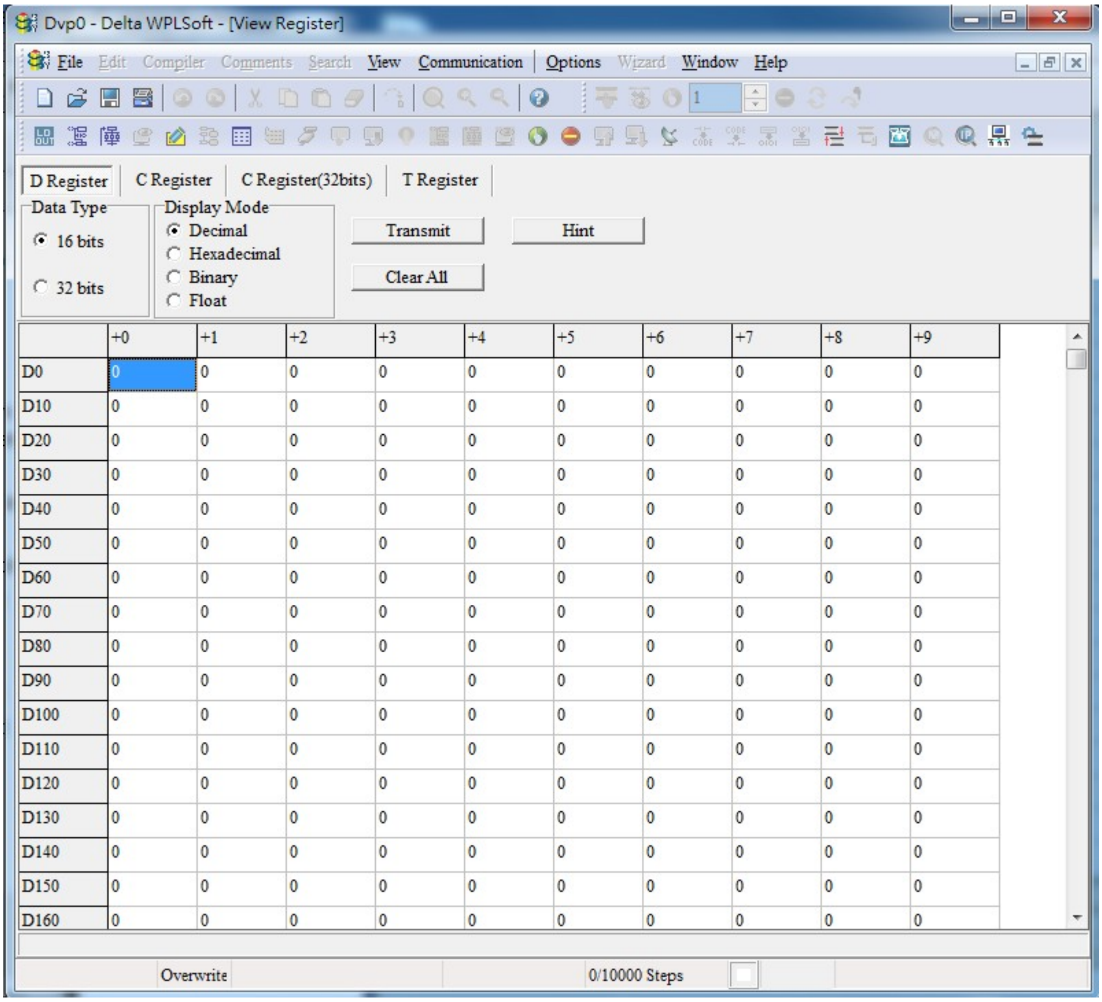
1. Pr.09-45 = 1 (initiates Master functions); restart power after completing setting, the status bar on the KPC-CC01 digital keypad will display "CAN Master".
2. Pr.00-02 = 6 reset PLC (please note that this action will reset the program and PLC registers to the default values)
3. Turn power off and on again.
4. Use the KPC-CC01 digital keypad to set the PLC control mode as **"PLC Stop"** (if a newly-introduced driver is used, the blank internal PLC program will cause a PLFF warning code to be issued).

Step 2: Master memory settings

1. After connecting the 485 communications cable, use WPL Soft to set the PLC **status** as Stop (if the PLC mode has been switched to the **"PLC Stop"** mode, the PLC **status** should already be Stop)
2. Set the address and corresponding station number of the slave station to be controlled. For instance, if it is wished to control two slave stations (a maximum of 8 stations can be controlled simultaneously), and the station numbers are 21 and 22, it is only necessary to set D2000 and D2100 as 20 and 21, and then set D2200, D2300, D2400, D2500, D2600, and D2700 as 0. The setting method involves use of the PLC's WPL editing software WPL as follows:
   - ■ Open WPL and implement **communications > register edit (T C D)** function



- After leaving the PLC register window, the register setting screen will appear, as shown below:



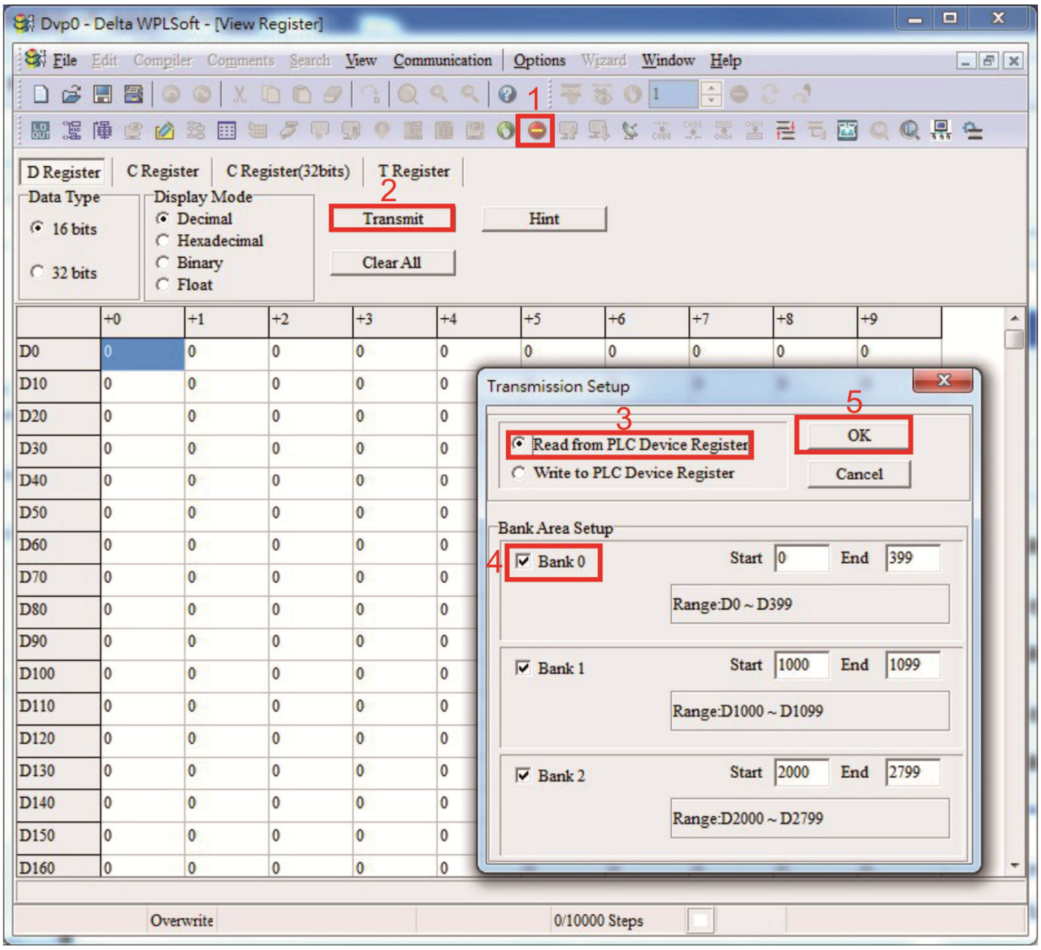
Data Type
● 16 bits
○ 32 bits

Display Mode
● Decimal
○ Hexadecimal
○ Binary
○ Float

	+0	+1	+2	+3	+4	+5	+6	+7	+8	+9
D0	0	0	0	0	0	0	0	0	0	0
D10	0	0	0	0	0	0	0	0	0	0
D20	0	0	0	0	0	0	0	0	0	0
D30	0	0	0	0	0	0	0	0	0	0
D40	0	0	0	0	0	0	0	0	0	0
D50	0	0	0	0	0	0	0	0	0	0
D60	0	0	0	0	0	0	0	0	0	0
D70	0	0	0	0	0	0	0	0	0	0
D80	0	0	0	0	0	0	0	0	0	0
D90	0	0	0	0	0	0	0	0	0	0
D100	0	0	0	0	0	0	0	0	0	0
D110	0	0	0	0	0	0	0	0	0	0
D120	0	0	0	0	0	0	0	0	0	0
D130	0	0	0	0	0	0	0	0	0	0
D140	0	0	0	0	0	0	0	0	0	0
D150	0	0	0	0	0	0	0	0	0	0
D160	0	0	0	0	0	0	0	0	0	0

Overwrite   0/10000 Steps

If there is a new PLC program and no settings have yet been made, you can read default data from the converter, and merely edit it to suit the current application. If settings have already been made, however, the special D in the CANopen area will display the saved status (the CANopen D area is located at D1090 to D1099 and D2000 to D2799). Assuming it is a new program, we will first read the default data from the converter; check the communications format if there is no communications link (the default PLC station number is 2, 9600, 7N2, ASCII). Perform the following steps: 1. Switch the PLC to Stop status; 2. Press the transmit button; 3. click on read memory after exiting the window; 4. Ignore D0-D399; and 5. click on the confirm button.)


Dvp0 - Delta WPLSoft - [View Register]
File Edit Compiler Comments Search View Communication Options Wizard Window Help
1
D Register
C Register
C Register(32bits)
T Register
2
Transmit
Hint
Clear All
Overwrite
0/10000 Steps
3
4
5
OK
Cancel

Data Type: ● 16 bits ○ 32 bits

Display Mode: ● Decimal ○ Hexadecimal ○ Binary ○ Float

Transmission Setup

3 ● Read from PLC Device Register

○ Write to PLC Device Register

Bank Area Setup

4 ☑ Bank 0 Start 0 End 399 Range:D0～D399

☑ Bank 1 Start 1000 End 1099 Range:D1000～D1099

☑ Bank 2 Start 2000 End 2799 Range:D2000～D2799

After reading the data, it is necessary to perform some special D settings. Before proceeding, we will first introduce the special D implications and setting range. The CANopen Master's special D range is currently D1070 to D1099 and D2000 to D2799; this range is divided into 3 blocks:

The first block is used to display CANopen's current status, and has a range of D1070 to D1089; the second block is used for CANopen's basic settings, and has a range of D1090 to D1099; the third block is the slave station mapping and control area, and has a range of D2000 to D2799;

These areas are therefore introduced as follows:

The first contains the current CANopen status display:

When the master initializes a slave station, we can find out from D1070 whether configuration of the slave device has been completed; we can find out whether an error occurred in the configuration process from D1071 and whether the configuration is inappropriate from D1074. After entering normal control, we can find out whether the slave device is offline from D1073. In addition, we can check the slave device's read/write information using the CANRX, CANTX, and CANFLS commands; error information can be obtained from D1076 to D1079 if there has been a read/write failure.

Special D	Description of Function	R/W
D1070	Channel opened by CANopen initialization (bit0=Machine code0 …….)	R
D1071	Error channel occurring in CANopen initialization process (bit0=Machine code0 …….)	R
D1072	Reserved	-

Special D	Description of Function	R/W
D1073	CANopen break channel (bit0=Machine code0 …….)	R
D1074	Error code of master error 0: No error 1: Slave station setting error 2: Synchronizing cycle setting error (too small)	R
D1075	Reserved	-
D1076	SDO error message (main index value)	R
D1077	SDO error message (secondary index value)	R
D1078	SDO error message (error code L)	R
D1079	SDO error message (error code H)	R

The second area is for basic CANopen settings: (the PLC must have **stopped** when this area is used to make settings)

We must set the information exchange time for the master and slave station,

Special D	Description of Function	Default:	R/W
D1090	Synchronizing cycle setting	4	RW

Use D1090 to perform settings; setting time relationships include:

$$\text{Sync time} \geq \frac{1M}{Rate} * \frac{N}{4}$$

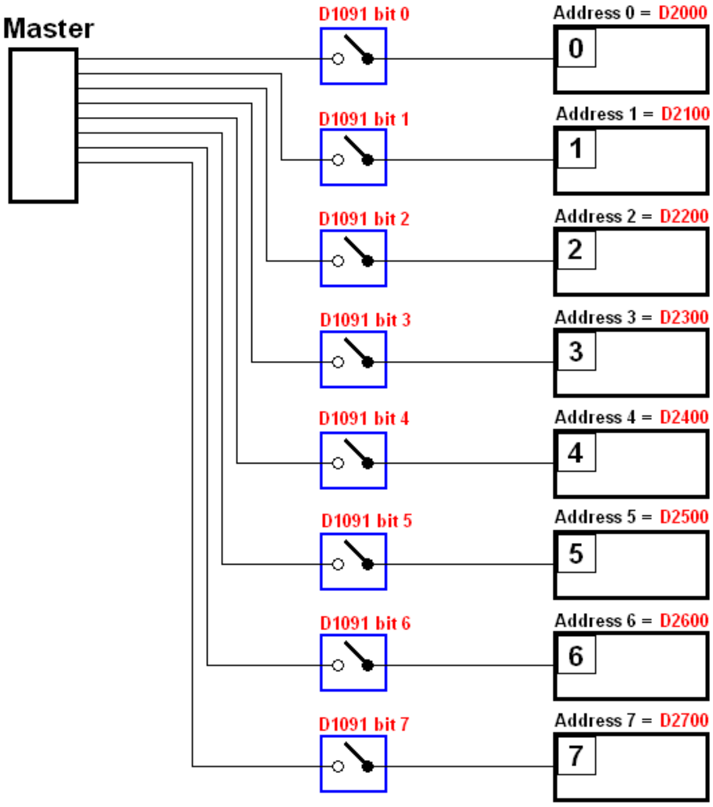
N: TXPDO + RXPDO

For instance, when communications speed is 500Kbps, TXPDO + RXPDO have 8 sets, and synchronizing time will require more than 4 ms

We must also define how many slave stations will be open. D1091 is the channel for defining station opening, and D2000+100 × n is the station number defining this channel. See the detailed explanation below.

Slave station number **n** = 0-7

Special D	Description of Function	R/W
D1091	Sets slave station On or Off (bit0–bit 7 correspond to slave stations number 0–7)	RW
D2000+100***n**	Slave station number	RW



If slave devices have a slow start-up, the master can delay for a short time before performing slave station configuration; this time delay can be set via D1092.

Special D	Description of Function	Default:	R/W
D1092	Delay before start of initialization	0	RW

With regard to slave device initialization, a delay time can be set to judge whether failure has occurred. If the communications speed is relatively slow, the delay time can be adjusted to judge whether initialization has been completed, which will ensure that there is time to perform slave device initialization.

Special D	Description of Function	Default:	R/W
D1099	Initialization completion delay time Setting range: 1 to 60000 sec	15 sec.	RW

After communication is successful, the system must detect whether there is a break in communications with the slave station. D1093 is used to set detection time, and D1094 sets the number of consecutive errors that will trigger a break error.

Special D	Description of Function	Default:	R/W
D1093	Break time detection	1000ms	RW
D1094	Break number detection	3	RW

The packet type transmitted by PDO is set before establishing normal communications and generally does not require adjustment.

Special D	Description of Function	Default:	R/W
D1097	Corresponding real-time transmission type (PDO) Setting range: 1–240	1	RW
D1098	Corresponding real-time receiving type (PDO) Setting range: 1–240	1	RW

The third block is the slave station mapping and control area.

CANopen provides a PDO method to perform mapping of the master and slave station memory, and enables the master to directly access read/write data in a certain memory area. The master will automatically perform data exchange with the corresponding slave device, and the read/write values can be seen directly from the special D area after real-time exchange (M1034 = 1 time) has been established. The CP2000 currently supports real-time mapping of four PDOs, and there are two types of PDO RXPDO (reads slave device information) and TXPDO (writes to slave device). In addition, in order to facilitate control, the CP2000 cannot perform mapping of commonly used registers; the following is an overview of the current PDO mapping situation:

TX PDO			
PDO2 (Remote I/O)		**PDO1 (Speed)**	
Description	Special D	Description	Special D
Slave device DO	D2027 + 100 × n	Controller word	D2008 + 100 × n
Slave device AO1	D2031 + 100 × n	Target speed	D2012 + 100 × n
Slave device AO2	D2032 + 100 × n		
Slave device AO3	D2033 + 100 × n		

RXPDO			
PDO2 (Remote I/O)		PDO1 (Speed)	
Description	Special D	Description	Special D
Slave device DI	D2026 + 100 × n	Mode word	D2009 + 100 × n
Slave device AI1	D2028 + 100 × n	Actual frequency	D2013 + 100 × n
Slave device AI2	D2029 + 100 × n		
Slave device AI3	D2030 + 100 × n		

Because usage requires only simple to open the corresponding PDO, where TXPDO employs D2034+100*n settings and RXPDO employs D2067+100*n settings.

These two special D areas are defined as follows:

	PDO2		PDO1	
Default definition	Remote I/O		Speed	
bit	7	6–4	3	2–0
Definition	En	Length:	En	Length:

En: indicates whether PDO is used

Length: indicates mapping of several variables

In a simple example, if we wish to control a CP2000 slave device and cause it to operate in speed mode, we only have to make the following settings:

D2034+100*n =000Ah

Length	TX PDO			
	PDO2		PDO1	
	Description	Special D	Description	Special D
1	Slave device DO	D2027 + 100 × n	Controller word	D2008 + 100 × n
2	Slave device AO1	D2031 + 100 × n	Target speed	D2012 + 100 × n
3	Slave device AO2	D2032 + 100 × n		
4	Slave device AO3	D2033 + 100 × n		

	PDO2		PDO1	
Definition	Remote I/O		Speed	
bit	7	6–4	3	2–0
Definition	0	0	1	2

D2067+100*n =000Ah

Length	TX PDO			
	PDO2		PDO1	
	Description	Special D	Description	Special D
1	Slave device DI	D2026 + 100 × n	Controller word	D2009 + 100 × n
2	Slave device AI1	D2028 + 100 × n	Actual frequency	D2013 + 100 × n
3	Slave device AI2	D2029 + 100 × n		
4	Slave device AI3	D2030 + 100 × n		

	PDO2		PDO1	
Definition	Remote I/O		Speed	
bit	7	6–4	3	2–0
Definition	0	0	1	2

Switch the PLC to Run after completing settings. Now wait for successful initialization of CANopen (M1059 = 1 and M1061 = 0), and then initiate CANopen memory mapping (M1034 = 1). The control word and frequency command will now automatically refresh to the corresponding slave device (D2008 + n × 100 and D2012 + n ×100), and the slave device's status word and currently frequency will also be automatically sent back to the master station (D2009 + n × 100 and

D2013 + n × 100). This also illustrates how the master can handle these tasks through read/write operations in the special D area.

