



General-Purpose AC Servo

MITSUBISHI SERVO AMPLIFIERS & MOTORS  
**MELSERVO-JE**

General-Purpose Interface AC Servo

MODEL

**MR-JE-  A**

SERVO AMPLIFIER

INSTRUCTION MANUAL

## ● Safety Instructions ●

Please read the instructions carefully before using the equipment.

To use the equipment correctly, do not attempt to install, operate, maintain, or inspect the equipment until you have read through this Instruction Manual, Installation guide, and appended documents carefully. Do not use the equipment until you have a full knowledge of the equipment, safety information and instructions. In this Instruction Manual, the safety instruction levels are classified into "WARNING" and "CAUTION".




Indicates that incorrect handling may cause hazardous conditions, resulting in death or severe injury.




Indicates that incorrect handling may cause hazardous conditions, resulting in medium or slight injury to personnel or may cause physical damage.

Note that the CAUTION level may lead to a serious consequence according to conditions. Please follow the instructions of both levels because they are important to personnel safety. What must not be done and what must be done are indicated by the following diagrammatic symbols.



Indicates what must not be done. For example, "No Fire" is indicated by .



Indicates what must be done. For example, grounding is indicated by .

In this Instruction Manual, instructions at a lower level than the above, instructions for other functions, and so on are classified into "POINT".

After reading this Instruction Manual, keep it accessible to the operator.

## 1. To prevent electric shock, note the following

### WARNING

- Before wiring and inspections, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Otherwise, an electric shock may occur. In addition, when confirming whether the charge lamp is off or not, always confirm it from the front of the servo amplifier.
- Ground the servo amplifier and servo motor securely.
- Any person who is involved in wiring and inspection should be fully competent to do the work.
- Do not attempt to wire the servo amplifier and servo motor until they have been installed. Otherwise, it may cause an electric shock.
- Do not operate switches with wet hands. Otherwise, it may cause an electric shock.
- The cables should not be damaged, stressed, loaded, or pinched. Otherwise, it may cause an electric shock.
- To prevent an electric shock, always connect the protective earth (PE) terminal (marked  $\oplus$ ) of the servo amplifier to the protective earth (PE) of the cabinet.
- To avoid an electric shock, insulate the connections of the power supply terminals.

## 2. To prevent fire, note the following

### CAUTION

- Install the servo amplifier, servo motor, and regenerative resistor on incombustible material. Installing them directly or close to combustibles will lead to smoke or a fire.
- Always connect a magnetic contactor between the power supply and the power supply (L1/L2/L3) of the servo amplifier, in order to configure a circuit that shuts down the power supply on the side of the servo amplifier's power supply. If a magnetic contactor is not connected, continuous flow of a large current may cause smoke or a fire when the servo amplifier malfunctions.
- Always connect a molded-case circuit breaker, or a fuse to each servo amplifier between the power supply and the power supply (L1/L2/L3) of the servo amplifier, in order to configure a circuit that shuts down the power supply on the side of the servo amplifier's power supply. If a molded-case circuit breaker or fuse is not connected, continuous flow of a large current may cause smoke or a fire when the servo amplifier malfunctions.
- When using the regenerative resistor, switch power off with the alarm signal. Otherwise, a regenerative transistor malfunction or the like may overheat the regenerative resistor, causing smoke or a fire.
- When you use a regenerative option with an MR-JE-40A to MR-JE-100A, remove the built-in regenerative resistor and wiring from the servo amplifier.
- Provide adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the servo amplifier and servo motor.

## 3. To prevent injury, note the following

### CAUTION

- Only the voltage specified in the Instruction Manual should be applied to each terminal. Otherwise, a burst, damage, etc. may occur.
- Connect cables to the correct terminals. Otherwise, a burst, damage, etc. may occur.
- Ensure that polarity (+/-) is correct. Otherwise, a burst, damage, etc. may occur.
- The servo amplifier heat sink, regenerative resistor, servo motor, etc., may be hot while the power is on and for some time after power-off. Take safety measures such as providing covers to avoid accidentally touching them by hands and parts such as cables.

## 4. Additional instructions

The following instructions should also be fully noted. Incorrect handling may cause a malfunction, injury, electric shock, fire, etc.

### (1) Transportation and installation

#### CAUTION

- Transport the products correctly according to their mass.
- Stacking in excess of the specified number of product packages is not allowed.
- Do not hold the lead wire of the regenerative resistor when transporting the servo amplifier.
- Install the servo amplifier and the servo motor in a load-bearing place in accordance with the Instruction Manual.
- Do not get on or put heavy load on the equipment. Otherwise, it may cause injury.
- The equipment must be installed in the specified direction.
- Leave specified clearances between the servo amplifier and the cabinet walls or other equipment.
- Do not install or operate the servo amplifier and servo motor which have been damaged or have any parts missing.
- Do not block the intake and exhaust areas of the servo amplifier. Otherwise, it may cause a malfunction.
- Do not drop or strike the servo amplifier and servo motor. Isolate them from all impact loads.
- When you keep or use the equipment, please fulfill the following environment.

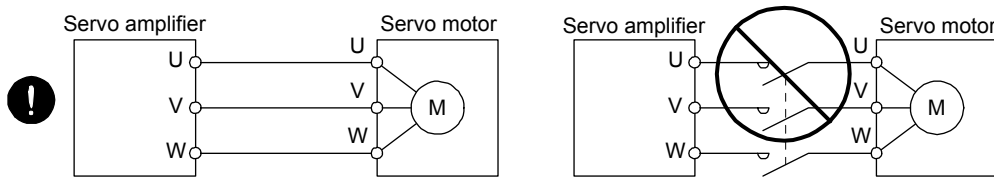
Item		Environment
Ambient temperature	Operation	0 °C to 55 °C (non-freezing)
	Storage	-20 °C to 65 °C (non-freezing)
Ambient humidity	Operation	5 %RH to 90 %RH (non-condensing)
	Storage	
Ambience		Indoors (no direct sunlight), free from corrosive gas, flammable gas, oil mist, dust, and dirt
Altitude		1000 m or less above sea level
Vibration resistance		5.9 m/s <sup>2</sup> , at 10 Hz to 55 Hz (directions of X, Y and Z axes)

- When the product has been stored for an extended period of time, contact your local sales office.
- When handling the servo amplifier, be careful about the edged parts such as corners of the servo amplifier.
- The servo amplifier must be installed in a metal cabinet.
- When fumigants that contain halogen materials such as fluorine, chlorine, bromine, and iodine are used for disinfecting and protecting wooden packaging from insects, they cause malfunction when entering our products. Please take necessary precautions to ensure that remaining materials from fumigant do not enter our products, or treat packaging with methods other than fumigation (heat method). Additionally, disinfect and protect wood from insects before packing products.

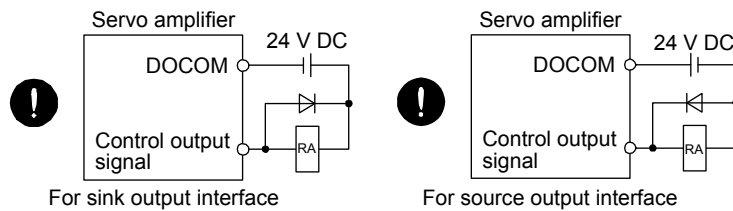
## (2) Wiring

### ⚠ CAUTION

- Before removing the CNP1 connector of MR-JE-40A to MR-JE-100A, disconnect the lead wires of the regenerative resistor from the CNP1 connector.
- Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpectedly.
- Do not install a power capacitor, surge killer, or radio noise filter (optional FR-BIF) on the servo amplifier output side.
- To avoid a malfunction, connect the wires to the correct phase terminals (U/V/W) of the servo amplifier and servo motor.
- Connect the servo amplifier power output (U/V/W) to the servo motor power input (U/V/W) directly. Do not let a magnetic contactor, etc. intervene. Otherwise, it may cause a malfunction.



- The connection diagrams in this instruction manual are shown for sink interfaces, unless stated otherwise.
- The surge absorbing diode installed to the DC relay for control output should be fitted in the specified direction. Otherwise, the emergency stop and other protective circuits may not operate.



- When the cable is not tightened enough to the terminal block, the cable or terminal block may generate heat because of the poor contact. Be sure to tighten the cable with specified torque.
- Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.
- Configure a circuit to turn off EM2 or EM1 when the power supply is turned off to prevent an unexpected restart of the servo amplifier.

## (3) Test run and adjustment

### ⚠ CAUTION

- Before operation, check the parameter settings. Improper settings may cause some machines to operate unexpectedly.
- Never make a drastic adjustment or change to the parameter values as doing so will make the operation unstable.
- Do not get close to moving parts during the servo-on status.