Furthermore, it should be noted that the remote I/O of PDO2 can obtain the slave device's current DI and AI status, and can also control the slave device's DO and AO status. Nevertheless, after introducing a fully automatic mapping special D, the CP2000 CANopen master also provides additional information refreshes. For instance, while in speed mode, acceleration/deceleration settings may have been refreshed. The special D therefore also stores some seldom-used real-time information, and these commands can be refreshed using the CANFLS command. The following is the CP2000's current CANopen master data conversion area, which has a range of D2001 + 100 × n - D2033 + 100 × n, as shown below:

1. The range of n is 0-7
2. ●Indicates PDOTX, ▲Indicates PDORX; unmarked special D can be refreshed using the CANFLS command

Special D	Description of Function	Default	PDO Default		R/W
			1	2	
D2000 + 100 × n	Station number n of slave station Setting range: 0–127 0: No CANopen function	0			RW
D2002 + 100 × n	Manufacturer code of slave station number n (L)	0			R
D2003 + 100 × n	Manufacturer code of slave station number n (H)	0			R
D2004 + 100 × n	Manufacturer's product code of slave station number n (L)	0			R
D2005 + 100 × n	Manufacturer's product code of slave station number n (H)	0			R

Basic definitions

Special D	Description of Function	Default	PDO Default		R/W
			1	2	
D2006 + 100 × n	Communications break handling method of slave station number n	0			RW
D2007 + 100 × n	Error code of slave station number n error	0			R
D2008 + 100 × n	Control word of slave station number n	0	●		RW
D2009 + 100 × n	Status word of slave station number n	0	▲		R
D2010 + 100 × n	Control mode of slave station number n	2			RW
D2011 + 100 × n	Actual mode of slave station number n	2			R

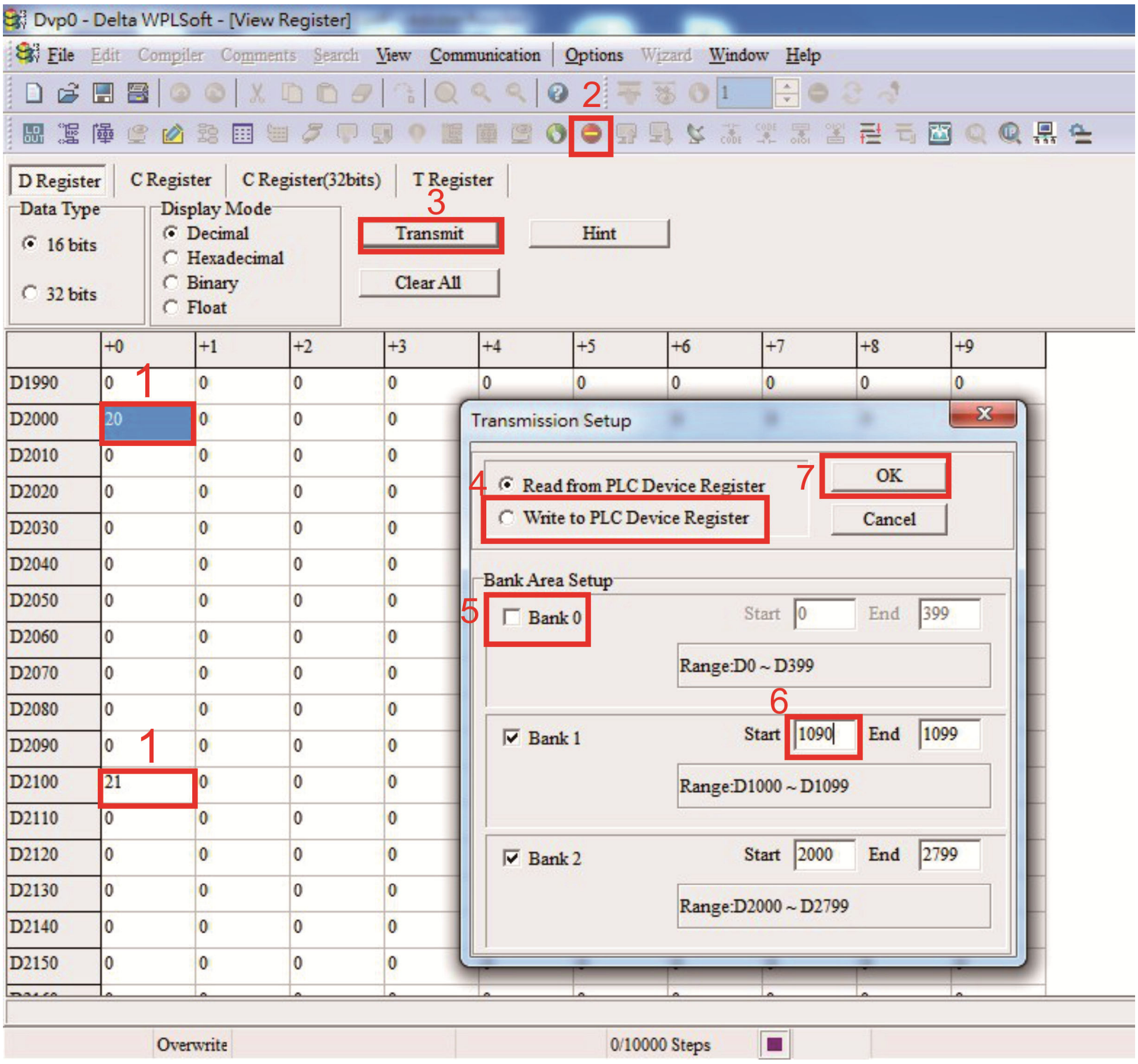
Velocity Control

Special D	Description of Function	Default	PDO Default		R/W
			1	2	
D2001 + 100 × n	Torque restriction on slave station number n	0			RW
D2012 + 100 × n	Target speed of slave station number n (rpm)	0	●		RW
D2013 + 100 × n	Actual speed of slave station number n (rpm)	0	▲		R
D2014 + 100 × n	Error speed of slave station number n (rpm)	0			R
D2015 + 100 × n	Acceleration time of slave station number n (ms)	1000			RW
D2016 + 100 × n	Deceleration time of slave station number n (ms)	1000			RW

Remote I/O

Special D	Description of Function	Default	PDO Default		R/W
			1	2	
D2026 + 100 × n	MI status of slave station number n	0		▲	R
D2027 + 100 × n	MO setting of slave station number n	0		●	RW
D2028 + 100 × n	AI1 status of slave station number n	0		▲	R
D2029 + 100 × n	AI2 status of slave station number n	0		▲	R
D2030 + 100 × n	AI3 status of slave station number n	0		▲	R
D2031 + 100 × n	AO1 setting of slave station number n	0		●	RW
D2032 + 100 × n	AO2 setting of slave station number n	0		●	RW
D2033 + 100 × n	AO3 setting of slave station number n	0		●	RW

After gaining an understanding of special D definitions, we return to setting steps. After entering the values corresponding to D1090 to D1099, D2000+100*n, D2034+100*n and D2067+100*n, we cannot begin to perform downloading, which is performed in accordance with the following steps: (1. D2000 and D2100 are set as 20 and 21, and D2200, D2300, D2400, D2500, D2600, and D2700 are set as 0; if a setting of 0 causes problems, D1091 can be set as 3, and slave stations 2 to 7 can be closed. 2. Switch PLC to Stop status. 3. Press the transmit button. 4. Click on write memory after exiting the window. 5. Ignore D0–D399. 6. Change the second range to D1090–D1099. 7. Click on Confirm.)



Dvp0 - Delta WPLSoft - [View Register]

D Register: Data Type ● 16 bits ○ 32 bits; Display Mode ● Decimal ○ Hexadecimal ○ Binary ○ Float

D2000 +0: 20

D2100 +0: 21

Transmission Setup

● Read from PLC Device Register

○ Write to PLC Device Register

Bank Area Setup

☐ Bank 0 Start 0 End 399 Range:D0 ~ D399

☑ Bank 1 Start 1090 End 1099 Range:D1000 ~ D1099

☑ Bank 2 Start 2000 End 2799 Range:D2000 ~ D2799

- Another method can be used to set D1091: Determine which of slave stations 0 to 7 will not be needed, and set the corresponding bits to 0. For instance, if it is not necessary to control slave stations 2, 6 and 7, merely set D1091 = 003B, and the setting method is the same as described above: Use WPL to initiate **communications > use register edit (T C D)** function to perform settings.

Step 3: Set the master's communications station number and communications speed

☑ When setting the master's station number (Pr.09-46, default is set as 100), make sure not to use the same number as a slave station.

☑ Set the CANopen communications speed (Pr.09-37); regardless of whether the driver is defined as a master or slave station, the communications speed is set via this parameter.

Step 4: Write program code

Real-time access: Can directly read/write to or from the corresponding D area.

Non real-time access:

Read command:

Use the CANRX command for reading. M1066 will be 1 when reading is complete; M1067 will be 1 if reading is successful, and M1067 will be 0 if an error has occurred.

Write command:

Use the CANTX command for writing. M1066 will be 1 when writing is complete; M1067 will be 1 if writing is successful, and M1067 will be 0 if an error has occurred.

Refresh command:

Use CANFLS command to refresh (if there are RW attributes, the master will write to the slave station; if there are RO attributes, the slave station will return the read values to the master); M1066 will be 1 if refresh has been completed; M1067 will be 1 if refresh is successful, and M1067 will be 0 if an error has occurred.

NOTE

When using CANRX, CANTX or CANFLS, internal implementation commands will wait until M1066 is completed before executing the next CANRX, CANTX or CANFLS.

Afterwards, download program to the driver (Please note that the PLC's default communications format is ASCII 7N2 9600, and the station number is 2. The WPL must therefore be modified, and the WPL setting pathway is **settings > communications settings**)

Step 5: Set the slave stations' station numbers, communications speed, control source, and command source

Delta's CP2000 and EC series devices currently support the CANopen communications interface driver, and the corresponding slave station numbers and communications speed parameters are as follows:

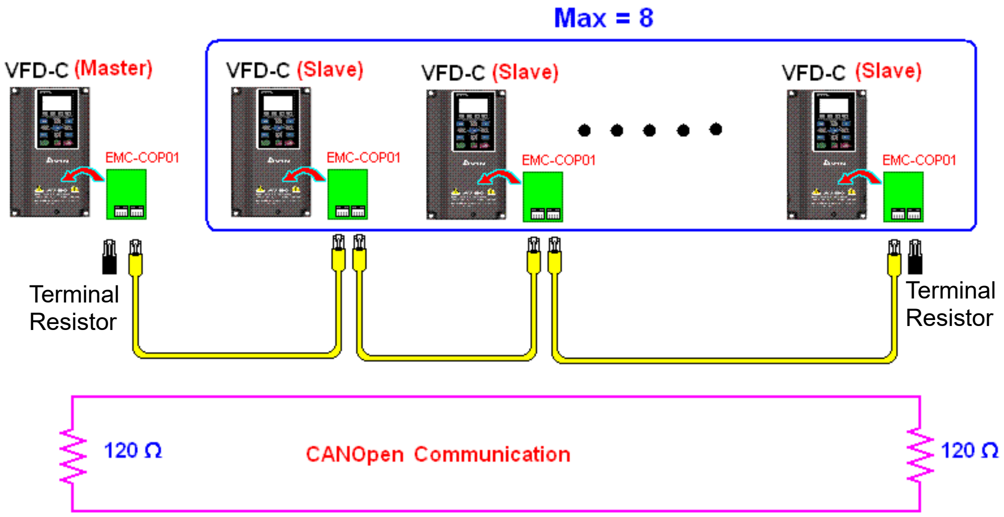
	Corresponding device parameters		Value	Definition
	CP2000	E-C		
Slave station address	09-36	09-20	0	Disable CANopen hardware interface
			1–127	CANopen Communication address
Communication speed	09-37	09-21	0	1 Mbps
			1	500 Kbps
			2	250 Kbps
			3	125 Kbps
			4	100 Kbps
			5	50 Kbps

Delta's A2 Servo currently supports the CANopen communications interface, and the corresponding slave station numbers and communications speed parameters are as follows:

	Corresponding device parameters	Value	Definition
	A2		
Slave station address	Pr.03-00	1–127	CANopen Communication address
Communication speed	Pr.03-01 bit8–11 XRXX	R= 0	125 Kbps
		R= 1	250 Kbps
		R= 2	500 Kbps
		R= 3	750 Kbps
		R= 4	1 Mbps
Control/command source	Pr.01-01	B	

Step 6: Connect hardware wiring

When performing wiring, note the head and tail terminal resistance; connection methods are as follows:



Step 7: Initiate control

After a program has been written and downloaded, switch the PLC mode to Run. Merely turn power to master and slave stations off and then on again.

Refer to CANMasterTest 1 vs. 2 driver.dvp

Example:

CP2000 driver one-to-two control

Step 1: Activating CANopen Master functions

☑ Pr.09-45 = 1 (initiates Master functions); restart power after completing setting, the status bar on the KPC-CC01 digital keypad will display "CAN Master".

☑ Pr.00-02 = 6 reset PLC (please note that this action will reset the program and PLC registers to the default values)

☑ Turn power off and on again.

☑ Use the KPC-CC01 digital keypad to set the PLC control mode as "PLC Stop" (if a newly-introduced driver is used, the blank internal PLC program will cause a PLFF warning code to be issued).

Step 2: Master memory correspondences

☑ Enable WPL

☑ Use keypad set PLC mode as Stop (PLC 2)

☑ WPL read D1070 to D1099, D2000 to D2799

☑ Set D2000 = 10 D2100 = 11

☑ Set D2100 2200 2300 2400 2500 2600 2700 = 0

☑ Download D2000 to D2799 settings

Step 3: Set the master's communications station number and communications speed

☑ When setting the master's station number (Pr.09-46, default is set as 100), make sure not to use the same number as a slave station.

☑ Set the CANopen communications speed as 1M (Pr.09-37 = 0); regardless of whether the driver is defined as a master or slave station, the communications speed is set via this parameter.

Step 4: Write program code

Real-time access: Can directly read/write to or from the corresponding D area.

Non real-time access:

Read command:

Use the CANRX command for reading. M1066 will be 1 when reading is complete; M1067 will be 1 if reading is successful, and M1067 will be 0 if an error has occurred.

Write command:

Use the CANTX command for writing. M1066 will be 1 when writing is complete; M1067 will be 1 if writing is successful, and M1067 will be 0 if an error has occurred.

Refresh command:

Use CANFLS command to refresh (if there are RW attributes, the master will write to the slave station; if there are RO attributes, the slave station will return the read values to the master); M1066 will be 1 if refresh has been completed; M1067 will be 1 if refresh is successful, and M1067 will be 0 if an error has occurred.

NOTE

When using CANRX, CANTX or CANFLS, internal implementation commands will wait until M1066 is completed before executing the next CANRX, CANTX or CANFLS.

Afterwards, download program to the driver (Please note that the PLC's default communications format is ASCII 7N2 9600, and the station number is 2. The WPL must therefore be modified, and the WPL setting pathway is **settings > communications settings**)

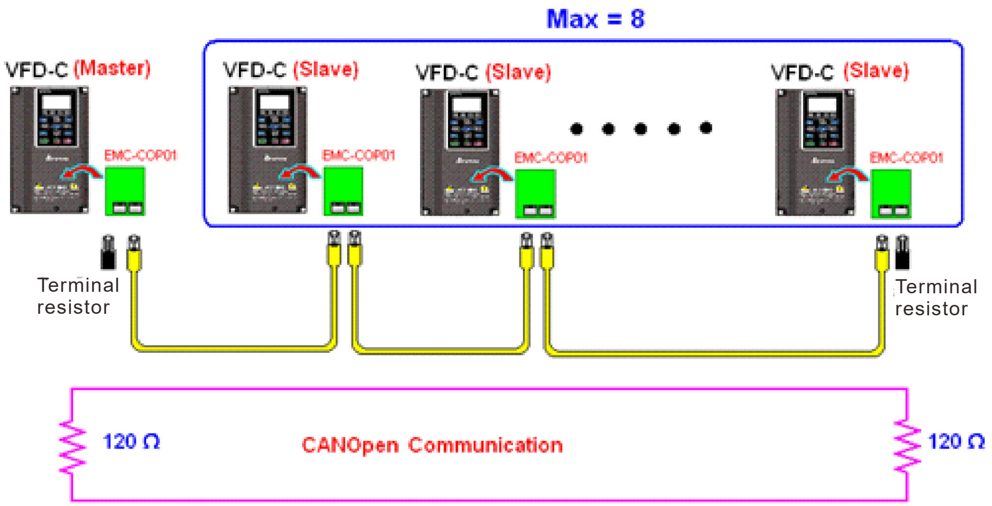
Step 5: Set the slave stations' station numbers and communications speed

Slave station no. 1: Pr.09-37 = 0 (Speed 1M)   Pr.09-36 = 10 (Node ID 10)

Slave station no. 2: Pr.09-37 = 0 (Speed 1M)   Pr.09-36 = 10 (Node ID 11)

Step 6: Connect hardware wiring

When performing wiring, note the head and tail terminal resistance; connection methods are as follows:



Step 7: Initiate control

After a program has been written and downloaded, switch the PLC mode to Run. Merely turn power to master and slave stations off and then on again.

Refer to CANMasterTest 1 vs. 2 driver.dvp

16-9 Explanation of various PLC speed mode controls

Speed mode supports SVC control. Under the speed mode of SVC control, it cannot be performed successfully unless finish motor parameter auto tuning ahead of time.

Control methods and settings are explained as follows:

Speed control:

Register table for speed mode:

Control special M

Special M	Description of Function	Attributes
M1025	Driver frequency = set frequency (ON)/driver frequency =0 (OFF)	RW
M1026	Driver operating direction FWD(OFF)/REV(ON)	RW
M1040	Hardware power (Servo On)	RW
M1042	Quick stop	RW
M1044	Pause (Halt)	RW
M1052	Lock frequency (lock, frequency locked at the current operating frequency)	RW

Status special M

Special M	Description of Function	Attributes
M1015	Frequency attained (when used together with M1025)	RO
M1056	Servo On Ready	RO
M1058	On Quick Stopping	RO

Control special D

Special D	Description of Function	Attributes
D1060	Mode setting (speed mode is 0)	RW

Status special D

Special D	Description of Function	Attributes
D1037	Converter output frequency (0.00–600.00)	RO
D1050	Actual operating mode (speed mode is 0)	RO

Speed mode control commands:

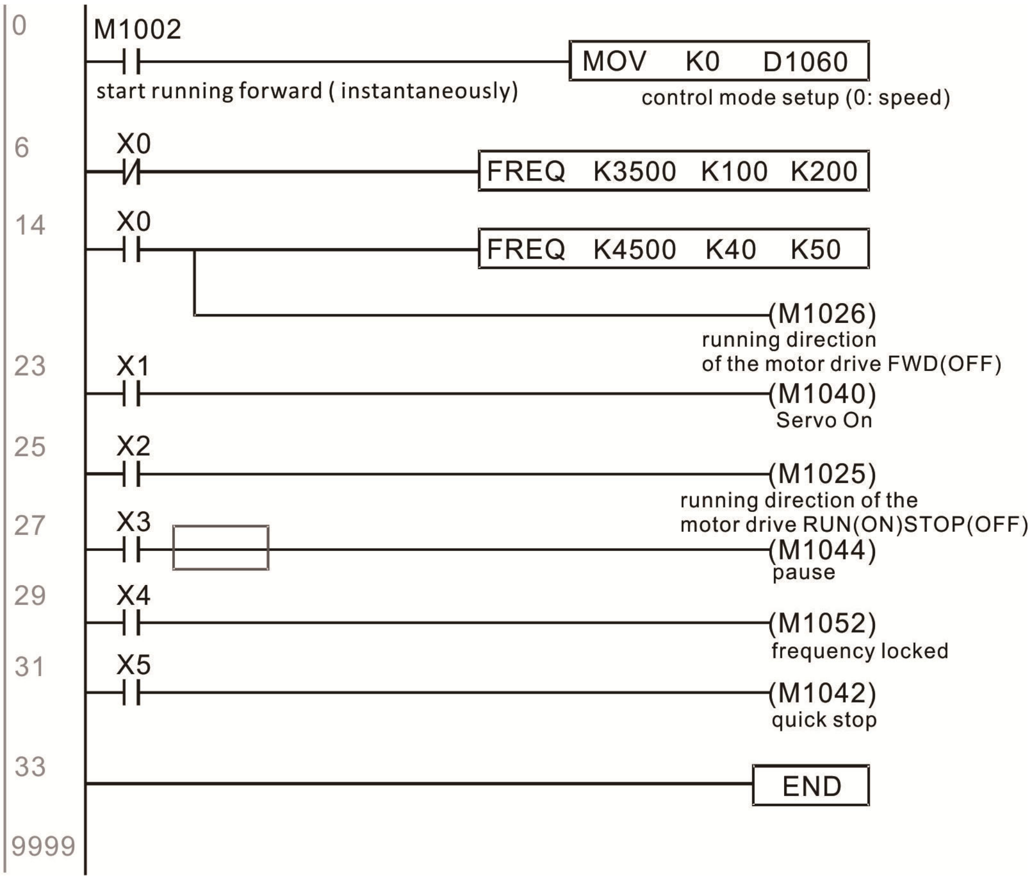
FREQ (P)	S1	S2	S3
	Target speed	The first acceleration time setting	The first deceleration time setting

Example of speed mode control:

Before performing speed control, if the SVC control method is used, setting of electromechanical parameters must first be completed.

1. Setting D1060 = 0 will shift the converter to the speed mode (default).
2. Use the FREQ command to control frequency, acceleration time, and deceleration time.
3. Set M1040 = 1, the driver will now be excited, but the frequency will be 0.
4. Set M1025 = 1, the driver frequency command will now jump to the frequency designated by FREQ, and acceleration/deceleration will be controlled on the basis of the acceleration time and deceleration time specified by FREQ.
5. M1052 can be used to lock the current operating frequency.
6. M1044 can be used to temporarily pause operation, and the deceleration method will comply with deceleration settings.

7. M1042 can be used to perform quick stop, and deceleration will be as quick as possible without giving rise to an error. (There may still be a jump error if the load is too large.)
8. Control user rights: M1040(Servo ON) > M1042(Quick Stop) >M1044(Halt) >M1052(LOCK)


0
M1002
start running forward (instantaneously)
MOV K0 D1060
control mode setup (0: speed)
6
X0
FREQ K3500 K100 K200
14
X0
FREQ K4500 K40 K50
M1026
running direction of the motor drive FWD(OFF)
23
X1
M1040
Servo On
25
X2
M1025
running direction of the motor drive RUN(ON)STOP(OFF)
27
X3
M1044
pause
29
X4
M1052
frequency locked
31
X5
M1042
quick stop
33
END
9999

16-10 Internal communications main node control

The protocol has been developed in order to facilitate the use of 485 instead of CANopen in certain application situations. The 485 protocol offers similar real-time characteristics as CANopen; this protocol can only be used on the CP2000 and CT2000 devices. The maximum number of slave devices is 8.

Internal communications have a master-slave structure. The initiation method is very simple:

Slave device:

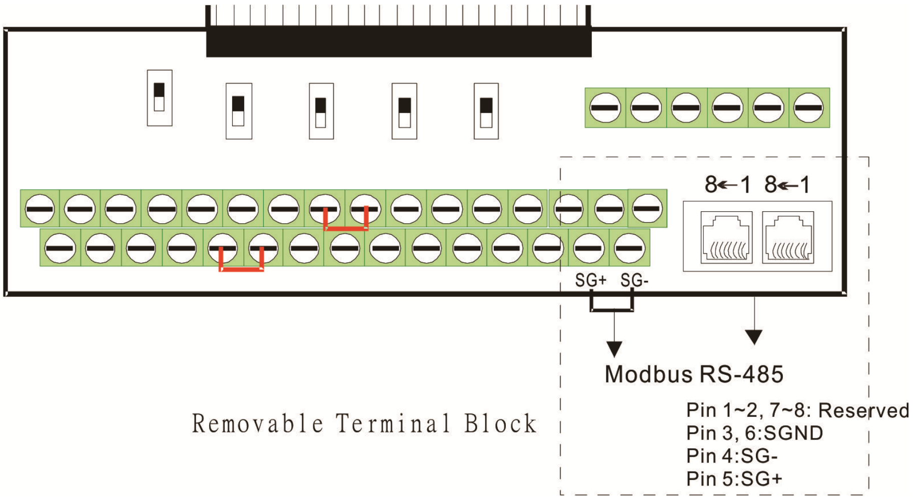
Set Pr.09-31 = -1 to -8 in order to access 8 nodes, and set Pr.00-20 = 1 to define the control source as 485 and access the reference sources that must be controlled, namely speed command (Pr.00-21 = 2). This will complete slave device settings. (PLC functions do not need to be activated)

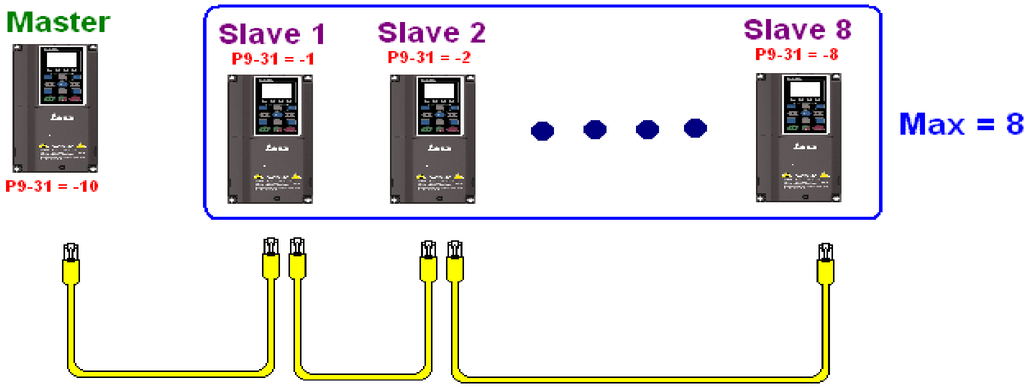
System:

Setting the master is even simpler; it is only necessary to set Pr.09-31 = -10, and enable the PLC.

Hardware wiring:

The master and slave stations are connected via the 485 serial port. The CP2000 provide two types of 485 serial port interfaces, see the figure below: (please refer to Section 06 Control terminals concerning detailed terminal connections)





Master programming: In a program, D1110 can be used to define a slave station to be controlled (1–8, if set as 0, can jump between 8 stations). Afterwards, M1035 is set as 1, and the memory positions of the master and slave stations will correspond. At this time, it is only necessary to send commands to the correlation slave station address to control that station. The following is a register table connected with internal communications:

Control special M

Special M	Description of Function	Attributes
M1035	Initiates internal communications control	RW

Control special D

Special D	Description of Function	Attributes
D1110	Internal node communications number 1–8 (set the station number of the slave station to be controlled)	RW

Special D	Description of Function				Attributes
	Definition	bit	User rights	Speed mode	
D1120 + 10 × N	Internal node N control command	0	4	Command functions	RW
		1	4	Reverse rotation requirements	
		2	4	-	
		3	3	Temporary pause	
		4	4	Frequency locking	
		5	4	JOG	
		6	2	Quick Stop	
		7	1	Servo ON	
		11–8	4	Speed interval switching	
		13–12	4	Deceleration time change	
		14	4	Enable bit13–8	
		15	4	Clear error code	
D1121 + 10 × N	Internal node N control mode			0	RW
D1122 + 10 × N	Internal node N reference command L			Speed command (no number)	RW
D1123 + 10 × N	Internal node N reference command H			-	RW

※ N = 0–7

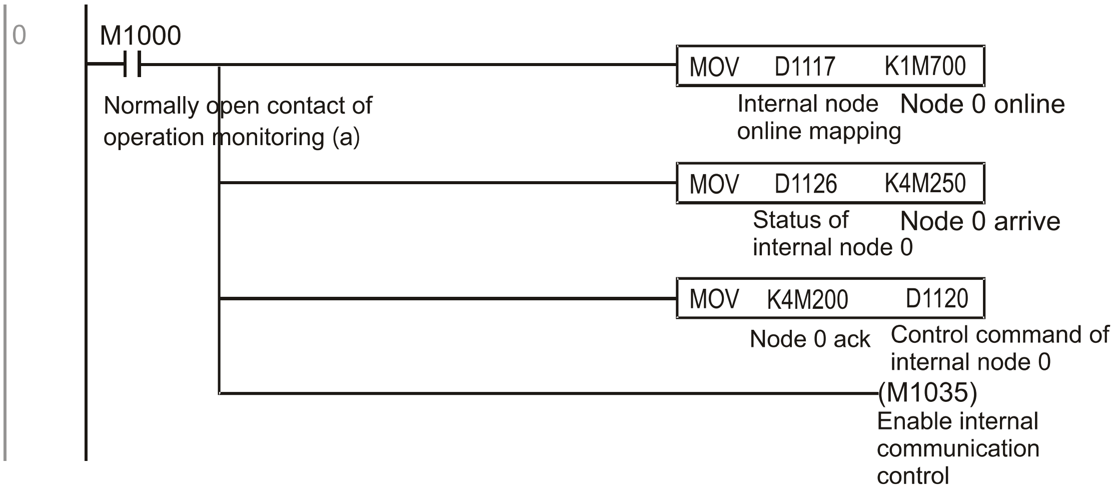
Status special D

Special D	Description of Function	Attributes
D1115	Internal node synchronizing cycle (ms)	RO
D1116	Internal node error (bit0 = slave device 1, bit1 = slave device 2,…bit7 = slave device 8)	RO
D1117	Internal node online correspondence (bit0 = slave device 1, bit1 = slave device 2,…bit7 = slave device 8)	RO

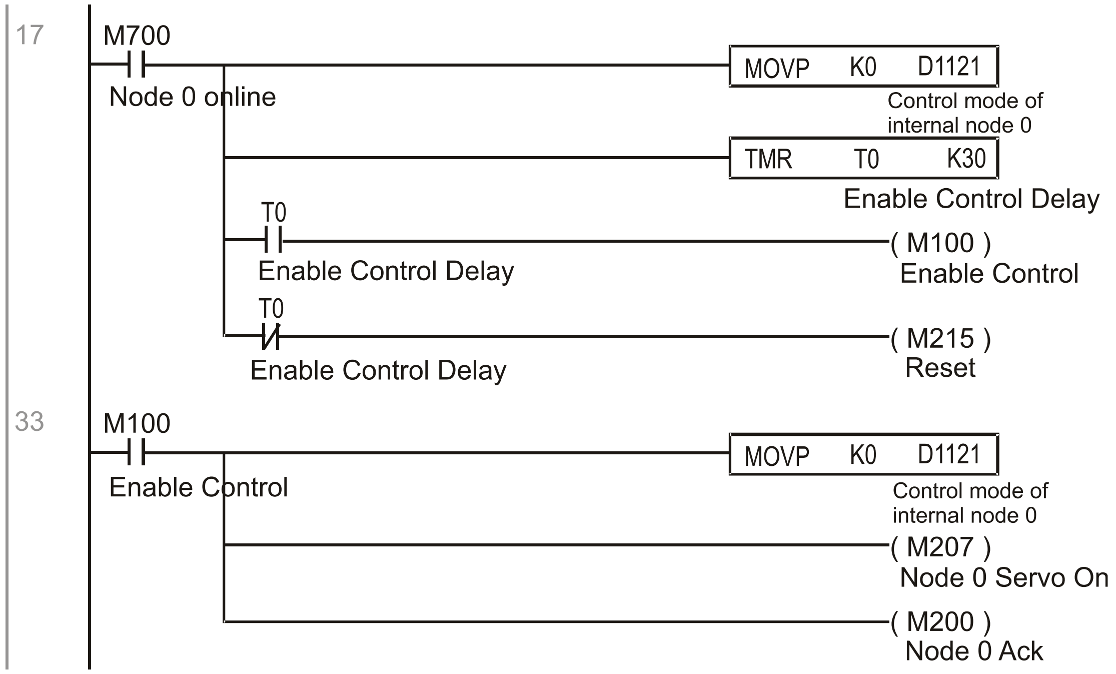
Special D	Description of Function		Attributes
	bit	Speed mode	
D1126 + 10 × N	0	Frequency command arrival	RO
	1	Clockwise	
		Counterclockwise:	
	2	Warning	
	3	Error	
	5	JOG	
	6	Quick Stop	
	7	Servo ON	
D1127 + 10 × N		Actual frequency	RO
D1128 + 10 × N		-	

※ N = 0–7

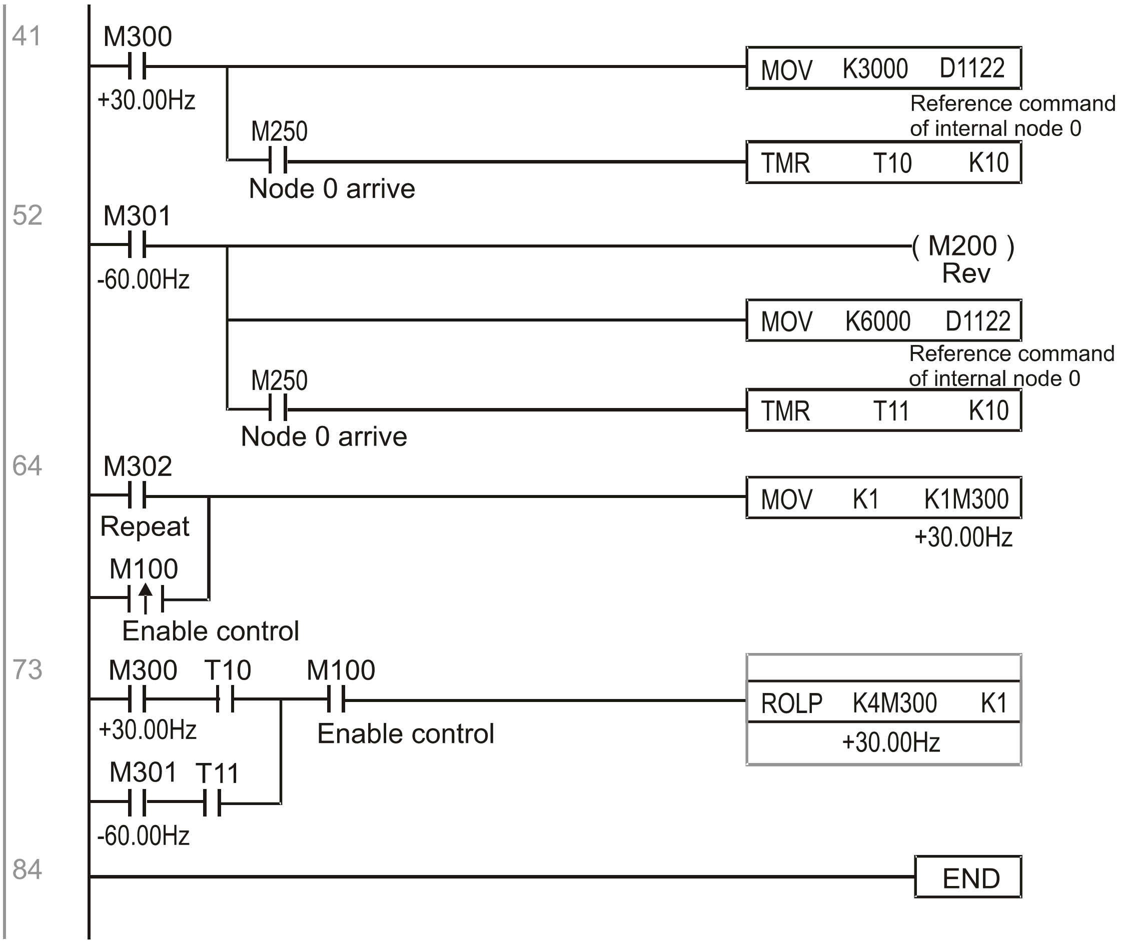
Example: Assume it is desired to control slave station 1 operation at frequencies of 30.00 Hz and 60.00 Hz, status, and online node correspondences:


0
M1000
Normally open contact of operation monitoring (a)
MOV D1117 K1M700
Internal node online mapping
Node 0 online
MOV D1126 K4M250
Status of internal node 0
Node 0 arrive
MOV K4M200 D1120
Node 0 ack
Control command of internal node 0
(M1035)
Enable internal communication control

When it is judged that slave station 1 is online, delay 3 sec. and begin control



It is required slave station 1 maintain forward rotation at 30.00 Hz for 1 sec., and maintain reverse rotation at 60.00 Hz for 1 sec., and repeat this cycle continuously.



16-11 Modbus remote IO control applications (use MODRW)

The CP2000's internal PLC supports 485 read/write functions, which can be realized using the MODRW command. However, the 485 serial port must be defined as available for the PLC's 485 use before writing a program, and the Pr.09-31 must be set as -12. After completing settings, the standard functions defined by 485 can be used to implement read/write commands at other stations. Communications speed is defined by Pr.09-01, the communications format is defined by Pr.09-04, and the PLC's current station number is defined by Pr.09-35. The CP2000 currently supports the functions read coil (0x01), read input (0x02), read register (0x03), write to single register (0x06), write to several coils (0x0F), and write to several registers (0x10). Explanations and the usage of these functions are provided as follows:

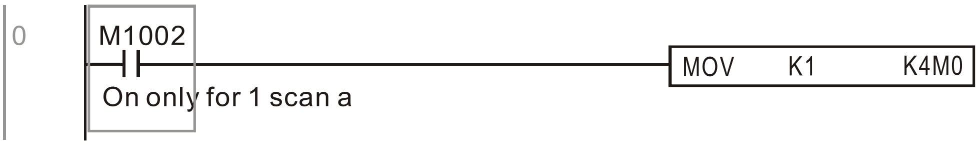
MODRW command					General meaning	Slave device is Delta's PLC meaning	Slave device is Delta's converter meaning
S1	S2	S3	S4	S5			
Node ID	Command	Address	Return: D area	Length:			
K3	H01	H500	D0	K18	Read coil (Bit)	Read 18 bits of data corresponding to slave station 3 PLC Y0 to Y21. This data is stored by bit 0 to 15 of this station's D0 and bit 0 to bit 3 of D1.	Does not support this function
K3	H02	H400	D10	K10	Read input (Bit)	Read 10 bits of data corresponding to slave station 3 PLC X0 to X11. This data is stored by bit 0 to 9 of this station's D10.	Does not support this function
K3	H03	H600	D20	K3	Read register (word)	Read 3 words of data corresponding to slave station 3 PLC T0 to T2. This data is stored by D20 to D22.	Read 3 words of data corresponding to slave station 3 converter parameters 06-00 to 06-02. This data is stored by D20 to D22
K3	H06	H610	D30	XX	Write to single register (word)	Write slave station 3 PLC's T16 to this station's D30 value	Write slave station 3 converter 06 to 16 parameter to this station's D30 value
K3	H0F	H509	D40	K10	Write to multiple coils (Bit)	Write slave station 3 PLC's Y11 to Y22 to bit 0 to 9 of D40.	Does not support this function
K3	H10	H602	D50	K4	Write to multiple registers (word)	Write slave station 3 PLC's T2 to T5 to D50 to D53	Write slave station 3 converter 06-02 to 06-05 parameters to this station's D50 to D53

※ XX indicates doesn't matter

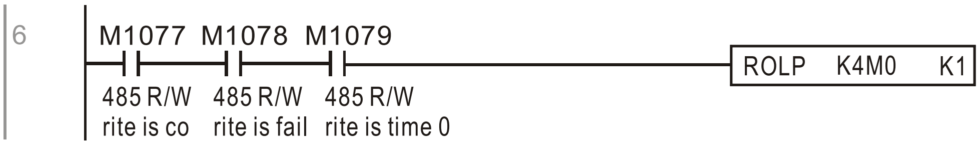
After implementing MODRW, the status will be displayed in M1077 (485 read/write complete), M1078 (485 read/write error), and M1079 (485 read/write time out). M1077 is defined so as to immediately revert to 0 after the MODRW command has been implemented. However, any of three situations—a report of no error, a data error report, or time out with no report—will cause the status of M1077 to change to On.