#### (4) Usage

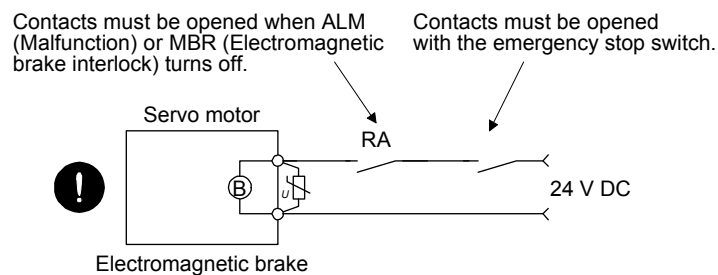
### ⚠ CAUTION

- When it is assumed that a hazardous condition may occur due to a power failure or product malfunction, use a servo motor with an external brake to prevent the condition.
- Do not disassemble, repair, or modify the equipment.
- Before resetting an alarm, make sure that the run signal of the servo amplifier is off in order to prevent a sudden restart. Otherwise, it may cause an accident.
- Use a noise filter, etc. to minimize the influence of electromagnetic interference. Electromagnetic interference may be given to the electronic equipment used near the servo amplifier.
- Burning or breaking a servo amplifier may cause a toxic gas. Do not burn or break it.
- Use the servo amplifier with the specified servo motor.
- The electromagnetic brake on the servo motor is designed to hold the motor shaft and should not be used for ordinary braking.
- For such reasons as service life and mechanical structure (e.g. where a ball screw and the servo motor are coupled via a timing belt), the electromagnetic brake may not hold the motor shaft. To ensure safety, install a stopper on the machine side.

#### (5) Corrective actions

### ⚠ CAUTION

- Ensure safety by confirming the power off, etc. before performing corrective actions. Otherwise, it may cause an accident.
- When it is assumed that a hazardous condition may occur due to a power failure or product malfunction, use a servo motor with an electromagnetic brake or external brake to prevent the condition.
- Configure an electromagnetic brake circuit which is interlocked with an external emergency stop switch.



- When any alarm has occurred, eliminate its cause, ensure safety, and deactivate the alarm before restarting operation.
- Provide an adequate protection to prevent unexpected restart after an instantaneous power failure.

## (6) Maintenance, inspection and parts replacement

### CAUTION

- Make sure that the emergency stop circuit operates properly such that an operation can be stopped immediately and a power is shut off by the emergency stop switch.
- It is recommended that the servo amplifier be replaced every 10 years when it is used in general environment.
- When using a servo amplifier whose power has not been turned on for a long time, contact your local sales office.

## (7) General instruction

- To illustrate details, the equipment in the diagrams of this Instruction Manual may have been drawn without covers and safety guards. When the equipment is operated, the covers and safety guards must be installed as specified. Operation must be performed in accordance with this Instruction Manual.

## ● DISPOSAL OF WASTE ●

Please dispose a servo amplifier and other options according to your local laws and regulations.

### EEPROM life

The number of write times to the EEPROM, which stores parameter settings, etc., is limited to 100,000. If the total number of the following operations exceeds 100,000, the servo amplifier may malfunction when the EEPROM reaches the end of its useful life.

- Write to the EEPROM due to parameter setting changes
- Write to the EEPROM due to device changes

### Compliance with global standards

Refer to app. 2 for the compliance with global standard.

### Using HF-KN series and HF-SN series servo motors

For the combinations and characteristics when using HF-KN series and HF-SN series servo motors, refer to app. 5.

### «About the manual»

You must have this Instruction Manual and the following manuals to use this servo. Ensure to prepare them to use the servo safely.

#### Relevant manuals

Manual name	Manual No.
MELSERVO-JE Servo Amplifier Instruction Manual (Troubleshooting)	SH(NA)030166ENG
MELSERVO MR-JE-_A Servo Amplifier Instruction Manual (Positioning Mode)	SH(NA)030150ENG
MELSERVO MR-JE-_A Servo Amplifier Instruction Manual (Modbus-RTU Protocol)	SH(NA)030177ENG
MELSERVO HG-KN/HG-SN Servo Motor Instruction Manual	SH(NA)030135ENG
MELSERVO EMC Installation Guidelines	IB(NA)67310ENG

«Cables used for wiring»

Wires mentioned in this Instruction Manual are selected based on the ambient temperature of 40 °C.

«U.S. customary units»

U.S. customary units are not shown in this manual. Convert the values if necessary according to the following table.

Quantity	SI (metric) unit	U.S. customary unit
Mass	1 [kg]	2.2046 [lb]
Length	1 [mm]	0.03937 [inch]
Torque	1 [N·m]	141.6 [oz·inch]
Moment of inertia	1 [(× 10 <sup>-4</sup> kg·m <sup>2</sup> )]	5.4675 [oz·inch <sup>2</sup> ]
Load (thrust load/axial load)	1 [N]	0.2248 [lbf]
Temperature	N [°C] × 9/5 + 32	N [°F]





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# MEMO

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# 1. FUNCTIONS AND CONFIGURATION

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## 1. FUNCTIONS AND CONFIGURATION

### 1.1 Summary

The Mitsubishi general-purpose AC servo MELSERVO-JE series have limited functions with keeping high performance based on MELSERVO-J4 series.

The servo amplifier has position, speed, and torque control modes. In the position control mode, the maximum pulse train of 4 Mpulses/s is supported. Further, it can perform operation with the control modes switched, e.g. position/speed control, speed/torque control and torque/position control. Hence, it is applicable to a wide range of fields, not only precision positioning and smooth speed control of machine tools and general industrial machines but also line control and tension control.

With one-touch tuning and real-time auto tuning, you can automatically adjust the servo gains according to the machine.

The tough drive function, drive recorder function, and preventive maintenance support function strongly support machine maintenance.

The servo amplifier has a USB communication interface. Therefore, you can connect the servo amplifier to the personal computer with MR Configurator2 installed to perform the parameter setting, test operation, gain adjustment, and others.

The MELSERVO-JE series servo motor equipped with an incremental encoder whose resolution is 131072 pulses/rev will enable a high-accuracy positioning.

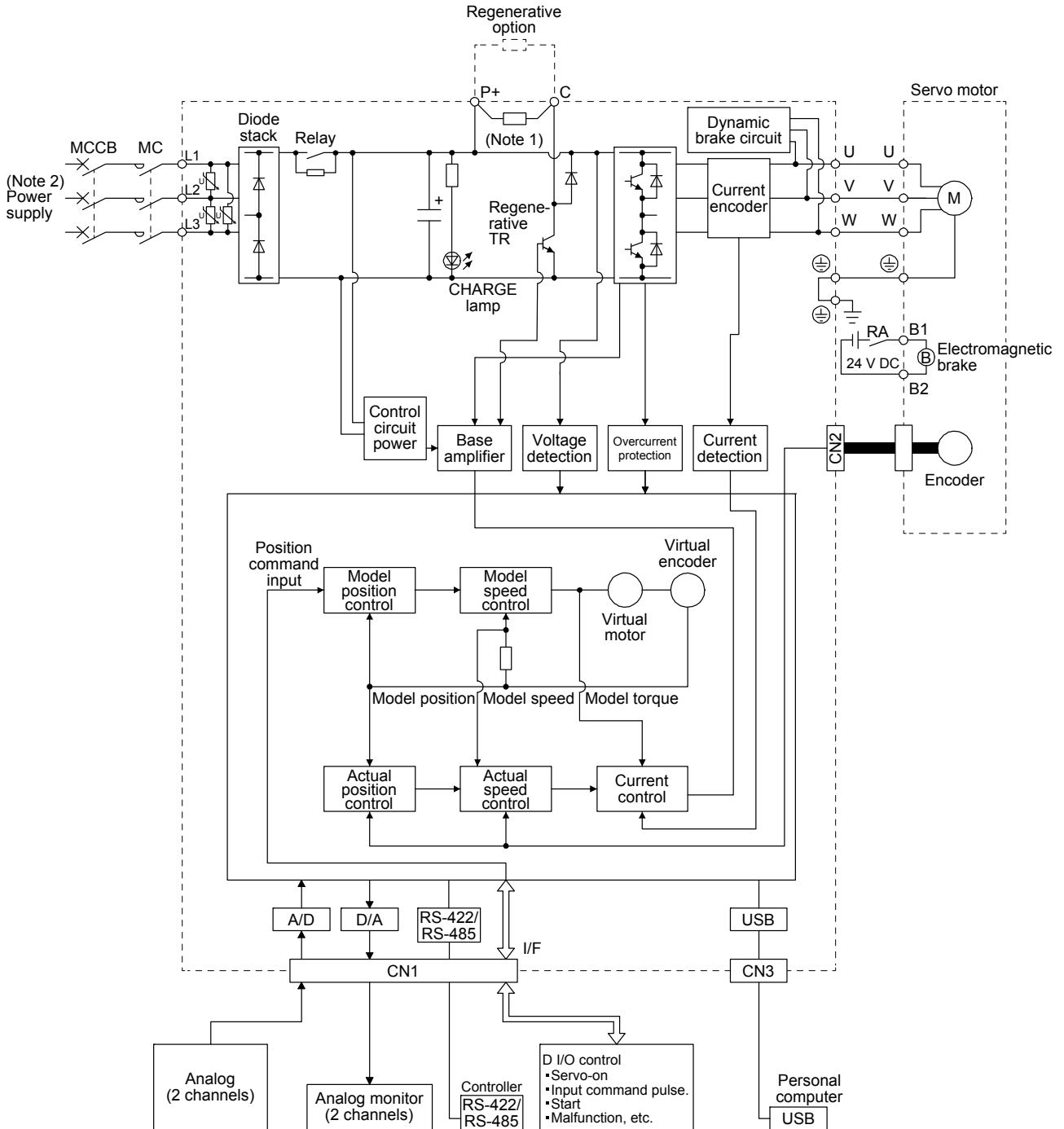


# 1. FUNCTIONS AND CONFIGURATION

## 1.2 Function block diagram

The function block diagram of this servo is shown below.

(1) MR-JE-100A or less

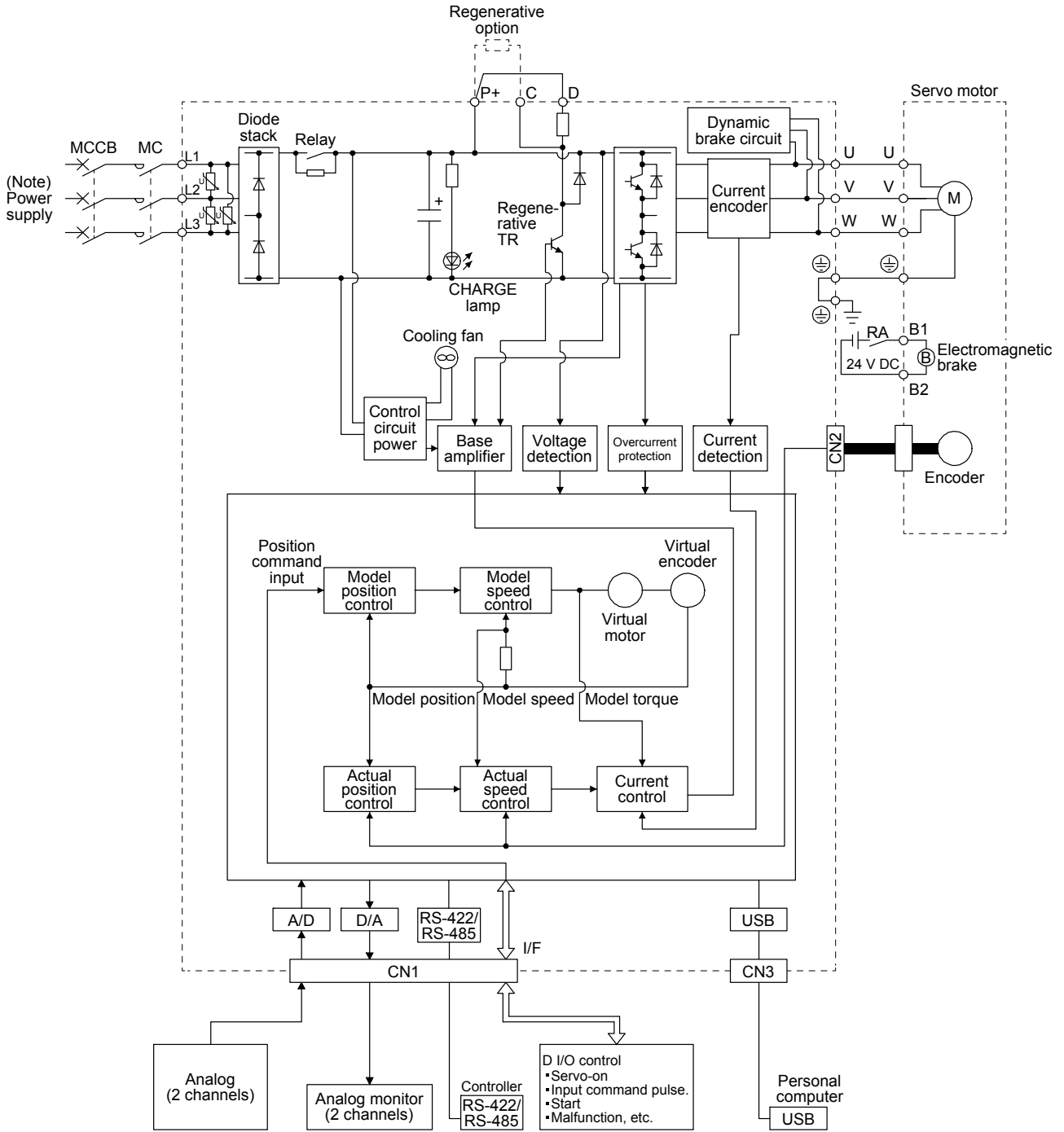


Note 1. The built-in regenerative resistor is not provided for MR-JE-10A and MR-JE-20A.

Note 2. For 1-phase 200 V AC to 240 V AC, connect the power supply to L1 and L3. Leave L2 open.  
For the power supply specifications, refer to section 1.3.

# 1. FUNCTIONS AND CONFIGURATION

(2) MR-JE-200A or more



Note. For the power supply specifications, refer to section 1.3.

# 1. FUNCTIONS AND CONFIGURATION

## 1.3 Servo amplifier standard specifications

Model: MR-JE-		10A	20A	40A	70A	100A	200A	300A	
Output	Rated voltage	3-phase 170 V AC							
	Rated current [A]	1.1	1.5	2.8	5.8	6.0	11.0	11.0	
Power supply input	Voltage/Frequency	3-phase or 1-phase 200 V AC to 240 V AC, 50 Hz/60 Hz				3-phase or 1-phase 200 V AC to 240 V AC, 50 Hz/60 Hz (Note 6)		3-phase 200 V AC to 240 V AC, 50 Hz/60 Hz	
	Rated current (Note 5) [A]	0.9	1.5	2.6	3.8	5.0	10.5	14.0	
	Permissible voltage fluctuation	3-phase or 1-phase 170 V AC to 264 V AC				3-phase or 1-phase 170 V AC to 264 V AC (Note 6)		3-phase 170 V AC to 264 V AC	
	Permissible frequency fluctuation	Within $\pm 5\%$							
	Power supply capacity [kVA]	Refer to section 10.2.							
	Inrush current [A]	Refer to section 10.5.							
Interface power supply	Voltage	24 V DC $\pm 10\%$							
	Current capacity [A]	0.3 (Note 1)							
Control method	Sine-wave PWM control, current control method								
Dynamic brake	Built-in								
Communication function	USB: connection to a personal computer or others (MR Configurator2-compatible)								
	RS-422/RS-485: Connection to controller (1: n communication up to 32 axes) (Note 4, 7)								
Encoder output pulses	Compatible (A/B/Z-phase pulse)								
Analog monitor	Two channels								
Position control mode	Max. input pulse frequency	4 Mpulses/s (for differential receiver) (Note 3), 200 kpulses/s (for open collector)							
	Positioning feedback pulse	Encoder resolution (resolution per servo motor revolution): 131072 pulses/rev							
	Command pulse multiplying factor	Electronic gear A:1 to 16777215, B:1 to 16777215, $1/10 < A/B < 4000$							
	In-position range setting	0 pulse to $\pm 65535$ pulses (command pulse unit)							
	Error excessive	$\pm 3$ revolutions							
	Torque limit	Set by parameter setting or external analog input (0 V DC to +10 V DC/maximum torque)							
Speed control mode	Speed control range	Analog speed command 1: 2000, internal speed command 1: 5000							
	Analog speed command input	0 to $\pm 10$ V DC/rated speed (The speed at 10 V is changeable with [Pr. PC12].)							
	Speed fluctuation ratio	$\pm 0.01\%$ or less (load fluctuation 0% to 100%), 0% (power fluctuation $\pm 10\%$ ), $\pm 0.2\%$ or less (ambient temperature $25\text{ }^\circ\text{C} \pm 10\text{ }^\circ\text{C}$ ) when using analog speed command							
	Torque limit	Set by parameter setting or external analog input (0 V DC to +10 V DC/maximum torque)							
Torque control mode	Analog torque command input	0 V DC to $\pm 8$ V DC/maximum torque (input impedance 10 k $\Omega$ to 12 k $\Omega$ )							
	Speed limit	Set by parameter setting or external analog input (0 V DC to 10 V DC/rated speed)							
Positioning mode	Refer to section 1.1 of "MR-JE-_A Servo Amplifier Instruction Manual (Positioning Mode)" The positioning mode is available with servo amplifiers with software version B7 or later.								
Protective functions	Overcurrent shut-off, regenerative overvoltage shut-off, overload shut-off (electronic thermal), servo motor overheat protection, encoder error protection, regenerative error protection, undervoltage protection, instantaneous power failure protection, overspeed protection, and error excessive protection								
Compliance to global standards	CE marking	LVD: EN 61800-5-1 EMC: EN 61800-3							
	UL standard	UL 508C							
Structure (IP rating)	Natural cooling, open (IP20)						Force cooling, open (IP20)		
Close mounting (Note 2)	3-phase power supply input	Possible							
	1-phase power supply input	Possible				Impossible			

# 1. FUNCTIONS AND CONFIGURATION

Model: MR-JE-			10A	20A	40A	70A	100A	200A	300A	
Environment	Ambient temperature	Operation	0 °C to 55 °C (non-freezing)							
		Storage	-20 °C to 65 °C (non-freezing)							
	Ambient humidity	Operation	5 %RH to 90 %RH (non-condensing)							
		Storage	5 %RH to 90 %RH (non-condensing)							
	Ambience	Indoors (no direct sunlight), free from corrosive gas, flammable gas, oil mist, dust, and dirt								
	Altitude	1000 m or less above sea level								
Vibration resistance		5.9 m/s <sup>2</sup> , at 10 Hz to 55 Hz (directions of X, Y and Z axes)								
Mass [kg]			0.8		1.5		2.1			

- Note
- 0.3 A is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.
  - When closely mounting the servo amplifier of 3.5 kW or less, operate them at the ambient temperatures of 0 °C to 45 °C or at 75% or smaller effective load ratio.
  - 1 Mpulse/s or lower commands are supported in the initial setting. When inputting commands over 1 Mpulse/s and 4 Mpulses/s or lower, change the setting in [Pr. PA13].
  - The RS-422 communication function is supported by servo amplifier manufactured in December 2013 or later. Refer to section 1.6 (1) for the year and month of manufacture.
  - These are current values for 3-phase power supply.
  - When using 1-phase 200 V AC to 240 V AC power supply, operate the servo amplifier at 75% or smaller effective load ratio.
  - The RS-485 communication function is available with servo amplifiers manufactured in May 2015 or later. Refer to section 1.6 (1) for the year and month of manufacture.