Example program: Testing of various functions

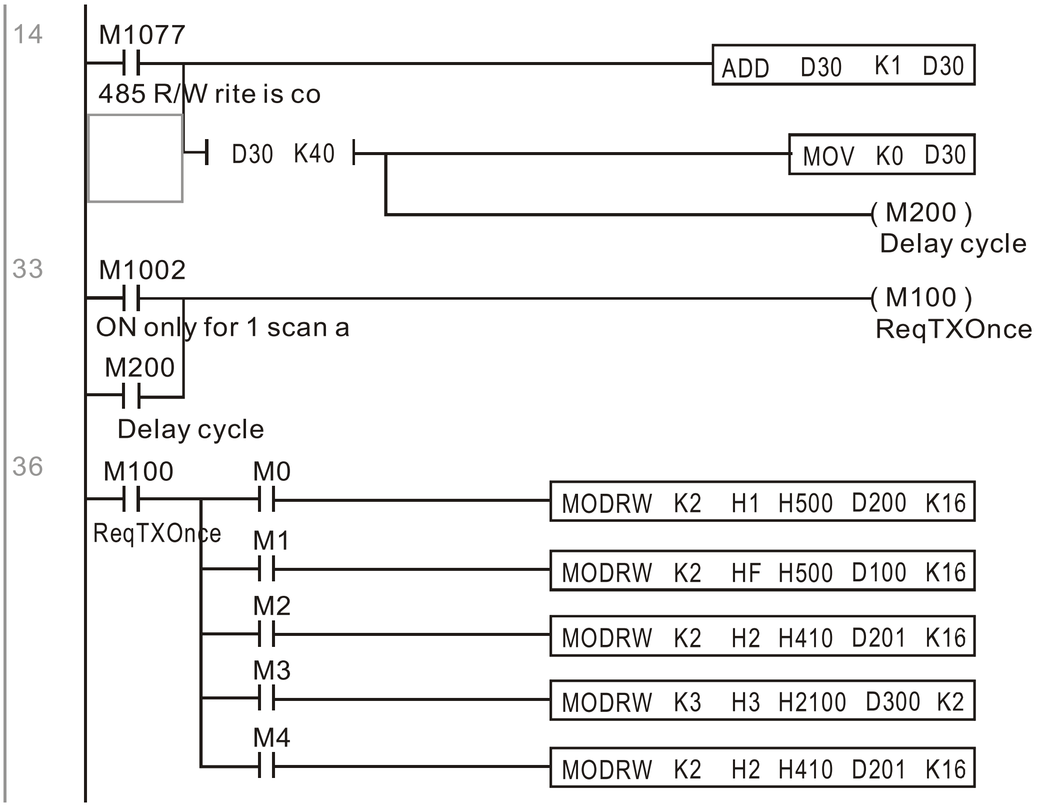
At the start, will cause the transmitted time sequence to switch to the first data unit.



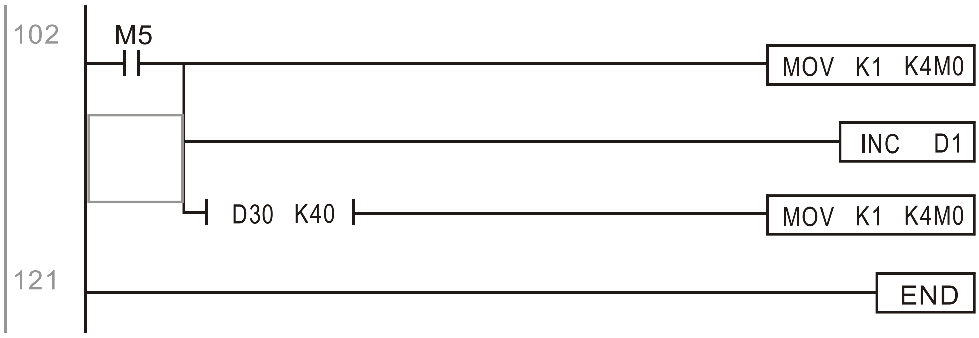
When the reported message indicates no error, it will switch to the next transmitted command



If time out occurs or an error is reported, the M1077 will change to ON. At this time, after a delay of 30 scanning cycles, it will re-issue the original command once



It will repeat after sending all commands



Practical applications:

Actual use to control the RTU-485 module.

Step 1: Set the communications format. Assume that the communications format is 115200, 8,N,2, RTU

CP2000：The default PLC station number is set as 2 (Pr.09-35)

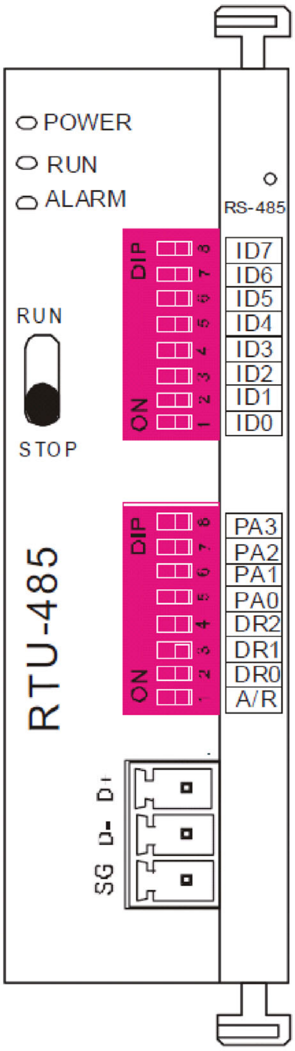
Pr.09-31 = -12 (COM1 is controlled by the PLC), Pr.09-01 = 115.2 (The communications speed is 115200)

Pr.09-04 = 13 (The format is 8,N,2, RTU)

RTU485: The station number = 8 (give example)

ID7	ID6	ID5	ID4	ID3	ID2	ID1	ID0
0	0	0	0	1	0	0	0

PA3	PA2	PA1	PA0	DR2	DR1	DR0	A/R
1	0	0	0	1	1	1	0



Communication station #:
ID0~ ID7 are defined as 2^0, 2^1, 2^2…2^6, 2^7

Communication protocol

PA3	PA2	PA1	PA0	A/R	Communication Protocol
OFF	OFF	OFF	OFF	ON	7,E,1、ASCII
OFF	OFF	OFF	ON	ON	7,O,1、ASCII
OFF	OFF	ON	OFF	ON	7,E,2、ASCII
OFF	OFF	ON	ON	ON	7,O,2、ASCII
OFF	ON	OFF	OFF	ON	7,N,2、ASCII
OFF	ON	OFF	ON	ON	8,E,1、ASCII
OFF	ON	ON	OFF	ON	8,O,1、ASCII
OFF	ON	ON	ON	ON	8,N,1、ASCII
ON	OFF	OFF	OFF	ON	8,N,2、ASCII
OFF	ON	OFF	ON	OFF	8,E,1、RTU
OFF	ON	ON	OFF	OFF	8,O,1、RTU
OFF	ON	ON	ON	OFF	8,N,1、RTU
ON	OFF	OFF	OFF	OFF	8,N,2、RTU

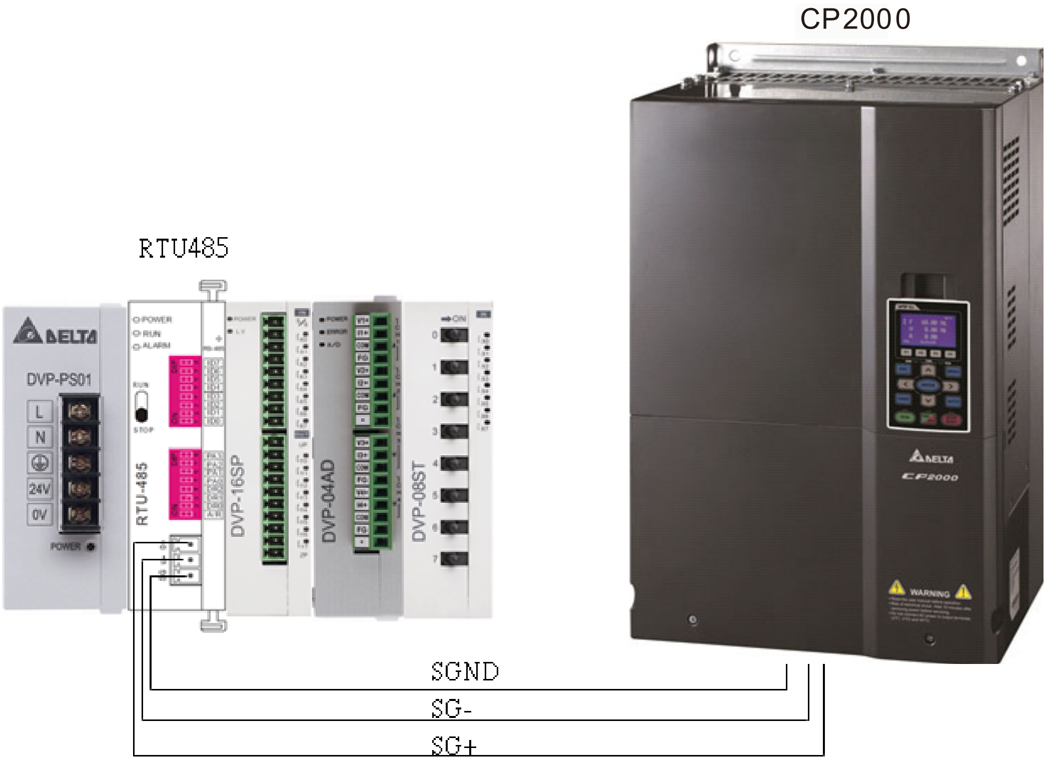
DR2	DR1	DR0	Communicaton Speed
OFF	OFF	OFF	1,200 bps
OFF	OFF	ON	2,400 bps
OFF	ON	OFF	4,800 bps
OFF	ON	ON	9,600 bps
ON	OFF	OFF	19,200 bps
ON	OFF	ON	38,400 bps
ON	ON	OFF	57,600 bps
ON	ON	ON	115,200 bps

Step 2: Install control equipment. We sequentially connect a DVP16-SP (8 IN 8 OUT), DVP-04AD (4 channels AD), DVP02DA (2 channels DA), and DVP-08ST (8 switches) to the RTU485.

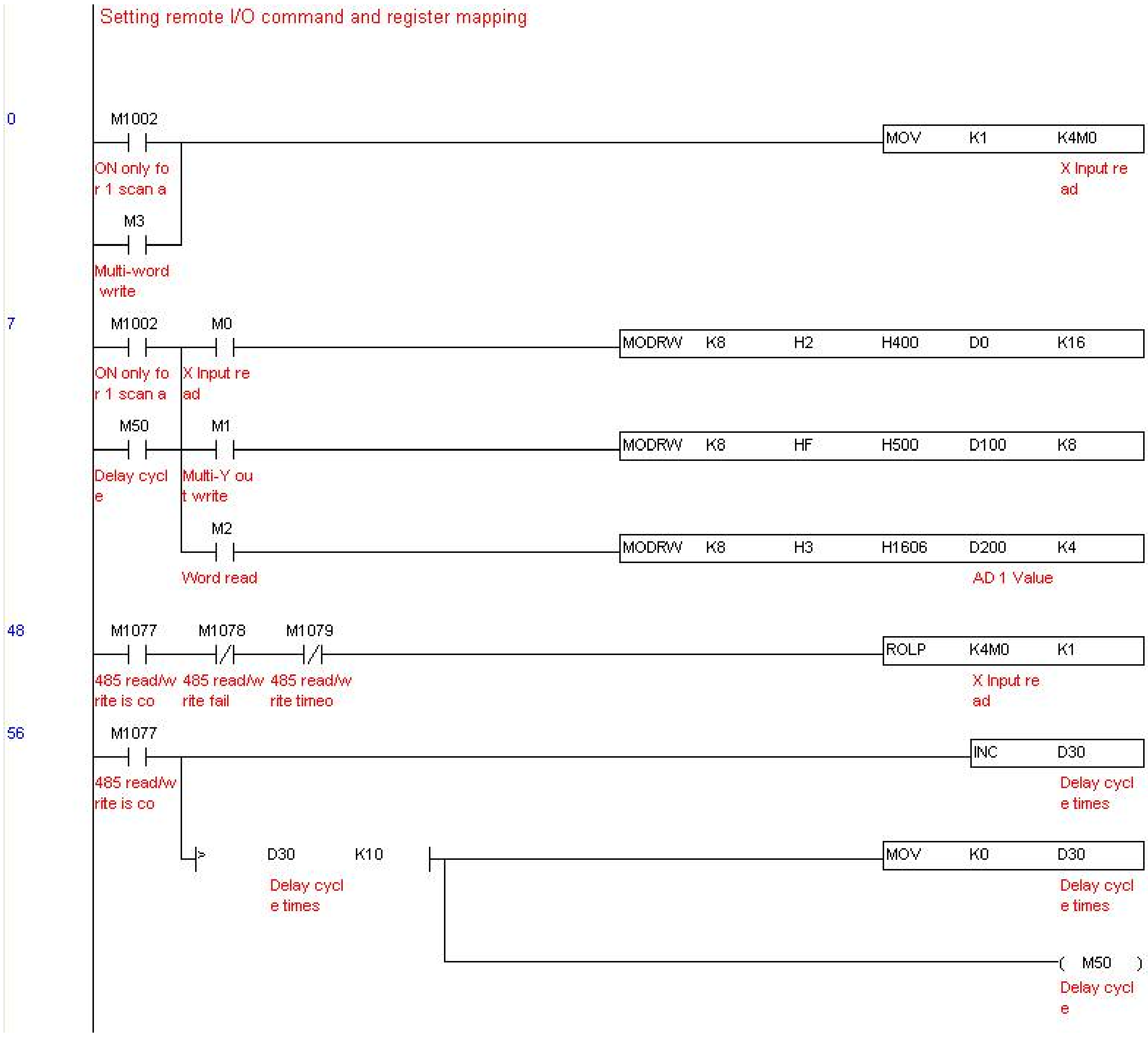
The following corresponding locations can be obtained from the RTU485's configuration definitions:

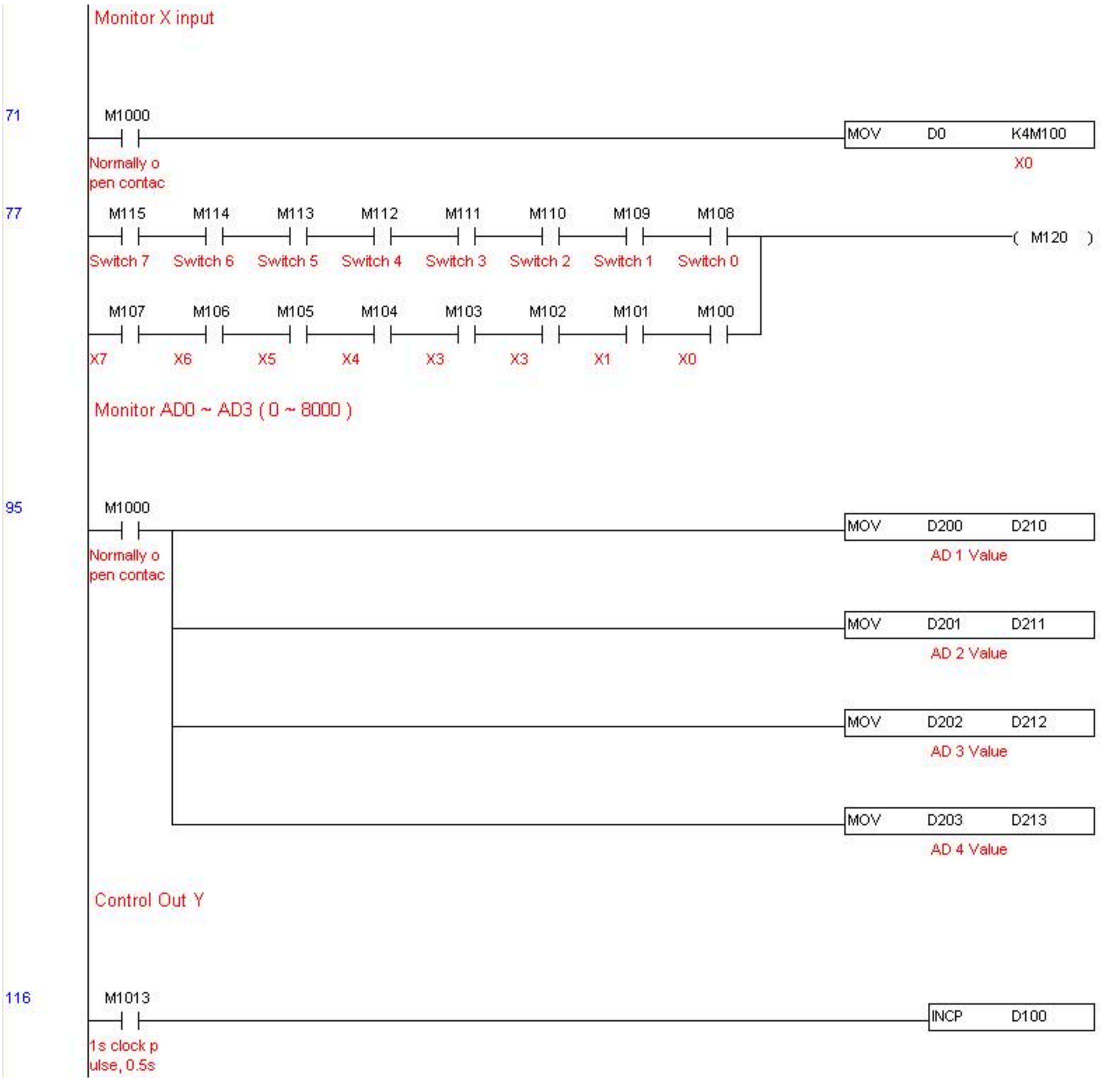
Module	Terminals	485 Address
DVP16-SP	X0–X7	0400H–0407H
	Y0–Y7	0500H–0507H
DVP-04AD	AD0–AD3	1600H–1603H
DVP02DA	DA0–DA1	1640H–1641H
DVP-08ST	Switch 0–7	0408H–040FH

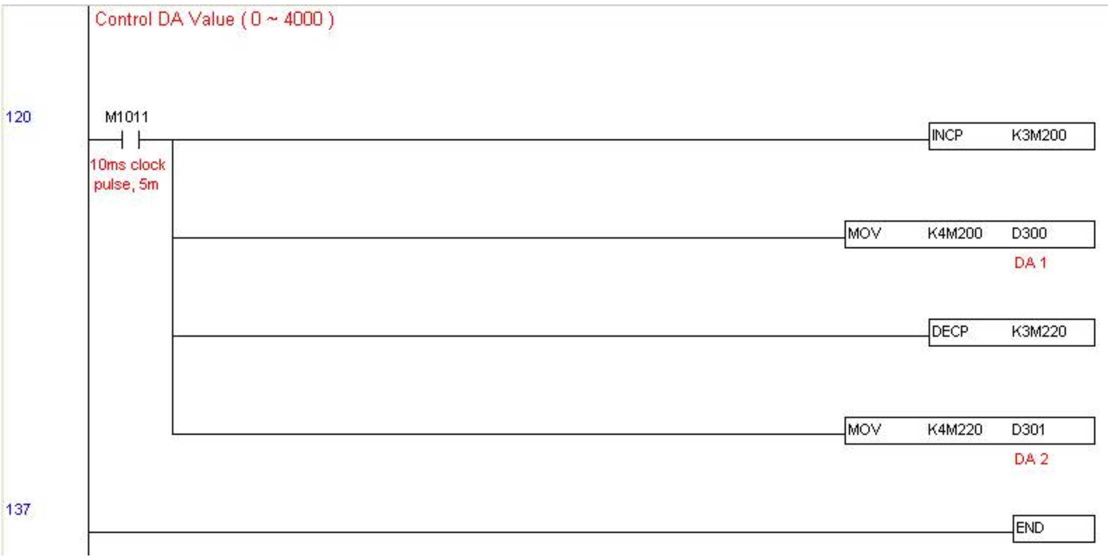
Step 3: Physical configuration



Step 4: Write to PLC program

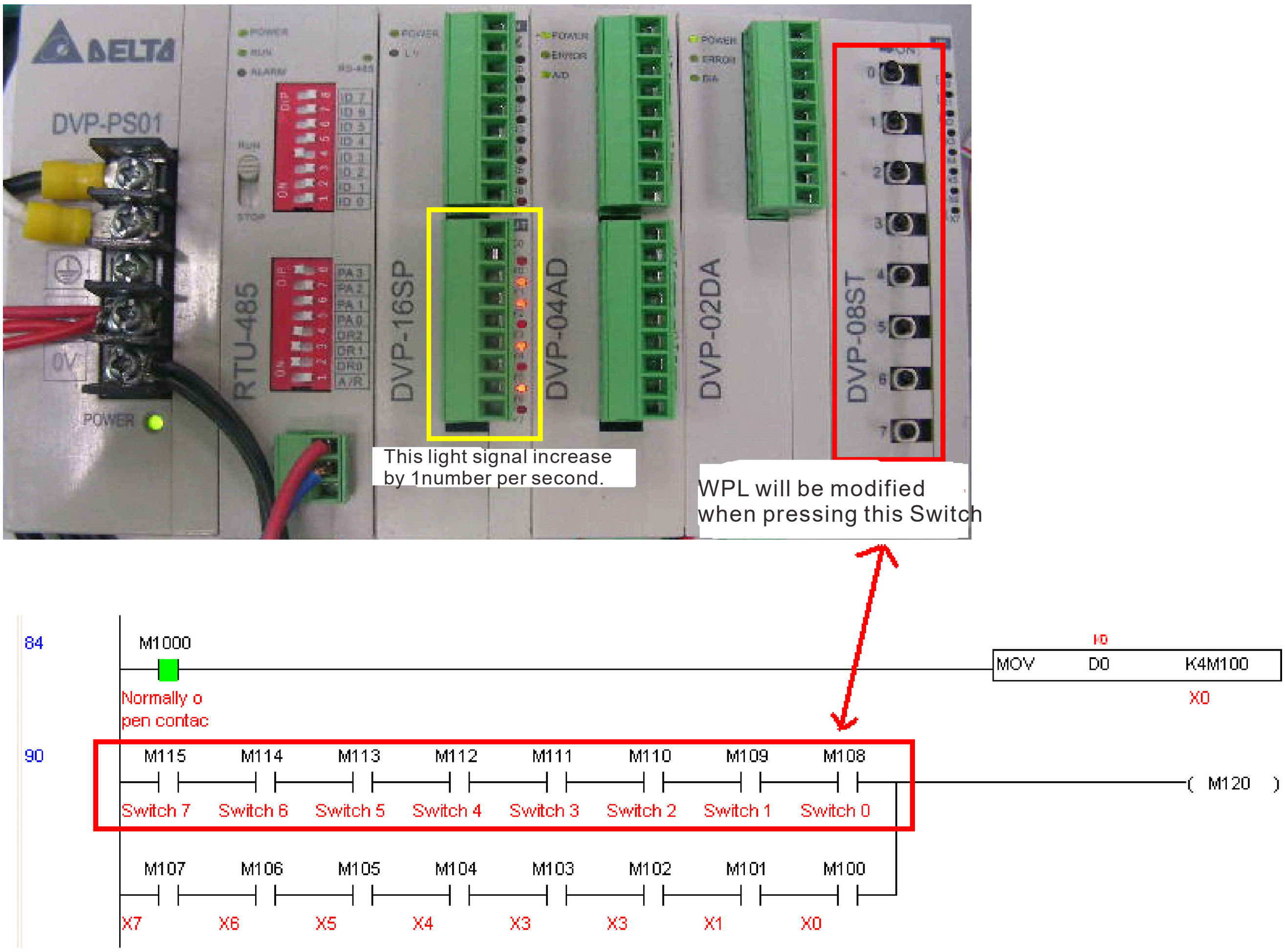



Monitor X input
71
M1000
Normally o pen contac
MOV D0 K4M100
X0
77
M115 M114 M113 M112 M111 M110 M109 M108
Switch 7 Switch 6 Switch 5 Switch 4 Switch 3 Switch 2 Switch 1 Switch 0
M120
M107 M106 M105 M104 M103 M102 M101 M100
X7 X6 X5 X4 X3 X3 X1 X0
Monitor AD0 ~ AD3 (0 ~ 8000)
95
M1000
Normally o pen contac
MOV D200 D210
AD 1 Value
MOV D201 D211
AD 2 Value
MOV D202 D212
AD 3 Value
MOV D203 D213
AD 4 Value
Control Out Y
116
M1013
1s clock p ulse, 0.5s
INCP D100


Control DA Value (0 ~ 4000)
120
M1011
10ms clock pulse, 5m
INCP K3M200
MOV K4M200 D300
DA 1
DECP K3M220
MOV K4M220 D301
DA 2
137
END

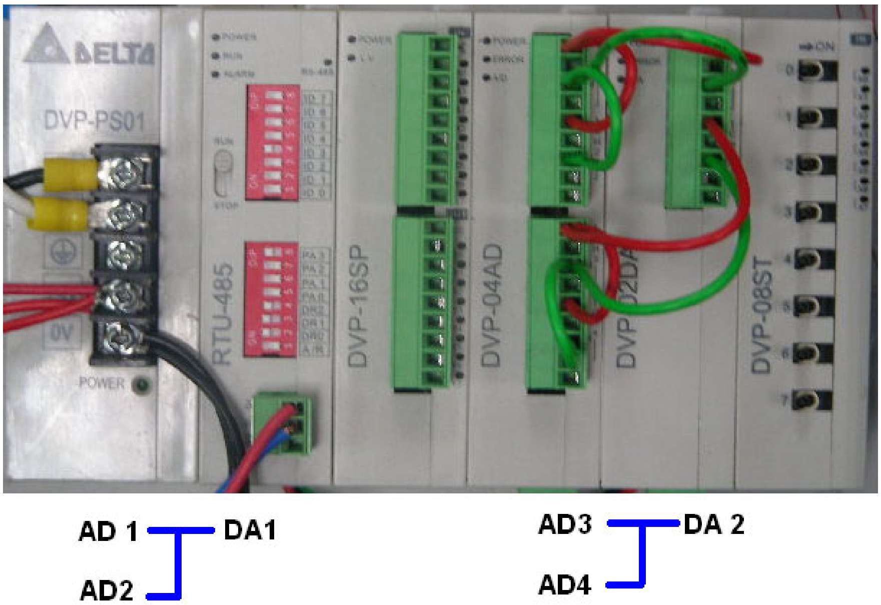
Step 5: Actual testing situation:

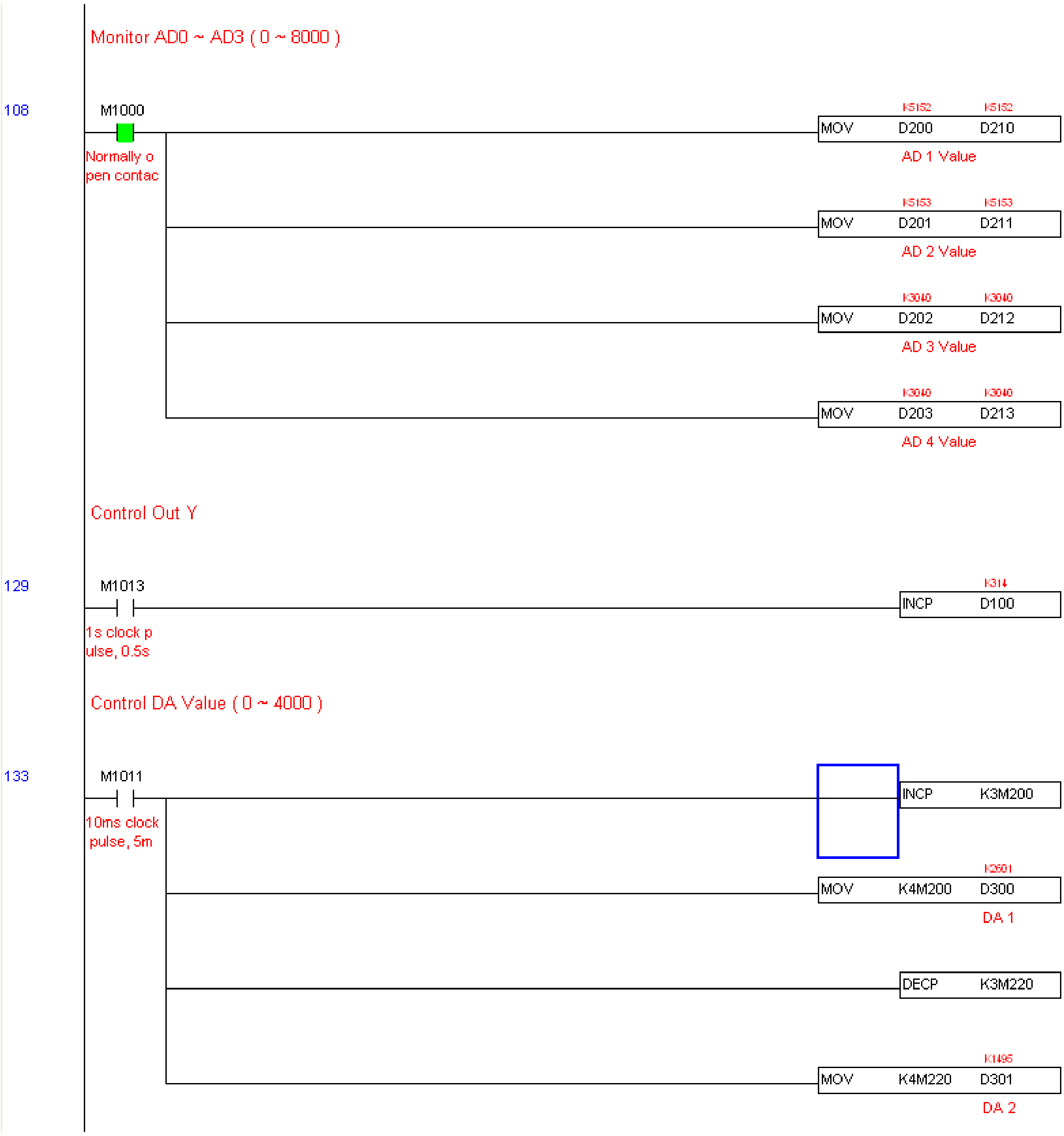
I/O testing: When the switch is activated, it can be discovered that the display corresponds to M115 - M108. Furthermore, it can be seen that one output point light is added every 1 sec. (the display uses a binary format)


This light signal increase by 1number per second.

WPL will be modified when pressing this Switch

AD DA testing: It can be discovered that D200 and D201 are roughly twice of the D300, and continue to increase progressively. For their part, the D202 and D203 are roughly twice of the D301, and continue to decrease progressively.




Monitor AD0 ~ AD3 (0 ~ 8000)
108
M1000
Normally o
pen contac
K5152
K5152
MOV D200 D210
AD 1 Value
K5153
K5153
MOV D201 D211
AD 2 Value
K3040
K3040
MOV D202 D212
AD 3 Value
K3040
K3040
MOV D203 D213
AD 4 Value
Control Out Y
129
M1013
1s clock p
ulse, 0.5s
K314
INCP D100
Control DA Value (0 ~ 4000)
133
M1011
10ms clock
pulse, 5m
INCP K3M200
K2601
MOV K4M200 D300
DA 1
DECP K3M220
K1496
MOV K4M220 D301
DA 2

16-12 Calendar functions

Keypad (KPC-CC01) should be connected, or the CP2000 cannot be used. Currently-support commands include TCMP (comparison of calendar data), TZCP (calendar data range comparison), TADD (calendar data addition), TSUB (calendar data subtraction), and TRD (calendar reading). Please refer to the explanation of relevant commands and functions for the usage of these commands.

In real applications, the internal PLC can judge whether calendar function have been activated; if they have been activated, calendar warning codes may be displayed in some situations. The basis for whether a calendar function has been activated is whether the program has written the calendar time (D1063 to D1069) in connection with the foregoing calendar commands or programs.

The calendar's time display is currently assigned to D1063 to D1069, and is defined as follows:

Special D	Item	Content	Attributes
D1063	Year (Western)	20xx (2000–2099)	RO
D1064	Weeks	1–7	RO
D1065	Month	1–12	RO
D1066	Day	1–31	RO
D1067	Hour	0–23	RO
D1068	Minute	0–59	RO
D1069	Second	0–59	RO

Calendar-related special M items are defined as follows:

Special D	Item	Attributes
M1068	Calendar time error	RO
M1076	Calendar time error or refresh time out	RO
M1036	Ignore calendar warning	RW

*When a program writes to the commands TCMP, TZCP, TADD, or TSUB, if it is discovered that a value exceeds the reasonable range, M1026 will be 1.

*When the keypad display is PLra (RTC correction warning) or PLrt (RTC time out warning), M1076 will be ON.

*When M1036 is 1, the PLC will ignore the calendar warning.

Calendar trigger warning code is defined as follows:

Warning	Description	Reset approach	Whether it affects PLC operation
PLra	Calendar time correction	Requires power restart	Will not have any effect
PLrt	Calendar time refresh time out	Requires power restart	Will not have any effect

*When the PLC's calendar functions are operating, if the keypad is replaced with another keypad, it will jump to PLra.

*When it is discovered at startup that the keypad has not been powered for more than 7 days, or the time is wrong, PLra will be triggered.

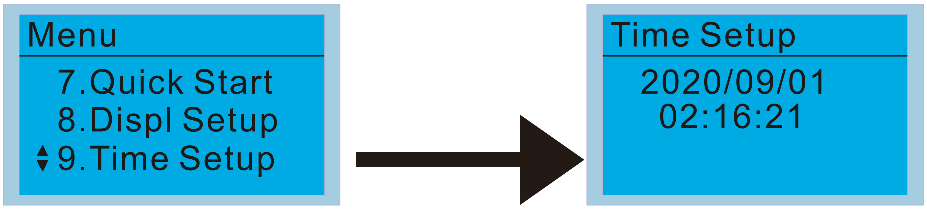
*When it is discovered that the CP2000 has no keypad in 10 sec. after start up, PLrt will be triggered.

*If the keypad is suddenly pulled out while the calendar is operating normally, and is not reconnected in 1 minute, PLrt will be triggered.

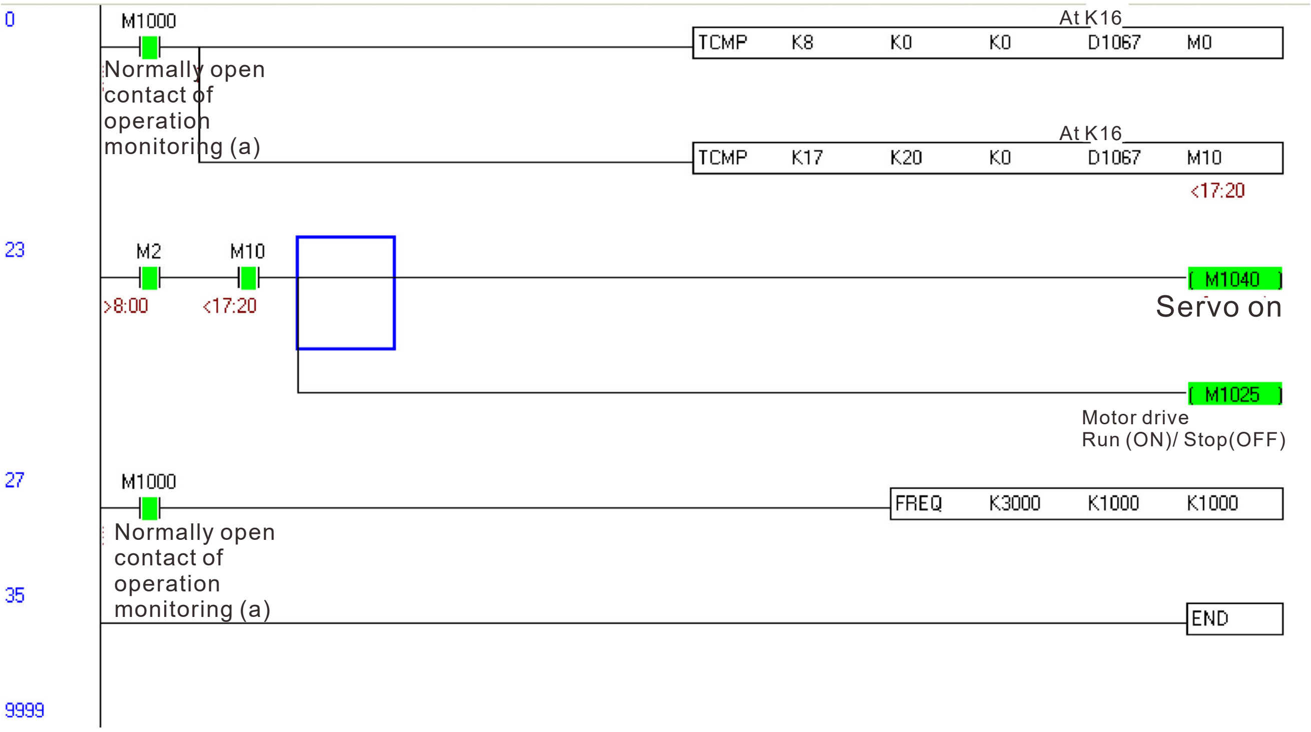
Practical applications:

We will perform a demo of simple applications.