# 1. FUNCTIONS AND CONFIGURATION

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## 1.4 Combinations of servo amplifiers and servo motors

Servo amplifier	Servo motor
MR-JE-10A	HG-KN13_
MR-JE-20A	HG-KN23_
MR-JE-40A	HG-KN43_
MR-JE-70A	HG-KN73_ HG-SN52_
MR-JE-100A	HG-SN102_
MR-JE-200A	HG-SN152_ HG-SN202_
MR-JE-300A	HG-SN302_

# 1. FUNCTIONS AND CONFIGURATION

## 1.5 Function list

The following table lists the functions of this servo. For details of the functions, refer to each section indicated in the detailed explanation field.

Function	Description	Detailed explanation
Model adaptive control	This function achieves a high response and stable control following the ideal model. The two-degree-of-freedom-model model adaptive control enables you to set a response to the command and response to the disturbance separately. Additionally, this function can be disabled. Refer to section 7.4 for disabling this function. Used by servo amplifiers with software version B4 or later. Check the software version using MR Configurator2.	
Position control mode	This servo is used as a position control servo.	Section 3.2.1 Section 3.6.1 Section 4.2
Speed control mode	This servo is used as a speed control servo.	Section 3.2.2 Section 3.6.2 Section 4.3
Torque control mode	This servo is used as a torque control servo.	Section 3.2.3 Section 3.6.3 Section 4.4
Position/speed control switch mode	Using an input device, control can be switched between position control and speed control.	Section 3.6.4
Speed/torque control switch mode	Using an input device, control can be switched between speed control and torque control.	Section 3.6.5
Torque/position control switch mode	Using an input device, control can be switched between torque control and position control.	Section 3.6.6
Positioning mode	In this mode, MR-JE-_A servo amplifiers are used in with point table or program method. For details, refer to "MR-JE-_A Servo Amplifier Instruction Manual (Positioning Mode)." The positioning mode is available with servo amplifiers with software version B7 or later.	MR-JE-_A Servo Amplifier Instruction Manual (Positioning Mode)
High-resolution encoder	High-resolution encoder of 131072 pulses/rev is used for the encoder of the servo motor compatible with the MELSERVO-JE series.	
Gain switching function	You can switch gains during rotation and during stop, and can use an input device to switch gains during operation.	Section 7.2
Advanced vibration suppression control II	This function suppresses vibration at the arm end or residual vibration.	Section 7.1.5
Machine resonance suppression filter	This is a filter function (notch filter) which decreases the gain of the specific frequency to suppress the resonance of the mechanical system.	Section 7.1.1
Shaft resonance suppression filter	When a load is mounted to the servo motor shaft, resonance by shaft torsion during driving may generate a mechanical vibration at high frequency. The shaft resonance suppression filter suppresses the vibration.	Section 7.1.3
Adaptive filter II	Servo amplifier detects mechanical resonance and sets filter characteristics automatically to suppress mechanical vibration.	Section 7.1.2
Low-pass filter	Suppresses high-frequency resonance which occurs as servo system response is increased.	Section 7.1.4
Machine analyzer function	Analyzes the frequency characteristic of the mechanical system by simply connecting an MR Configurator2 installed personal computer and servo amplifier. MR Configurator2 is necessary for this function.	
Robust filter	This function provides better disturbance response in case low response level that load to motor inertia ratio is high for such as roll send axes.	[Pr. PE41]
Slight vibration suppression control	Suppresses vibration of $\pm 1$ pulse produced at a servo motor stop.	[Pr. PB24]
Electronic gear	Input pulses can be multiplied by 1/10 to 4000.	[Pr. PA06] [Pr. PA07]
S-pattern acceleration/deceleration time constant	Speed can be increased and decreased smoothly.	[Pr. PC03]
Auto tuning	Automatically adjusts the gain to optimum value if load applied to the servo motor shaft varies.	Section 6.3
Regenerative option	Used when the built-in regenerative resistor of the servo amplifier does not have sufficient regenerative capability for the regenerative power generated.	Section 11.2
Alarm history clear	Alarm history is cleared.	[Pr. PC18]
Output signal selection (device settings)	ST1 (Forward rotation start), ST2 (Reverse rotation start), and SON (Servo-on) and other input device can be assigned to any pins.	[Pr. PD03] to [Pr. PD20]

# 1. FUNCTIONS AND CONFIGURATION

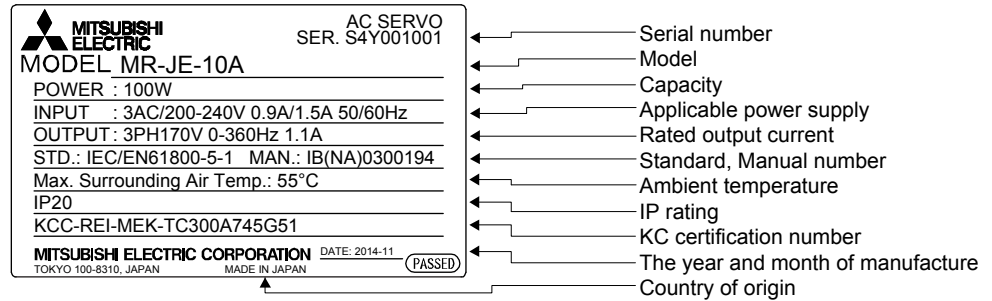
Function	Description	Detailed explanation
Output signal selection (device settings)	The output devices including MBR (Electromagnetic brake interlock) can be assigned to certain pins of the CN1 connector.	[Pr. PD24] to [Pr. PD28]
Output signal (DO) forced output	Output signal can be forced on/off independently of the servo status. Use this function for checking output signal wiring, etc.	Section 4.5.8
Command pulse selection	Command pulse train form can be selected from among three different types.	[Pr. PA13]
Torque limit	Servo motor torque can be limited to any value.	Section 3.6.1 (5) [Pr. PA11] [Pr. PA12]
Speed limit	Servo motor speed can be limited to any value.	Section 3.6.3 (3) [Pr. PC05] to [Pr. PC11]
Status display	Servo status is shown on the 5-digit, 7-segment LED display.	Section 4.5.3
External I/O signal display	On/off statuses of external I/O signals are shown on the display.	Section 4.5.7
Automatic VC offset	Voltage is automatically offset to stop the servo motor if it does not come to a stop when VC (Analog speed command) or VLA (Analog speed limit is 0 V).	Section 4.5.4
Alarm code output	If an alarm has occurred, the corresponding alarm number is outputted in 3-bit code.	Chapter 8
Test operation mode	Jog operation, positioning operation, motor-less operation, DO forced output, and program operation MR Configurator2 is required for the positioning operation and program operation.	Section 4.5.9
Analog monitor output	Servo status is outputted in terms of voltage in real time.	[Pr. PC14], [Pr. PC15]
MR Configurator2	Using a personal computer, you can perform the parameter setting, test operation, monitoring, and others.	Section 11.4
One-touch tuning	Gain adjustment is performed just by one click on a certain button on MR Configurator2 or operation section.	Section 6.2
Tough drive function	This function makes the equipment continue operating even under the condition that an alarm occurs. The tough drive function includes two types: the vibration tough drive and the instantaneous power failure tough drive.	Section 7.3
Drive recorder function	This function continuously monitors the servo status and records the status transition before and after an alarm for a fixed period of time. You can check the recorded data on the drive recorder window on MR Configurator2 by clicking the "Graph" button. However, the drive recorder will not operate on the following conditions. 1. You are using the graph function of MR Configurator2. 2. You are using the machine analyzer function. 3. [Pr. PF21] is set to "-1".	[Pr. PA23]
Servo amplifier life diagnosis function	You can check the cumulative energization time and the number of on/off times of the inrush relay. This function gives an indication of the replacement time for parts of the servo amplifier including a capacitor and a relay before they malfunction. MR Configurator2 is necessary for this function.	
Power monitoring function	This function calculates the power running energy and the regenerative power from the data in the servo amplifier such as speed and current. Power consumption and others are displayed on MR Configurator2.	
Machine diagnosis function	From the data in the servo amplifier, this function estimates the friction and vibrational component of the drive system in the equipment and recognizes an error in the machine parts, including a ball screw and bearing. MR Configurator2 is necessary for this function.	
Lost motion compensation function	This function improves the response delay occurred when the machine moving direction is reversed. This is used with servo amplifiers with software version C5 or later. Check the software version of the servo amplifier using MR Configurator2.	Section 7.5
Modbus-RTU communication function	The Modbus protocol uses dedicated message frames for the serial communication between a master and slaves. The dedicated message frames have functions for reading and writing data, and users can write parameters from servo amplifiers and check the operation status of the servo amplifiers by using this function.	MR-JE-_A Servo Amplifier Instruction Manual (Modbus-RTU Protocol)

# 1. FUNCTIONS AND CONFIGURATION

## 1.6 Model designation

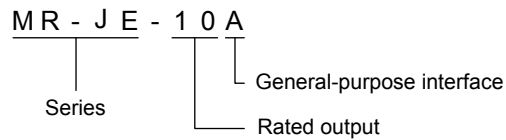
### (1) Rating plate

The following shows an example of rating plate for explanation of each item.