We first correct the keypad time. After pressing Menu on the keypad, select the 9th time setting option. After selection, set the current time.



We set converter on during the period of 8:00–17:20, which allows us to write the following example


0
M1000
Normally open contact of operation monitoring (a)
At K16
TCMP K8 K0 K0 D1067 M0
At K16
TCMP K17 K20 K0 D1067 M10
<17:20
23
M2
M10
>8:00
<17:20
M1040
Servo on
M1025
Motor drive Run (ON)/ Stop(OFF)
27
M1000
Normally open contact of operation monitoring (a)
FREQ K3000 K1000 K1000
35
END
9999

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Chapter 17 Introduction to BACnet

1. About BACnet:

BACnet is an ASHRAE communication protocol for **b**uilding **a**utomation and **c**ontrol **net**works.
(ASHRAE: **A**merican **S**ociety of **H**eating, **R**efrigerating and Air-Conditioning **E**ngineers, Inc.).
CP2000's BACnet is based on version 2004.

BACnet's regulations are related to several kinds of physical layers' interfaces. The physical layer built inside CP2000 is achieved via MS/TP interface.

The BACnet of CP2000 supports a device type called B-ASC. B-ASC supports six types of services such as DS-RP-B, DS-RPM-B, DS-WP-B, DM-DDB-B, DM-DOB-B and DM-DCC-B.

2. CP2000 BACnet-Object and Property:

In CP2000, BACnet supports 3 object types: Device, AnalogValue (AV) and BinaryValue (BV). In each object type, we have the following table to show the Properties list:

Property ID		Object Type		
		Device	Analog Value	Binary Value
#4	ACTIVE TEXT			V
#11	APDU_TIMEOUT	V		
#12	APPLICATION_SOFTWARE_VERSION	V		
#28	DESCRIPTION	V	V	V
#30	DEVICE ADDRESS BINDING	V	V	
#36	EVENT STATE		V	V
#44	FIRMWARE_REVISION	V		
#46	INACTIVE TEXT			V
#62	MAX_APDU_LENGTH_ACCEPTED	V		
#63	MAX_INFO_FRAMES	V		
#64	MAX_MASTER	V		
#70	MODEL_NAME	V		
#73	NUMBER_OF_APDU_RETRIES	V		
#75	OBJECT_IDENTIFIER	V *1	V	V
#76	OBJECT_LIST	V		
#77	OBJECT_NAME	V *1	V	V
#79	OBJECT_TYPE	V	V	V
#81	OUT OF SERVICE		V	V
#85	PRESENT VALUE		V *2	V *2
#87	PRIORITY ARRAY		V *3	V *3
#96	PROTOCOL_OBJECT_TYPES_SUPPORTED	V		
#97	PROTOCOL_SERVICES_SUPPORTED	V		
#98	PROTOCOL_VERSION	V		

Property ID		Object Type		
		Device	Analog Value	Binary Value
#104	RELINQUISH DEFAULT		V *3	V *3
#107	SEGMENTATION_SUPPORTED	V		
#111	STATUS FLAGS		V	V
#112	SYSTEM_STATUS	V		
#117	UNITS		V	
#120	VENDOR_IDENTIFIER	V		
#121	VENDOR_NAME	V		
#139	PROTOCOL_REVISION	V		
#155	DATABASE_REVISION	V		

*1. The Object_ID and Object_Name Properties of Device are writeable.

*2. The Present_Value Property of some AV and BV objects is commandable.

*3. Only Commandable objects support Priority_Array and Relinquish_Default.

The AV objects, we have commandable and read-only cases.

- Commendable case: We can use Write_Service to access the Present_Value property of commandable AV objects. Thus, the commandable AV objects are linking to the Control_Word and Pr_Word in CP2000.
- Readonly case: We can use Read_Service to access the Present_Value property of readonly AV objects. Thus, these readonly AV objects are linking to the Status_Word in CP2000.

The BV objects, we also have commandable and readonly cases.

- Commendable case: We can use Write_Service to access the Present_Value property of commendable BV objects. Thus, the commandable BV objects are linking to the Control_Bit in CP2000.
- Readonly case: We can use Read_Service to access the Present_Value property of readonly BV objects. Thus, these readonly BV objects are linking to the Status_Bit in CP2000.

2.1 Commandable Analog Value Object

In CP2000, we have AV_000–AV_026 supporting commandable Present_Value property. For these AV_Objects, we also can use (Multi) Read_Service to access Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description	Unit
AV 000	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 001	RW	FreqRefValue	Frequency Reference Value	UNITS_HERTZ
AV 002	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 003	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 004	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 005	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 006	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 007	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 008	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 009	RW	Reserved	Reserved	UNITS_NO_UNITS

Object Number	R/W	Object Name	Object Description	Unit
AV 010	RW	Reserved	Reserved	UNITS_NO_UNITS
AV 011	RW	(P9-11 map set)	AV11 will modify data which is P9-11 mapping to	Depends
AV 012	RW	(P9-12 map set)	AV12 will modify data which is P9-12 mapping to	Depends
AV 013	RW	(P9-13 map set)	AV13 will modify data which is P9-13 mapping to	Depends
AV 014	RW	(P9-14 map set)	AV14 will modify data which is P9-14 mapping to	Depends
AV 015	RW	(P9-15 map set)	AV15 will modify data which is P9-15 mapping to	Depends
AV 016	RW	(P9-16 map set)	AV16 will modify data which is P9-16 mapping to	Depends
AV 017	RW	(P9-17 map set)	AV17 will modify data which is P9-17 mapping to	Depends
AV 018	RW	(P9-18 map set)	AV18 will modify data which is P9-18 mapping to	Depends
AV 019	RW	(P9-19 map set)	AV19 will modify data which is P9-19 mapping to	Depends
AV 020	RW	(P9-20 map set)	AV20 will modify data which is P9-20 mapping to	Depends
AV 021	RW	(P9-21 map set)	AV21 will modify data which is P9-21 mapping to	Depends
AV 022	RW	(P9-22 map set)	AV22 will modify data which is P9-22 mapping to	Depends
AV 023	RW	(P9-23 map set)	AV23 will modify data which is P9-23 mapping to	Depends
AV 024	RW	(P9-24 map set)	AV24 will modify data which is P9-24 mapping to	Depends
AV 025	RW	(P9-25 map set)	AV25 will modify data which is P9-25 mapping to	Depends
AV 026	RW	(P9-26 map set)	AV26 will modify data which is P9-26 mapping to	Depends

2.2 Status (Readonly) Analog Value Object

In CP2000, we have AV_027–AV_068 with read-only Present_Value property. For these AV_Objects, we do NOT have Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description	Unit
AV 027	R	Reserved	Reserved	UNITS_NO_UNITS
AV 028	R	Reserved	Reserved	UNITS_NO_UNITS
AV 029	R	Reserved	Reserved	UNITS_NO_UNITS
AV 030	R	Reserved	Reserved	UNITS_NO_UNITS
AV 031	R	Output frequency	Display output frequency(Hz)	UNITS_HERTZ
AV 032	R	Reserved	Reserved	UNITS_NO_UNITS
AV 033	R	Reserved	Reserved	UNITS_NO_UNITS
AV 034	R	Reserved	Reserved	UNITS_NO_UNITS
AV 035	R	Output torque (%)	Display output torque (%)	UNITS_PERCENT
AV 036	R	Reserved	Reserved	UNITS_NO_UNITS
AV 037	R	Reserved	Reserved	UNITS_NO_UNITS
AV 038	R	Reserved	Reserved	UNITS_NO_UNITS
AV 039	R	Status word	Display status word,made from BV16~BV31	UNITS_NO_UNITS
AV 040	R	Reserved	Reserved	UNITS_NO_UNITS
AV 041	R	Driver type code	Driver type code	UNITS_NO_UNITS
AV 042	R	Warn code	Warn code	UNITS_NO_UNITS

Object Number	R/W	Object Name	Object Description	Unit
AV 043	R	Error code	Error code	UNITS_NO_UNITS
AV 044	R	Output current	Display output current (Amp)	UNITS_AMPERES
AV 045	R	DC bus voltage	Display DC bus voltage (Volt)	UNITS_VOLTS
AV 046	R	Output Voltage	Display output voltage of U, V, W (Volt)	UNITS_VOLTS
AV 047	R	Count Value	Display counter value of TRG terminal	UNITS_NO_UNITS
AV 048	R	Power Angle	Display output power angle of U, V, W	UNITS_POWER_FACTOR
AV 049	R	Output Power	Display actual output power of U, V, W (kw)	UNITS_KILOWATTS
AV 050	R	IGBT temperature	Display the IGBT temperature	UNITS_DEGREES_CELSIUS
AV 051	R	Temperature of driver	Display the temperature of capacitance	UNITS_DEGREES_CELSIUS
AV 052	R	Real carry frequency	Display real carrier frequency of the drive (kHz)	UNITS_KILOHERTZ
AV 053	R	PID feedback value	Display PID feedback value (%)	UNITS_PERCENT
AV 054	R	Overload rate	Display overload condition (%)	UNITS_PERCENT
AV 055	R	Ground fail detect level	Display GND fail detect level (%)	UNITS_PERCENT
AV 056	R	DC bus ripple	Display DC bus voltage ripples (Volt)	UNITS_VOLTS
AV 057	R	Fan Speed	Fan speed of the drive (%)	UNITS_PERCENT
AV 058	R	Output speed(rpm)	Output speed(rpm)	UNITS_REVOLUTIONS_PER_MINUTE
AV 059	R	kW per Hour	kW per Hour	UNITS_KILOWATTS
AV 060	R	Multi-speed switch	Real multi-speed switch	UNITS_NO_UNITS
AV 061	R	AVI1 input value	0–10 V corresponds to 0–100%	UNITS_PERCENT
AV 062	R	ACI input value	4–20 mA/0–10 V corresponds to 0–100%	UNITS_PERCENT
AV 063	R	AVI2 input value	0–10 V corresponds to 0–100%	UNITS_PERCENT
AV 064	R	Digital input status	Refer to Pr.02-12	UNITS_NO_UNITS
AV 065	R	Digital output status	Refer to Pr.02-18	UNITS_NO_UNITS
AV 066	R	CPU pin status of DI	Corresponding CPU pin status of digital input	UNITS_NO_UNITS
AV 067	R	CPU pin status of DO	Corresponding CPU pin status of digital output	UNITS_NO_UNITS
AV 068	R	PLC D1043 value	PLC D1043 value	UNITS_NO_UNITS

2.3 Commandable Binary Value Object

In CP2000, we have BV_000–BV_015 supporting commandable Present_Value property. For these BV_Objects, we also can use (Multi) Read_Service to access Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description
BV 000	RW	ACTIVE CMD	(0)FreqCmd=0;(1)FreqCmd=FreqRefValue
BV 001	RW	FWD/REV CMD	(0)Forward; (1)Reverse
BV 002	RW	Reserved	Reserved
BV 003	RW	HALT CMD	(0)None;(1)Ramp Down to 0 Hz.
BV 004	RW	LOCK CMD	(0)None;(1)OutputFreq stays at current frequency
BV 005	RW	Reserved	Reserved
BV 006	RW	QSTOP CMD	(0)None;(1)Force driver quick stop
BV 007	RW	ServoPower CMD	(0)PowerOff(free run to stop);(1)PowerOn
BV 008	RW	Reserved	Reserved
BV 009	RW	Reserved	Reserved
BV 010	RW	Reserved	Reserved
BV 011	RW	Reserved	Reserved
BV 012	RW	Reserved	Reserved
BV 013	RW	Reserved	Reserved
BV 014	RW	Reserved	Reserved
BV 015	RW	RESET	RESET:(0)Do nothing;(1)Reset fault

2.4 Status (Readonly) Binary Value Object

In CP2000, we have BV_016–BV_031 with read-only Present_Value property. For these BV_Objects, we do NOT have Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description
BV 016	R	ARRIVE STATE	(0)Not yet;(1)Arrive (OutputFreq=FreqCmd)
BV 017	R	FWD/REV STATE	(0)Forward;(1)Reverse
BV 018	R	WARN STATE	(0)No Warn;(1)Occur Warn
BV 019	R	ERROR STATE	(0)No Error;(1)Occur Error
BV 020	R	Reserved	Reserved
BV 021	R	Reserved	Reserved
BV 022	R	QSTOP STATE	(0)No QSTOP;(1)Occur QSTOP
BV 023	R	Servo Power STATE	(0)PowerOff(free run to stop);(1)PowerOn
BV 024	R	Reserved	Reserved
BV 025	R	Reserved	Reserved
BV 026	R	Reserved	Reserved
BV 027	R	Reserved	Reserved
BV 028	R	Reserved	Reserved

Object Number	R/W	Object Name	Object Description
BV 029	R	Reserved	Reserved
BV 030	R	Reserved	Reserved
BV 031	R	Reserved	Reserved

3. Steps to setup the Pr about BACnet in CP2000

Related to BACnet function in CP2000, We have to configure 2 parts of Parameters

Part1. Setup parameters related to Communication at Pr_Group9.

Part2. Setup parameters related to System_Parameter at Pr_Group0.

Part1. Pr_Group9, Communication.

1-1. Set Pr.09-31 =1, BACnet is enabled, then the COM1_Port will be accessed by BACnet. When this is set, the COM1_Port communication format will be changed to RTU 8, N, 1.

(Note: The HW Pins of COM1_Port are shared by RJ45 and RS-485. When BACnet is enabled, BACnet will access the COM1_Port, that also means we can **NOT** have Modbus, PLC connections, VFDSoft and VFD Explorer by COM1_Port).

1-2. Set Pr.09-50, Default = 10, BACnet's MS/TP station number 0–127

1-3. Set Pr.09-51, Default = 38400, BACnet communication baud rate, 9600, 19200, 38400 or 76800 bps.

1-4. Set Pr.09-52 and Pr.09-53, The default setting of Device Object_Identifier is 0x000A (Pr.09-52=10, Pr.09-53=00). Device Object_Identifier is the combination of Pr.09-52 and Pr.09-53, thus the setting range can be 0–4194303.

For example, Pr.09-53=12(0x0C) and Pr.09-52 =3456(0x0D80), then the device Identifier's value =12*65536+3456 =789888(0x0C0D80).

1-5. Set Pr.09-55, Default =127, the highest allowable address for master nodes on the same MS/TP network. CP2000 base on this setting to know the Max search range.

1-6. Set Pr.09-56, setup the BACnet password. If setup is successful, the keypad will display 8888.

Part2. Pr_Group0, System Parameter.

2-1. Set Pr.00-20 =1, That means the source of the Frequency command is from RS-485 Interface (accessed by BACnet).

2-2. Set Pr.00-21 =2, That means the source of the Operation command is from RS-485 Interface (accessed by BACnet).

Here is a simple example:

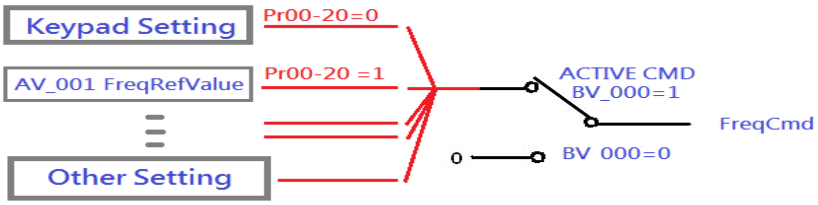
After setting up the 2 parts of Pr, we can enable the BACnet function in CP2000. Thus, we can access some BACnet objects to make the CP2000 driving motor Run or Stop.

Step1. Write_Service on AV_001, Present_Value =60.0 ➔ Setup Frequency Reference Value.

Step2. Write_Service on BV_007, Present_Value =Active. ➔ Setup Servo Power CMD.

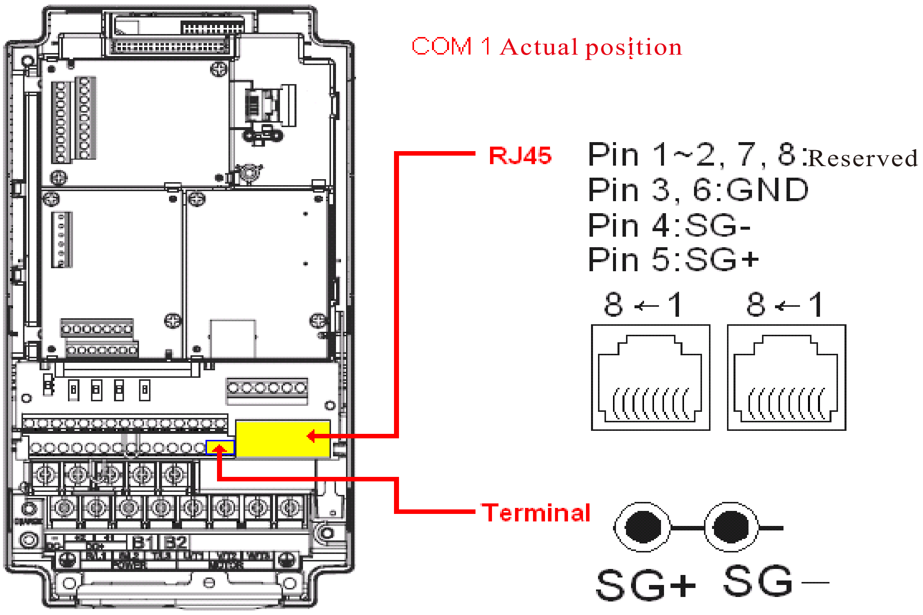
Step3. Write_Service on BV_000, Present_Value =Active. ➔ Setup Active CMD.

Step4. Read_Service on AV_031, Present_Value ➔ User can know the Output frequency.



PS. In CP2000, base on different Pr setting or IO setting, we can make FreqCmd with different source of Reference Value. Please check the usage of Keypad, Pr and IO setting for more detail information.

- Connection of the communication cable as shown in the below diagram.
  Please note that HW Pins of COM1_Port are shared by RJ45 and RS-485. That means user can use RJ45_cable or RS-485_lines to access the COM1_Port.
  When BACnet is enabled, COM1_Port will be dominated by BACnet function. Under this condition, user will not be able to have Modbus VFD Soft, VFD Explorer or PLC function on COM1_Port.



BACnet Protocol Implementation Conformance Statement

Date：July 24, 2014

Vendor Name: Delta Electronics, Inc.

Product Name: CP2000

Product Model Number: VFD-CP2000

Applications Software Version: Ver 01.04- yyyymm **Firmware Revision:** Ver 01.04 **BACnet Protocol Revision:** 7

Product Description:

Delta VFD-CP2000 is a Variable Frequency AC motor Drive with BACnet embedded.