### (2) Model

The following describes what each block of a model name indicates.



Symbol	Rated output [kW]
10	0.1
20	0.2
40	0.4
70	0.75
100	1
200	2
300	3

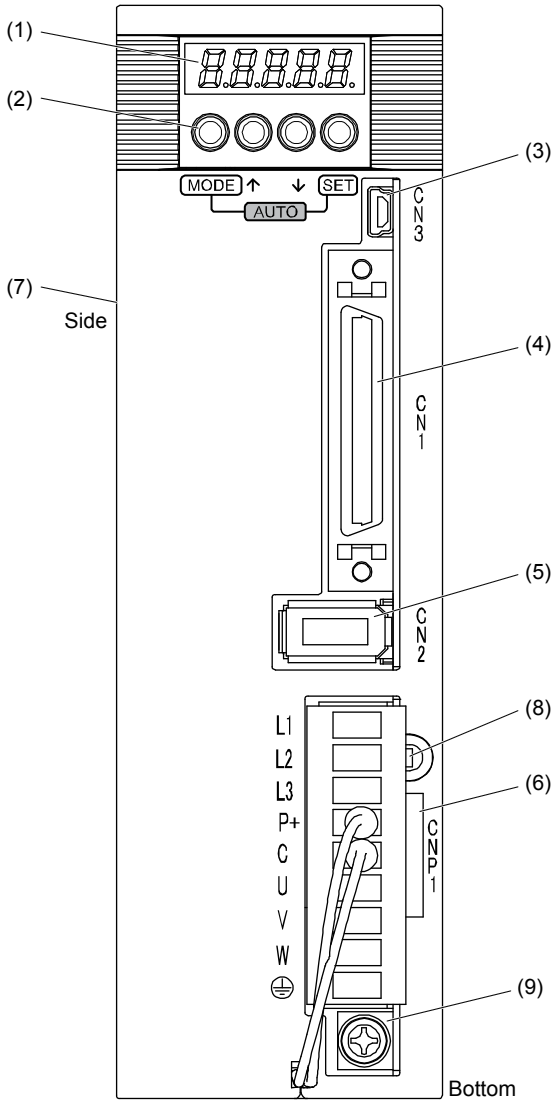


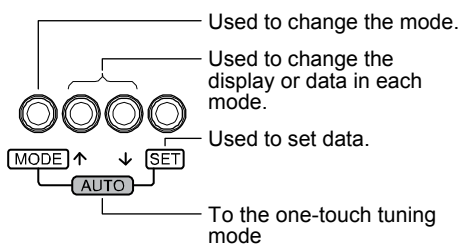
# 1. FUNCTIONS AND CONFIGURATION

## 1.7 Structure

### 1.7.1 Parts identification

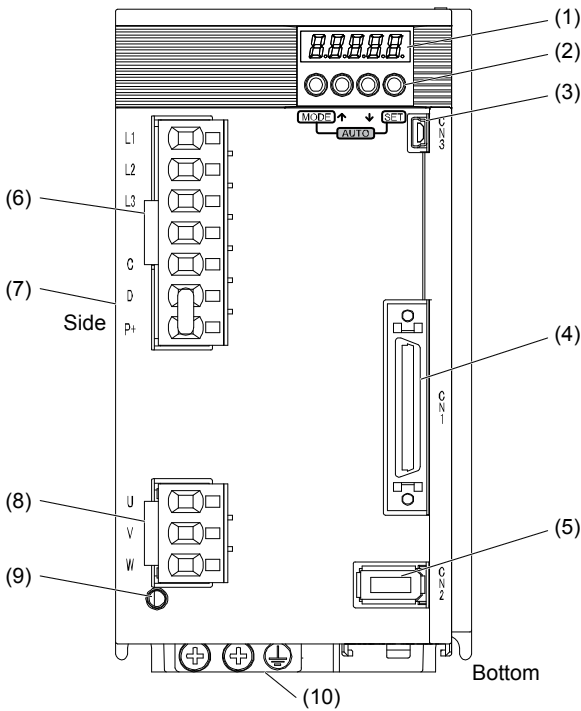
#### (1) MR-JE-100A or less



No.	Name/Application	Detailed explanation
(1)	Display The 5-digit, 7-segment LED shows the servo status and the alarm number.	Section 4.5
(2)	Operation section Used to perform status display, diagnostic, alarm, and parameter setting operations. Push the "MODE" and "SET" buttons at the same time for 3 s or more to switch to the one-touch tuning mode. 	Section 4.5 Section 6.2
(3)	USB communication connector (CN3) Connect with the personal computer.	Section 11.4
(4)	I/O signal connector (CN1) Digital I/O signal, analog input signal, analog monitor output signal, and RS-422/RS-485 communication controller are connected.	Section 3.2 Section 3.4 Chapter 12
(5)	Encoder connector (CN2) Used to connect the servo motor encoder.	Section 3.4
(6)	Power connector (CNP1) Input power supply, built-in regenerative resistor, regenerative option, and servo motor are connected.	Section 3.1 Section 3.3
(7)	Rating plate	Section 1.6
(8)	Charge lamp When the main circuit is charged, this will light up. While this lamp is lit, do not reconnect the cables.	
(9)	Protective earth (PE) terminal Grounding terminal	Section 3.1 Section 3.3

# 1. FUNCTIONS AND CONFIGURATION

(2) MR-JE-200A or more



No.	Name/Application	Detailed explanation
(1)	Display	The 5-digit, 7-segment LED shows the servo status and the alarm number.
(2)	Operation section	Used to perform status display, diagnostic, alarm, and parameter setting operations. Push the "MODE" and "SET" buttons at the same time for 3 s or more to switch to the one-touch tuning mode.
(2)		<p>Used to change the mode.</p> <p>Used to change the display or data in each mode.</p> <p>Used to set data.</p> <p>To the one-touch tuning mode</p>
(3)	USB communication connector (CN3)	Connect with the personal computer.
(4)	I/O signal connector (CN1)	Digital I/O signal, analog input signal, analog monitor output signal, and RS-422/RS-485 communication controller are connected.
(5)	Encoder connector (CN2)	Used to connect the servo motor encoder.
(6)	Power connector (CNP1)	Input power supply and regenerative option are connected.
(7)	Rating plate	
(8)	Servo motor power connector (CNP2)	Connect the servo motor.
(9)	Charge lamp	When the main circuit is charged, this will light up. While this lamp is lit, do not reconnect the cables.
(10)	Protective earth (PE) terminal	Grounding terminal