In VFD-CP2000, the BACnet connection is by MS/TP, RS-485-based. VFD-CP2000 provides a BACnet communication function that permits it as a server and supports BIBBs defined by the BACnet B-ASC. VFD-CP2000 BACnet provides the capability to control and monitor the VFD-CP2000 machine.

BACnet Standardized Device Profile (Annex L):

☐ **BACnet Operator Workstation (B-OWS)_**
☐ **BACnet Building Controller (B-BC)**
☐ **BACnet Advanced Application Controller (B-AAC)_**
■ **BACnet Application Specific Controller (B-ASC)**
☐ **BACnet Smart Sensor (B-SS)**
☐ **BACnet Smart Actuator (B-SA)**

List all BACnet Interoperability Building Blocks Supported (Annex K):

Data Sharing BIBBs

Data Sharing-ReadProperty-B (DS-RP-B)
Data Sharing-WriteProperty-B (DS-WP-B)
Data Sharing-ReadPropertyMultiple-B (DS-RPM-B)

Device and Network Management BIBBs

Device Management-Dynamic Device Binding-B (DM-DDB-B)
Device Management-Dynamic Object Binding-B (DM-DOB-B)
Device Management-DeviceCommunicationControl-B (DM-DCC-B)

Segmentation Capability:

☐ Segmented requests supported Window Size ____________________
☐ Segmented responses supported Window Size ________________

Standard Object Types Supported:

Analog Value
Binary Value
Device

Object instantiation is static. Refer to table at end of this document for object details.

Data Link Layer Options:

☐ BACnet IP, (Annex J)

☐ BACnet IP, (Annex J), Foreign Device

☐ ISO 8802-3, Ethernet (Clause 7)

☐ ANSI/ATA 878.1, 2.5 Mb. ARCNET (Clause 8)

☐ ANSI/ATA 878.1, RS-485 ARCNET (Clause 8), baud rate(s) ____________

■ MS/TP master (Clause 9), baud rate(s): 9600, 19200, 38400, 76800

☐ MS/TP slave (Clause 9), baud rate(s): ________

☐ Point-To-Point, EIA 232 (Clause 10), baud rate(s):______

☐ Point-To-Point, modem, (Clause 10), baud rate(s): _____

☐ LonTalk, (Clause 11), medium: __________

☐ Other: _________

Device Address Binding:

Is static device binding supported? (This is currently necessary for two-way communication with MS/TP slaves and certain other devices.) ☐Yes ■No

Networking Options:

☐ Router, Clause 6 - List all routing configurations, e.g., ARCNET-Ethernet, Ethernet-MS/TP, etc.

☐ Annex H, BACnet Tunneling Router over IP

☐ BACnet/IP Broadcast Management Device (BBMD)

Does the BBMD support registrations by Foreign Devices? ☐ Yes ☐ No

Character Sets Supported:

Indicating support for multiple character sets does not imply that they can all be supported simultaneously.

■ ANSI X3.4

☐ ISO 10646 (UCS-2)

☐ IBM™/Microsoft™ DBCS

☐ ISO 10646 (UCS-4)

☐ ISO 8859-1

☐ JIS C 6226

If this product is a communication gateway, describe the types of non-BACnet equipment/networks(s) that the gateway supports:

____

____

____

____

The Properties of Objects

Property ID		Object Type		
		Device	**Analog Value**	**Binary Value**
#4	ACTIVE TEXT			V
#11	APDU_TIMEOUT	V		
#12	APPLICATION_SOFTWARE_VERSION	V		
#28	DESCRIPTION	V	V	V
#30	DEVICE ADDRESS BINDING	V	V	
#36	EVENT STATE		V	V
#44	FIRMWARE_REVISION	V		
#46	INACTIVE TEXT			V
#62	MAX_APDU_LENGTH_ACCEPTED	V		
#63	MAX_INFO_FRAMES	V		
#64	MAX_MASTER	V		
#70	MODEL_NAME	V		
#73	NUMBER_OF_APDU_RETRIES	V		
#75	OBJECT_IDENTIFIER	**V *1**	V	V
#76	OBJECT_LIST	V		
#77	OBJECT_NAME	**V *1**	V	V
#79	OBJECT_TYPE	V	V	V
#81	OUT OF SERVICE		V	V
#85	PRESENT VALUE		**V *2**	**V *2**
#87	PRIORITY ARRAY		V *3	V *3
#96	PROTOCOL_OBJECT_TYPES_SUPPORTED	V		
#97	PROTOCOL_SERVICES_SUPPORTED	V		
#98	PROTOCOL_VERSION	V		
#104	RELINQUISH DEFAULT		V *3	V *3
#107	SEGMENTATION_SUPPORTED	V		
#111	STATUS FLAGS		V	V
#112	SYSTEM_STATUS	V		
#117	UNITS		V	
#120	VENDOR_IDENTIFIER	V		
#121	VENDOR_NAME	V		
#139	PROTOCOL_REVISION	V		
#155	DATABASE_REVISION	V		

*1. The Object_ID and Object_Name Properties of Device are writeable.

*2. The Present_Value Property of some AV and BV objects are commandable.

*3. Only Commandable objects support Priority_Array and Relinquish_Default.

- **Commandable Analog Value Object**

  In VFD-CP2000, we have AV_000–AV_026 supporting commandable Present_Value property. In these AV_Objects, we also can use (Multi) Read_Service to access Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description	Unit
AV 000	RW	AV_000_Reserved	Reserved	UNITS_NO_UNITS
AV 001	RW	AV_001_FreqRefValue	Frequency Reference Value	UNITS_HERTZ
AV 002	RW	AV_002_Reserved	Reserved	UNITS_NO_UNITS
AV 003	RW	AV_003_Reserved	Reserved	UNITS_NO_UNITS
AV 004	RW	AV_004_Reserved	Reserved	UNITS_NO_UNITS
AV 005	RW	AV_005_Reserved	Reserved	UNITS_NO_UNITS
AV 006	RW	AV_006_Reserved	Reserved	UNITS_NO_UNITS
AV 007	RW	AV_007_Reserved	Reserved	UNITS_NO_UNITS
AV 008	RW	AV_008_Reserved	Reserved	UNITS_NO_UNITS
AV 009	RW	AV_009_Reserved	Reserved	UNITS_NO_UNITS
AV 010	RW	AV_010_Reserved	Reserved	UNITS_NO_UNITS
AV 011	RW	AV_011_P9-11 map set= -----	AV11 will modify data which is P9-11 mapping to	Depends
AV 012	RW	AV_012_P9-12 map set= -----	AV12 will modify data which is P9-12 mapping to	Depends
AV 013	RW	AV_013_P9-13 map set= -----	AV13 will modify data which is P9-13 mapping to	Depends
AV 014	RW	AV_014_P9-14 map set= -----	AV14 will modify data which is P9-14 mapping to	Depends
AV 015	RW	AV_015_P9-15 map set= -----	AV15 will modify data which is P9-15 mapping to	Depends
AV 016	RW	AV_016_P9-16 map set= -----	AV16 will modify data which is P9-16 mapping to	Depends
AV 017	RW	AV_017_P9-17 map set= -----	AV17 will modify data which is P9-17 mapping to	Depends
AV 018	RW	AV_018_P9-18 map set= -----	AV18 will modify data which is P9-18 mapping to	Depends
AV 019	RW	AV_019_P9-19 map set= -----	AV19 will modify data which is P9-19 mapping to	Depends
AV 020	RW	AV_020_P9-20 map set= -----	AV20 will modify data which is P9-20 mapping to	Depends
AV 021	RW	AV_021_P9-21 map set= -----	AV21 will modify data which is P9-21 mapping to	Depends
AV 022	RW	AV_022_P9-22 map set= -----	AV22 will modify data which is P9-22 mapping to	Depends
AV 023	RW	AV_023_P9-23 map set= -----	AV23 will modify data which is P9-23 mapping to	Depends
AV 024	RW	AV_024_P9-24 map set= -----	AV24 will modify data which is P9-24 mapping to	Depends
AV 025	RW	AV_025_P9-25 map set= -----	AV25 will modify data which is P9-25 mapping to	Depends
AV 026	RW	AV_026_P9-26 map set= -----	AV26 will modify data which is P9-26 mapping to	Depends

- **Status (Readonly) Analog Value Object**

In VFD-CP2000, we have AV_027–AV_068 with read-only Present_Value property. In these AV_Objects, we do NOT have Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description	Unit
AV 027	R	AV_027_Reserved	Reserved	UNITS_NO_UNITS
AV 028	R	AV_028_Reserved	Reserved	UNITS_NO_UNITS
AV 029	R	AV_029_Reserved	Reserved	UNITS_NO_UNITS
AV 030	R	AV_030_Reserved	Reserved	UNITS_NO_UNITS
AV 031	R	AV_031_Output frequency	Display output frequency(Hz)	UNITS_HERTZ
AV 032	R	AV_032_Reserved	Reserved	UNITS_NO_UNITS
AV 033	R	AV_033_Reserved	Reserved	UNITS_NO_UNITS
AV 034	R	AV_034_Reserved	Reserved	UNITS_NO_UNITS
AV 035	R	AV_035_Output torque (%)	Display output torque (%)	UNITS_PERCENT
AV 036	R	AV_036_Reserved	Reserved	UNITS_NO_UNITS
AV 037	R	AV_037_Reserved	Reserved	UNITS_NO_UNITS
AV 038	R	AV_038_Reserved	Reserved	UNITS_NO_UNITS
AV 039	R	AV_039_Status word	Display status word,made from BV16~BV31	UNITS_NO_UNITS
AV 040	R	AV_040_Reserved	Reserved	UNITS_NO_UNITS
AV 041	R	AV_041_Driver type code	Driver type code	UNITS_NO_UNITS
AV 042	R	AV_042_Warn code	Warn code	UNITS_NO_UNITS
AV 043	R	AV_043_Error code	Error code	UNITS_NO_UNITS
AV 044	R	AV_044_Output current	Display output current(Amp)	UNITS_AMPERES
AV 045	R	AV_045_DC-bus voltage	Display DC-BUS voltage(Volt)	UNITS_VOLTS
AV 046	R	AV_046_Output Voltage	Display output voltage of U, V, W(Volt)	UNITS_VOLTS
AV 047	R	AV_047_Count Value	Display counter value of TRG terminal	UNITS_NO_UNITS
AV 048	R	AV_048_Power Angle	Display output power angle of U, V, W	UNITS_POWER_FACTOR
AV 049	R	AV_049_Output Power	Display actual output power of U, V, W(kw)	UNITS_KILOWATTS
AV 050	R	AV_050_IGBT temperature	Display the IGBT temperature	UNITS_DEGREES_CELSIUS
AV 051	R	AV_051_Temperature of driver	Display the temperature of capacitance	UNITS_DEGREES_CELSIUS
AV 052	R	AV_052_Real carry frequency	Display real carrier frequency of the drive(KHz)	UNITS_KILOHERTZ
AV 053	R	AV_053_PID feedback value	Display PID feedback value (%)	UNITS_PERCENT
AV 054	R	AV_054_Overload rate	Display overload condition (%)	UNITS_PERCENT
AV 055	R	AV_055_Ground fail detect level	Display GND fail detect level (%)	UNITS_PERCENT
AV 056	R	AV_056_DC bus ripple	Display DCbus voltage ripples(Volt)	UNITS_VOLTS
AV 057	R	AV_057_Fan Speed	Fan speed of the drive (%)	UNITS_PERCENT
AV 058	R	AV_058_Output speed(rpm)	Output speed(rpm)	UNITS_REVOLUTIONS_PER_MINUTE

Object Number	R/W	Object Name	Object Description	Unit
AV 059	R	AV_059_KW per Hour	KW per Hour	UNITS_KILOWATTS
AV 060	R	AV_060_Multi-speed switch	Real multi-speed switch	UNITS_NO_UNITS
AV 061	R	AV_061_AVI1 input value	0~10V corresponds to 0~100%	UNITS_PERCENT
AV 062	R	AV_062_ACI input value	4~20mA/0~10V corresponds to 0~100%	UNITS_PERCENT
AV 063	R	AV_063_AVI2 input value	0V~10V corresponds to 0~100%	UNITS_PERCENT
AV 064	R	AV_064_Digital input status	Refer to P2-12	UNITS_NO_UNITS
AV 065	R	AV_065_Digital output status	Refer to P2-18	UNITS_NO_UNITS
AV 066	R	AV_066_CPU pin status of DI	Corresponding CPU pin status of digital input	UNITS_NO_UNITS
AV 067	R	AV_067_CPU pin status of DO	Corresponding CPU pin status of digital output	UNITS_NO_UNITS
AV 068	R	AV_068_PLC D1043 value	PLC D1043 value	UNITS_NO_UNITS

- **Commandable Binary Value Object**

  In VFD-CP2000, we have BV_000–BV_015 supporting commandable Present_Value property. In these BV_Objects, we also can use (Multi) Read_Service to access Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description
BV 000	RW	BV_000_ACTIVE CMD	(0)FreqCmd=0;(1)FreqCmd=FreqRefValue
BV 001	RW	BV_001_FWD/REV CMD	(0)Forward; (1)Reverse
BV 002	RW	BV_002_Reserved	Reserved
BV 003	RW	BV_003_HALT CMD	(0)None;(1)RampDown to 0Hz.
BV 004	RW	BV_004_LOCK CMD	(0)None;(1)OutputFreq stays at current frequency
BV 005	RW	BV_005_Reserved	Reserved
BV 006	RW	BV_006_QSTOP CMD	(0)None;(1)Force driver quick stop
BV 007	RW	BV_007_ServoPower CMD	(0)PowerOff(free run to stop);(1)PowerOn
BV 008	RW	BV_008_Reserved	Reserved
BV 009	RW	BV_009_Reserved	Reserved
BV 010	RW	BV_010_Reserved	Reserved
BV 011	RW	BV_011_Reserved	Reserved
BV 012	RW	BV_012_Reserved	Reserved
BV 013	RW	BV_013_Reserved	Reserved
BV 014	RW	BV_014_Reserved	Reserved
BV 015	RW	BV_015_RESET	RESET:(0)Do nothing;(1)Reset fault

- **Status (Readonly) Binary Value Object**

In VFD-CP2000, we have BV_016–BV_031 with read-only Present_Value property. In these BV_Objects, we do NOT have Priority_Array and Relinquish_Default properties.

Object Number	R/W	Object Name	Object Description
BV 016	R	BV_016_ARRIVE STATE	(0)Not yet;(1)Arrive (OutputFreq=FreqCmd)
BV 017	R	BV_017_FWD/REV STATE	(0)Forward;(1)Reverse
BV 018	R	BV_018_WARN STATE	(0)No Warn;(1)Occur Warn
BV 019	R	BV_019_ERROR STATE	(0)No Error;(1)Occur Error
BV 020	R	BV_020_Reserved	Reserved
BV 021	R	BV_021_Reserved	Reserved
BV 022	R	BV_022_QSTOP STATE	(0)No QSTOP;(1)Occur QSTOP
BV 023	R	BV_023_ServoPower STATE	(0)PowerOff(free run to stop);(1)PowerOn
BV 024	R	BV_024_Reserved	Reserved
BV 025	R	BV_025_Reserved	Reserved
BV 026	R	BV_026_Reserved	Reserved
BV 027	R	BV_027_Reserved	Reserved
BV 028	R	BV_028_Reserved	Reserved
BV 029	R	BV_029_Reserved	Reserved
BV 030	R	BV_030_Reserved	Reserved
BV 031	R	BV_031_Reserved	Reserved

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Chapter 18 Safe Torque Off Function

18-1 The Drive Safety Function Failure Rate

Item	Definition	Standard	Performance
STO	Safe Torque Off	IEC61508	Channel 1: 80.08% Channel 2: 68.91%
HFT (Type A subsystem)	Hardware Fault Tolerance	IEC61508	1
SIL	Safety Integrity Level	IEC61508	SIL 2
		IEC62061	SILCL 2
PFH	Average frequency of dangerous failure [h-1]	IEC61508	9.56×10^{-10}
PFD_{av}	Probability of Dangerous Failure on Demand	IEC61508	4.18×10^{-6}
Category	Category	ISO13849-1	Category 3
PL	Performance level	ISO13849-1	d
$MTTF_d$	Mean time to dangerous failure	ISO13849-1	High
DC	Diagnostic coverage	ISO13849-1	Low

18-2 Safe Torque Off Terminal Function Description

The Safe Torque Off function is to cut off the power supply to motor through the hardware, thereby the motor could not produce torque.

The STO function controls the motor current driving signal through two hardware circuits respectively, and thus cut off the inverter power module output in order to achieve the status of safety stop.

Operation Principle Description as following table 1:

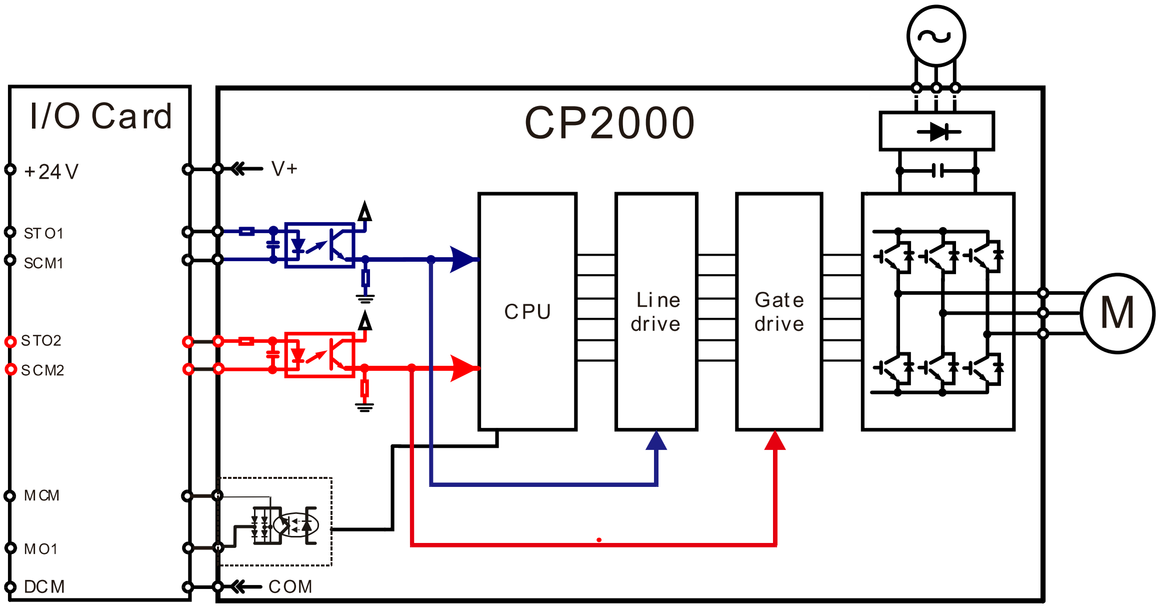
Table 1: Terminal operation description

Signal	Channel	Photo-coupler status			
STO signal	STO1–SCM1	ON (High)	ON (High)	OFF (Low)	OFF (Low)
	STO2–SCM2	ON (High)	OFF (Low)	ON (High)	OFF (Low)
Driver Output status		Ready	STL2 mode (Torque output off)	STL1 mode (Torque output off)	STO mode (Torque output off)

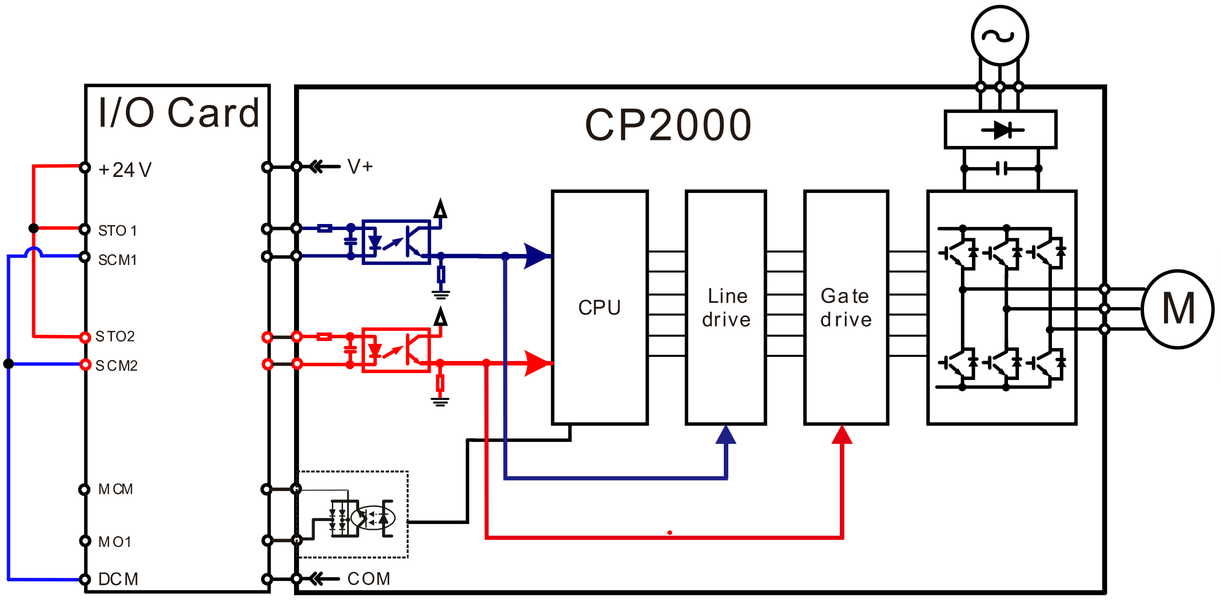
- STO means Safe Torque Off
- STL1–STL3 means Safe Torque Off hardware abnormal.
- STL3 means STO1–SCM1 and STO2–SCM2 internal circuit detected abnormal.
- STO1–SCM1 ON (High): means STO1–SCM1 has connected to a +24 V_{DC} power supply.
- STO2–SCM2 ON (High): means STO2–SCM2 has connected to a +24 V_{DC} power supply.
- STO1–SCM1 OFF (Low): means STO1–SCM1 has not connected to a +24 V_{DC} power supply.
- STO2–SCM2 OFF (Low): means STO2–SCM2 has not connected to a +24 V_{DC} power supply.

18-3 Wiring diagram

18-3-1Internal STO circuit as below:

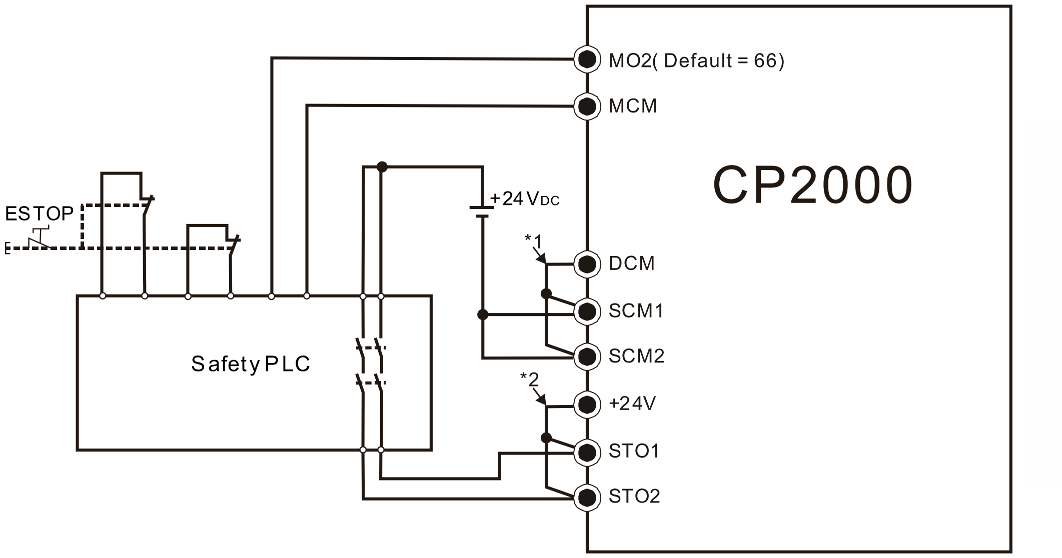


18-3-2 In the figure below, the default setting for +24V-STO1-STO2 and SCM1-SCM2-DCM is short circuit:



18-3-3 The control loop wiring diagram:

1. Remove the shot-circuit of +24V-STO1-STO2 and DCM-SCM1-SCM2.
2. The wiring as below diagram. The ESTOP switch must at Close status in normal situation and drive will be able to Run.
3. STO mode, switch ESTOP open. Drive output stop and keypad display STO.



NOTE

*1: Factory short-circuit of DCM-SCM1-SCM2. Remove the short-circuit to use the Safety function.
*2: Factory short-circuit of +24V-STO1-STO2. Remove the short-circuit to use the Safety function.

18-4 Parameter

06-44 STO Alarm Latch

Default: 0

Settings 0：STO Alarm Latch
1：STO Alarm no Latch

- Pr.06-44 = 0 STO Alarm Latch: after the reason of STO Alarm is cleared, you need a Reset command to clear STO Alarm.
- Pr.06-44 = 1 STO Alarm no Latch: after the reason of STO Alarm is cleared, the STO Alarm will be cleared automatically.
- The STL1–STL3 error are all “Alarm latch” mode (in STL1–STL3 mode, the Pr.06-44 function is no effective).

02-13 Multi-function Output 1 (Relay1)

Default: 11

02-14 Multi-function Output 2 (Relay2)

Default: 1

02-15 Multi-function Output 3 (Relay3)

Default: 66

Settings
66: SO N.O. logic A output
68: SO N.C. logic B output

Settings	Functions	Descriptions
66	SO Logic A output	Safety Output Normal Open
68	SO Logic B output	Safety Output Normal Close

- CP2000 default Pr.02-15 (Relay3) = 66 (N.O.) and Multi-function Output setting item adds two new functions: 66 and 68.

Drive status	Safety Output status	
	N.O. (MOx = 66)	N.C. (MOx = 68)
Normal run	Open	Close
STO	Close	Open
STL1~STL3	Close	Open

00-04 Content of Multi-function Display

Default: 3

Settings 45: Hardware version

18-5 Operating Sequence Description

18-5-1 Normal operation status

As shown in Figure 1: When the STO1–SCM1 and STO2–SCM2 = ON (no STO function is needed), the drive executes "Operating" or "Output Stop" according to the RUN/STOP command.

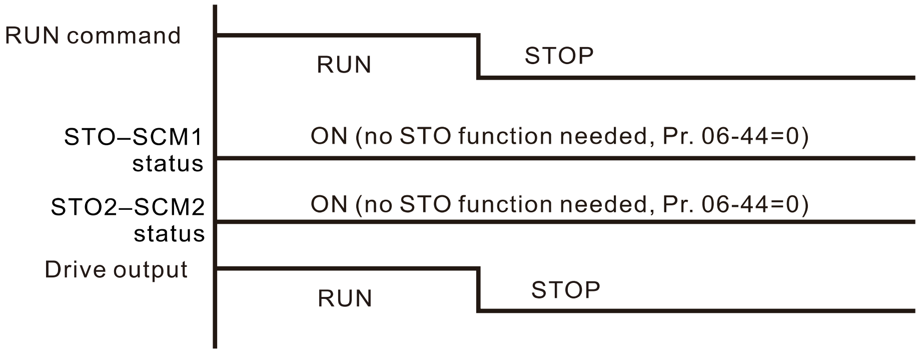

RUN command
RUN
STOP
STO–SCM1 status
ON (no STO function needed, Pr. 06-44=0)
STO2–SCM2 status
ON (no STO function needed, Pr. 06-44=0)
Drive output
RUN
STOP

Figure 1

18-5-2-1 STO, Pr.06-44 = 0, Pr.02-35 = 0

As shown in Figure 4: When both of STO1–SCM1 and STO2–SCM2 channel have turned off during operating, the STO function enables and the drive stops output regardless of Run command is ON or OFF status.

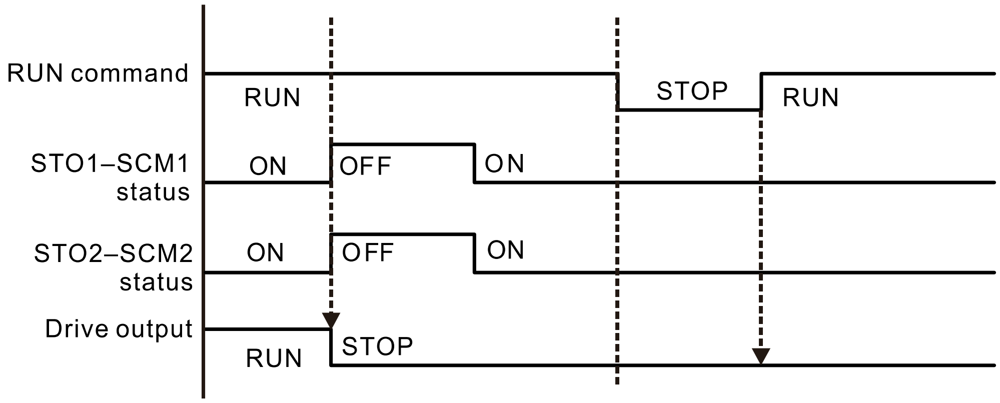


Figure 2

18-5-2-2 STO, Pr.06-44 = 0, Pr.02-35 = 1

As shown in Figure 3: the same as figure 2. However, due to the setting for Pr.02-35 is 1, if the operating command still exists after the Reset command, the drive will immediately execute the run command again.

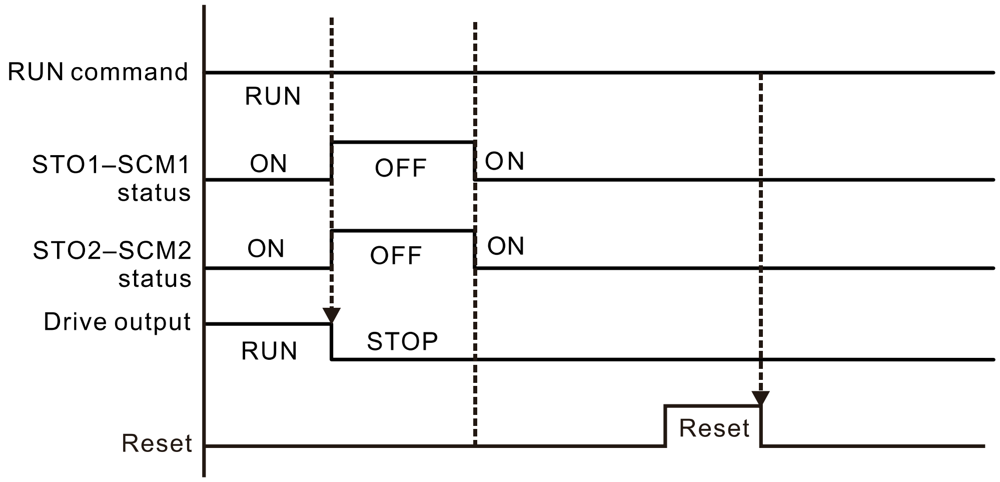


Figure 3

18-5-3 STO, Pr.06-44 = 1 STO Alarm no latch

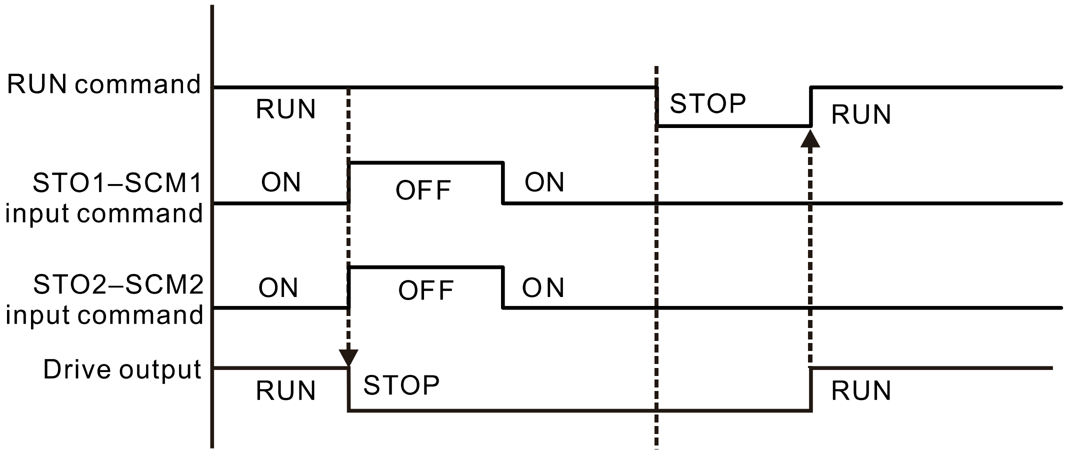


Figure 4

18-5-4 STL1

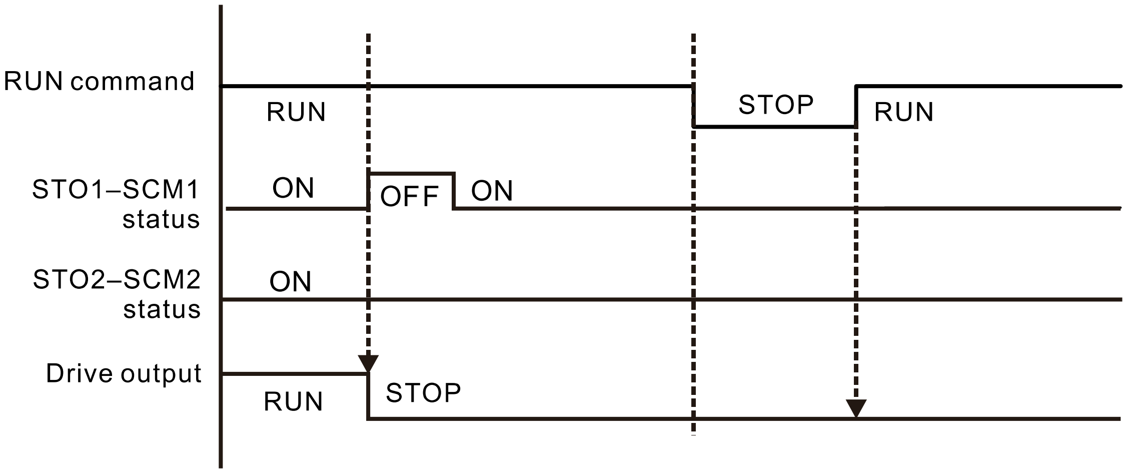


Figure 5

18-5-4 STL2

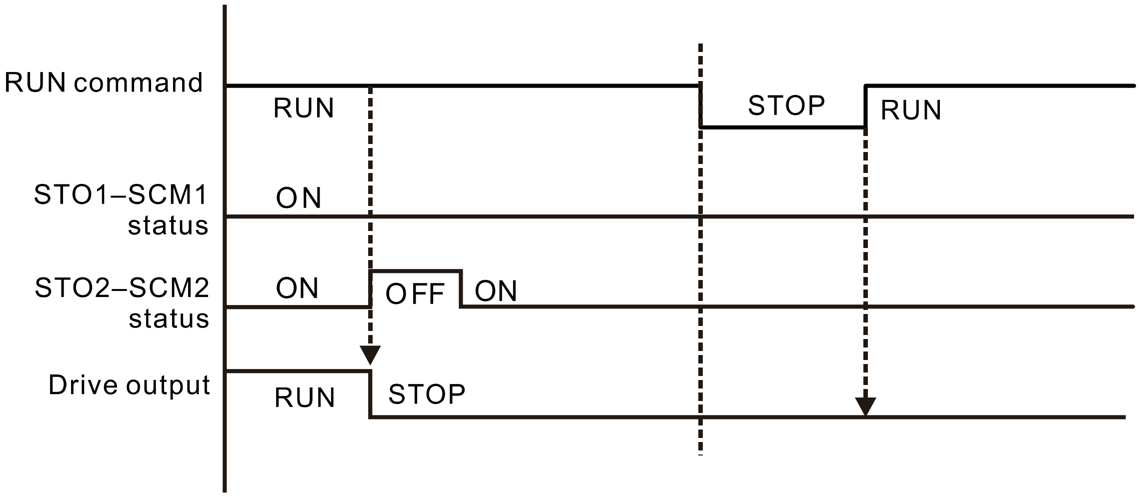


Figure 6

18-6 New Error Code for STO Function

06 - 17 Fault Record 1

06 - 18 Fault Record 2

06 - 19 Fault Record 3

06 - 20 Fault Record 4

06 - 21 Fault Record 5

06 - 22 Fault Record 6

Settings
72: Channel 1 (STO1–SCM1) safety loop error (STL1)
76: Safe torque off (STO)
77: Channel 2 (STO2–SCM2) safety loop error (STL2)
78: Internal loop error (STL3)

Error code	Name	Description
76	STO	Safe Torque Off function active
72	STL1 (STO1–SCM1)	STO1–SCM1 internal hardware detect error
77	STL2 (STO2–SCM2)	STO2–SCM2 internal hardware detect error
78	STL3	STO1–SCM1 and STO2–SCM2 internal hardware detect error

The Old/New control board and Old/New I/O card:

CP2000	v1.20 firmware	v1.21 firmware
v1.20 control board + old I/O card (no STO function)	OK	OK
v1.20 control board + new I/O card (with STO function)	Error	Error
v1.21 control board + old I/O card (no STO function)	Error	Error
v1.21 control board + new I/O card (with STO function)	Error	OK

Appendix A. Revision History

New information	
Description	**Related part**
Add 200 kW and 250 kW models to 460V series	Whole manual
Add consumption data to AC input / output reactor	Chapter 07
Add option card eZVFD-CC	Chapter 08
Add SynRM Sensorless control mode and PM Sensorless control mode	Whole manual
Add keypad languages: Polski, Deutsch, Italiano and Svenska	Chapter 10
SynRM parameters: ● Parameter group 00: 00-11, 00-17 ● Parameter group 05: 05-00, 05-33, 05-34~05-41 Other new parameters: ● Parameter group 00: 00-37 ● Parameter group 01: 01-50, 01-51 ● Parameter group 06: 06-12 ● Parameter group 07: 07-21, 07-41–07-45 ● Parameter group 09: 09-49 ● Parameter group 10: 10-08–10-15, 10-33, 10-35, 10-36, 10-54–10-58 ● Parameter group 11: 11-00–11-23	Chapter 11 Section 12-1
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Correct the HP value of 630 kW and 560kW models for 690V	Chapter 09
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