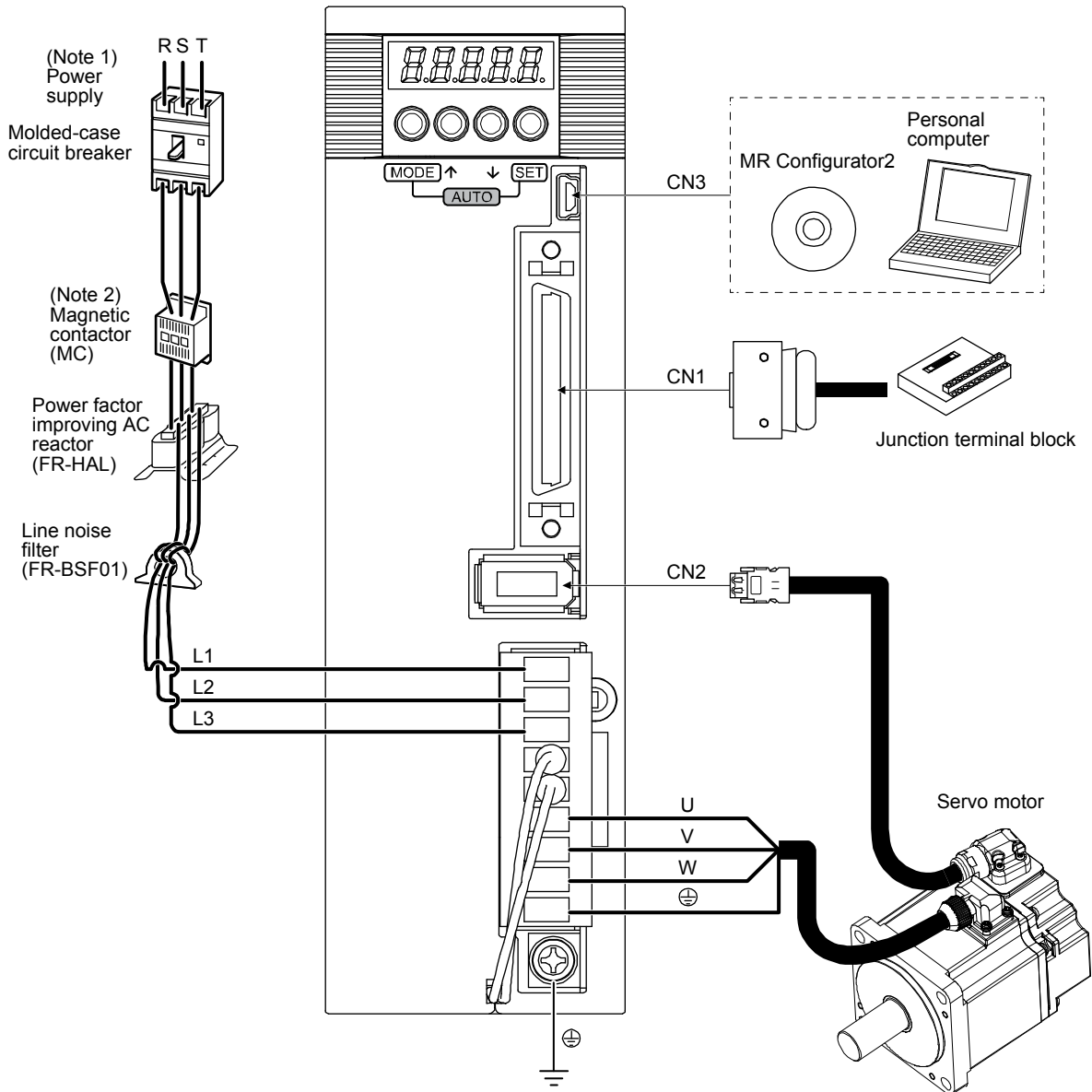
# 1. FUNCTIONS AND CONFIGURATION

## 1.8 Configuration including peripheral equipment

**CAUTION** ● Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.

**POINT**  
● Equipment other than the servo amplifier and servo motor are optional or recommended products.

(1) MR-JE-100A or less  
The diagram shows MR-JE-40A.

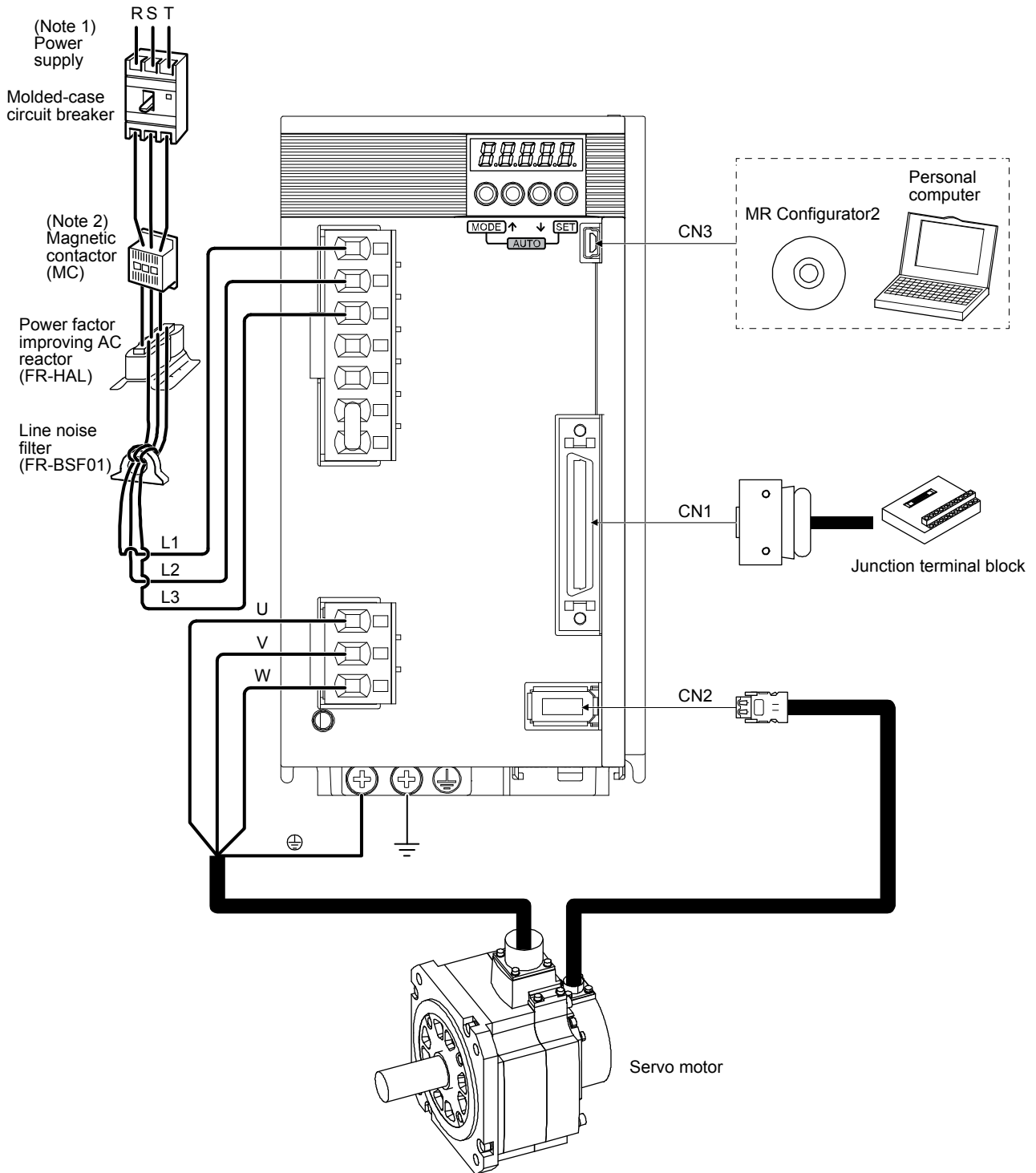


- Note 1. For 1-phase 200 V AC to 240 V AC, connect the power supply to L1 and L3. Leave L2 open. For the power supply specifications, refer to section 1.3.
- Note 2. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.

# 1. FUNCTIONS AND CONFIGURATION

(2) MR-JE-200A or more

The diagram shows MR-JE-200A.



- Note 1. A 1-phase 200 V AC to 240 V AC power supply may be used with the servo amplifier of MR-JE-200A. For 1-phase 200 V AC to 240 V AC, connect the power supply to L1 and L2. Leave L3 open. For the power supply specifications, refer to section 1.3.
- Note 2. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.



## 2. INSTALLATION

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### 2. INSTALLATION



**WARNING** ● To prevent electric shock, ground each equipment securely.



### CAUTION

- Stacking in excess of the specified number of product packages is not allowed.
- Do not hold the lead wire of the regenerative resistor when transporting the servo amplifier.
- Install the equipment on incombustible material. Installing them directly or close to combustibles will lead to smoke or a fire.
- Install the servo amplifier and the servo motor in a load-bearing place in accordance with the Instruction Manual.
- Do not get on or put heavy load on the equipment. Otherwise, it may cause injury.
- Use the equipment within the specified environment. For the environment, refer to section 1.3.
- Provide an adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the servo amplifier.
- Do not block the intake and exhaust areas of the servo amplifier. Otherwise, it may cause a malfunction.
- Do not drop or strike the servo amplifier. Isolate it from all impact loads.
- Do not install or operate the servo amplifier which has been damaged or has any parts missing.
- When the product has been stored for an extended period of time, contact your local sales office.
- When handling the servo amplifier, be careful about the edged parts such as corners of the servo amplifier.
- The servo amplifier must be installed in a metal cabinet.
- When fumigants that contain halogen materials such as fluorine, chlorine, bromine, and iodine are used for disinfecting and protecting wooden packaging from insects, they cause malfunction when entering our products. Please take necessary precautions to ensure that remaining materials from fumigant do not enter our products, or treat packaging with methods other than fumigation (heat method). Additionally, disinfect and protect wood from insects before packing products.

## 2. INSTALLATION

### 2.1 Installation direction and clearances



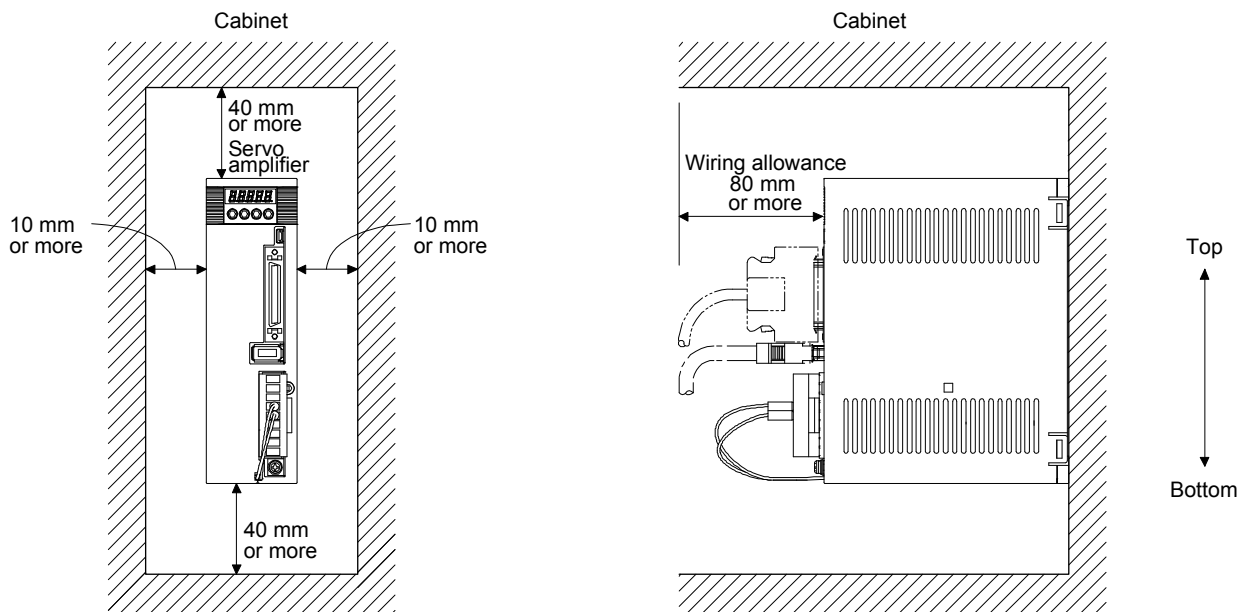
**CAUTION**

- The equipment must be installed in the specified direction. Otherwise, it may cause a malfunction.
- Leave specified clearances between the servo amplifier and the cabinet walls or other equipment. Otherwise, it may cause a malfunction.

MR-JE-40A to MR-JE-100A have a regenerative resistor on their back face. The regenerative resistor generates heat of 100 °C higher than the ambient temperature. Please fully consider heat dissipation, installation position, etc. when mounting it.

#### (1) Installation clearances of the servo amplifier

##### (a) Installation of one servo amplifier



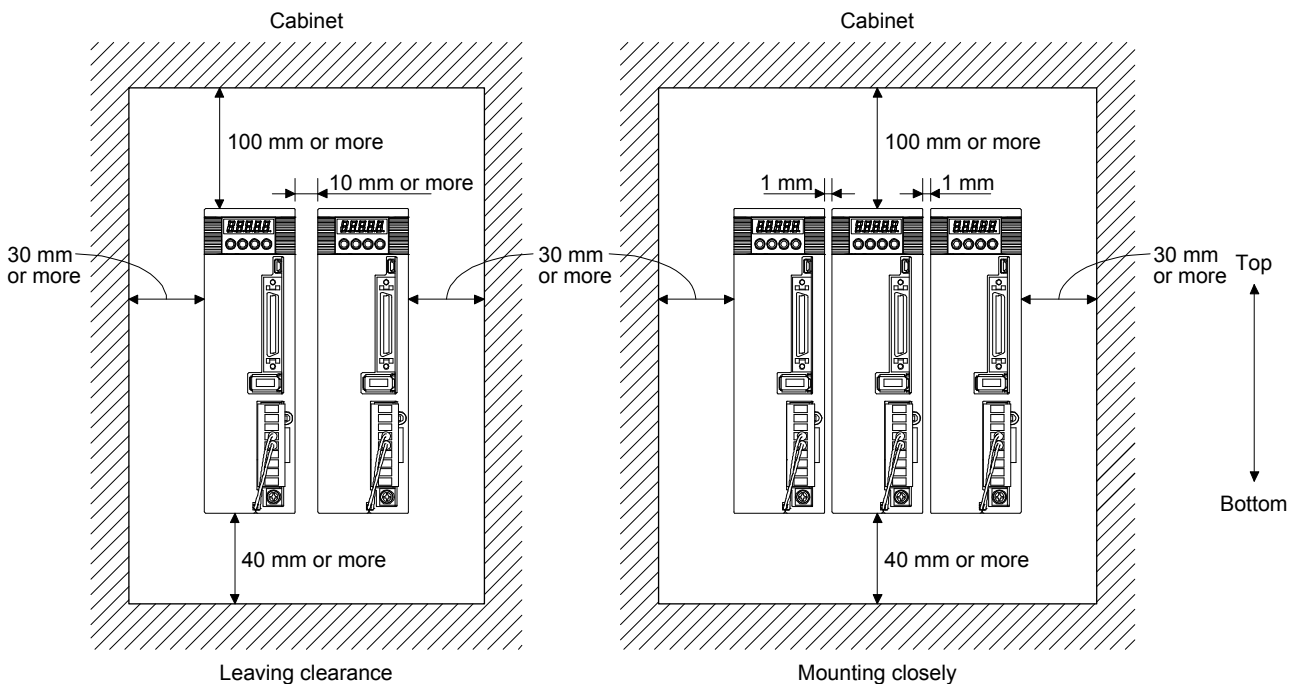
## 2. INSTALLATION

### (b) Installation of two or more servo amplifiers

#### POINT

- Close mounting is possible depending on the capacity of the servo amplifier. Refer to section 1.3 for availability of close mounting.

Leave a large clearance between the top of the servo amplifier and the cabinet walls, and install a cooling fan to prevent the internal temperature of the cabinet from exceeding the environment. When mounting the servo amplifiers closely, leave a clearance of 1 mm between the adjacent servo amplifiers in consideration of mounting tolerances. In this case, keep the ambient temperature within 0 °C to 45 °C or use the servo amplifier with 75% or less of the effective load ratio.



### (2) Others

When using heat generating equipment such as the regenerative option, install them with full consideration of heat generation so that the servo amplifier is not affected.

Install the servo amplifier on a perpendicular wall in the correct vertical direction.

### 2.2 Keep out foreign materials

- (1) When drilling in the cabinet, prevent drill chips and wire fragments from entering the servo amplifier.
- (2) Prevent oil, water, metallic dust, etc. from entering the servo amplifier through openings in the cabinet or a cooling fan installed on the ceiling.
- (3) When installing the cabinet in a place where toxic gas, dirt and dust exist, conduct an air purge (force clean air into the cabinet from outside to make the internal pressure higher than the external pressure) to prevent such materials from entering the cabinet.




## 2. INSTALLATION


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### 2.3 Encoder cable stress

- (1) The way of clamping the cable must be fully examined so that bending stress and cable's own weight stress are not applied to the cable connection.
- (2) For use in any application where the servo motor moves, fix the cables (encoder, power supply, and brake) with having some slack from the connector connection part of the servo motor to avoid putting stress on the connector connection part. Use the optional encoder cable within the bending life range. Use the power supply and brake wiring cables within the bending life of the cables.
- (3) Avoid any probability that the cable insulator might be cut by sharp chips, rubbed by a machine corner or stamped by workers or vehicles.
- (4) For installation on a machine where the servo motor moves, the flexing radius should be made as large as possible. Refer to section 10.4 for the bending life.

### 2.4 Inspection items

 <b>WARNING</b>	<ul style="list-style-type: none"><li>● Before starting maintenance and/or inspection, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Otherwise, an electric shock may occur. In addition, when confirming whether the charge lamp is off or not, always confirm it from the front of the servo amplifier.</li><li>● To avoid an electric shock, only qualified personnel should attempt inspections. For repair and parts replacement, contact your local sales office.</li></ul>
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 <b>CAUTION</b>	<ul style="list-style-type: none"><li>● Do not perform insulation resistance test on the servo amplifier. Otherwise, it may cause a malfunction.</li><li>● Do not disassemble and/or repair the equipment on customer side.</li></ul>
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It is recommended that the following points periodically be checked.

- (1) Check for loose terminal block screws. Retighten any loose screws.
- (2) Check the cables and the like for scratches or cracks. Inspect them periodically according to operating conditions especially when the servo motor is movable.
- (3) Check that the connector is securely connected to the servo amplifier.
- (4) Check that the wires are not coming out from the connector.
- (5) Check for dust accumulation on the servo amplifier.
- (6) Check for unusual noise generated from the servo amplifier.
- (7) Make sure that the emergency stop circuit operates properly such that an operation can be stopped immediately and a power is shut off by the emergency stop switch.

## 2. INSTALLATION

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### 2.5 Parts having service life

Service life of the following parts is listed below. However, the service life varies depending on operating methods and environment. If any fault is found in the parts, they must be replaced immediately regardless of their service life. For parts replacement, please contact your local sales office.

Part name	Life guideline
Smoothing capacitor	10 years
Relay	Number of power-on and forced stop times by EM1 (Forced stop 1): 100,000 times
Cooling fan	50,000 hours to 70,000 hours (7 years to 8 years)

(1) Smoothing capacitor

The characteristic of smoothing capacitor is deteriorated due to ripple currents, etc. The life of the capacitor greatly depends on ambient temperature and operating conditions. The capacitor will reach the end of its life in 10 years of continuous operation in normal air-conditioned environment (ambient temperature of 40 °C or less).

(2) Relays

Contact faults will occur due to contact wear arisen from switching currents. Relays will reach the end of their lives depending on their power supply capacity when the number of power-on times and number of forced stop times by EM1 (Forced stop 1) are 100,000 times in total.

(3) Servo amplifier cooling fan

The cooling fan bearings reach the end of their life in 50,000 hours to 70,000 hours. Normally, therefore, the cooling fan must be replaced in seven to eight years of continuous operation as a guideline. It must also be changed if unusual noise or vibration is found during inspection.

The life indicates under the yearly average ambient temperature of 40 °C, free from corrosive gas, flammable gas, oil mist, dust and dirt.



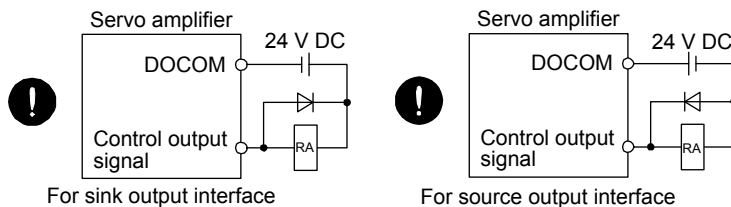
### 3. SIGNALS AND WIRING

#### 3. SIGNALS AND WIRING

**⚠ WARNING**

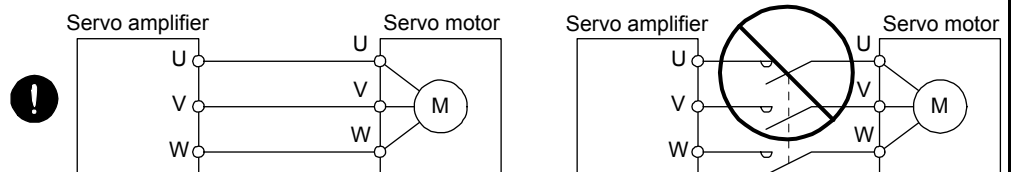
- Any person who is involved in wiring should be fully competent to do the work.
- Before wiring, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Otherwise, an electric shock may occur. In addition, when confirming whether the charge lamp is off or not, always confirm it from the front of the servo amplifier.
- Ground the servo amplifier and servo motor securely.
- Do not attempt to wire the servo amplifier and servo motor until they have been installed. Otherwise, it may cause an electric shock.
- The cables should not be damaged, stressed, loaded, or pinched. Otherwise, it may cause an electric shock.
- To avoid an electric shock, insulate the connections of the power supply terminals.

- Before removing the CNP1 connector from MR-JE-40A to MR-JE-100A, disconnect the lead wires of the regenerative resistor from the CNP1 connector.
- Wire the equipment correctly and securely. Otherwise, the servo motor may operate unexpectedly, resulting in injury.
- Connect cables to the correct terminals. Otherwise, a burst, damage, etc. may occur.
- Ensure that polarity (+/-) is correct. Otherwise, a burst, damage, etc. may occur.
- The surge absorbing diode installed to the DC relay for control output should be fitted in the specified direction. Otherwise, the emergency stop and other protective circuits may not operate.



**⚠ CAUTION**

- Use a noise filter, etc. to minimize the influence of electromagnetic interference. Electromagnetic interference may be given to the electronic equipment used near the servo amplifier.
- Do not install a power capacitor, surge killer or radio noise filter (optional FR-BIF) with the power line of the servo motor.
- When using the regenerative resistor, switch power off with the alarm signal. Otherwise, a transistor fault or the like may overheat the regenerative resistor, causing a fire.
- Do not modify the equipment.
- Connect the servo amplifier power output (U/V/W) to the servo motor power input (U/V/W) directly. Do not let a magnetic contactor, etc. intervene. Otherwise, it may cause a malfunction.



- Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.

### 3. SIGNALS AND WIRING

---

#### 3.1 Input power supply circuit

#### CAUTION

- Always connect a magnetic contactor between the power supply and the power supply (L1/L2/L3) of the servo amplifier, in order to configure a circuit that shuts down the power supply on the side of the servo amplifier's power supply. If a magnetic contactor is not connected, continuous flow of a large current may cause a fire when the servo amplifier malfunctions.
- Use ALM (Malfunction) to switch power off. Not doing so may cause a fire when a regenerative transistor malfunctions or the like may overheat the regenerative resistor.
- Before removing the CNP1 connector from MR-JE-40A to MR-JE-100A, disconnect the lead wires of the regenerative resistor from the CNP1 connector. Not doing so may break the lead wires of the regenerative resistor.
- Check the servo amplifier model, and then input proper voltage to the servo amplifier power supply. If input voltage exceeds the upper limit of the specification, the servo amplifier will break down.
- The servo amplifier has a built-in surge absorber (varistor) to reduce exogenous noise and to suppress lightning surge. Exogenous noise or lightning surge deteriorates the varistor characteristics, and the varistor may be damaged. To prevent a fire, use a molded-case circuit breaker or fuse for input power supply.
- Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.
- The N- terminal is not a neutral point of the power supply. Incorrect wiring will cause a burst, damage, etc. The servo amplifiers without the N- terminal will be available sequentially from the December 2016 production.

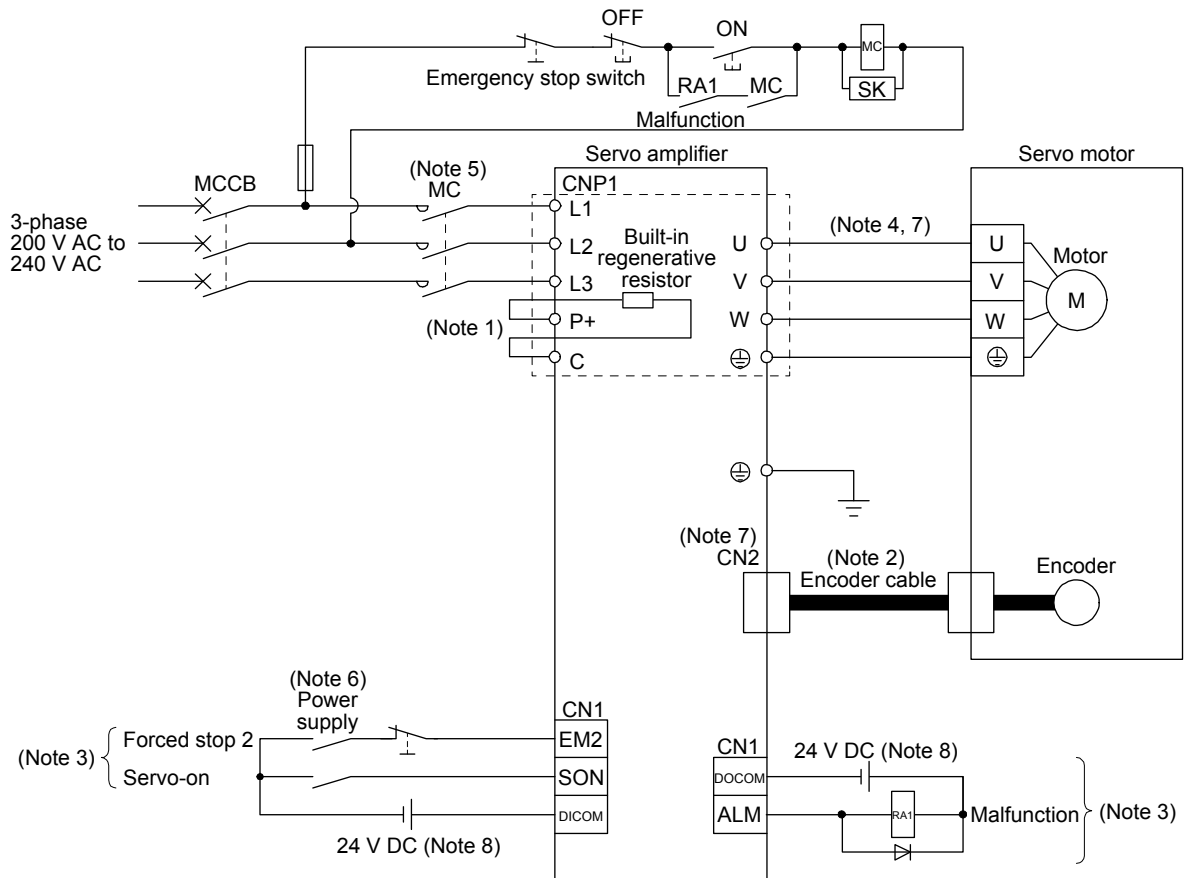
#### POINT

- EM2 has the same function as EM1 in the torque control mode.
- When a 1-phase 200 V AC to 240 V AC power supply is used, the connection destination differs depending on the servo amplifier. Ensure that the connection destination is correct.

Configure the wirings so that the power supply is shut off and SON (Servo-on) is turned off after deceleration to a stop due to an alarm occurring, enabled servo forced stop, etc. A molded-case circuit breaker (MCCB) must be used with the input cables of the power supply.

### 3. SIGNALS AND WIRING

(1) For 3-phase 200 V AC to 240 V AC power supply of MR-JE-10A to MR-JE-100A



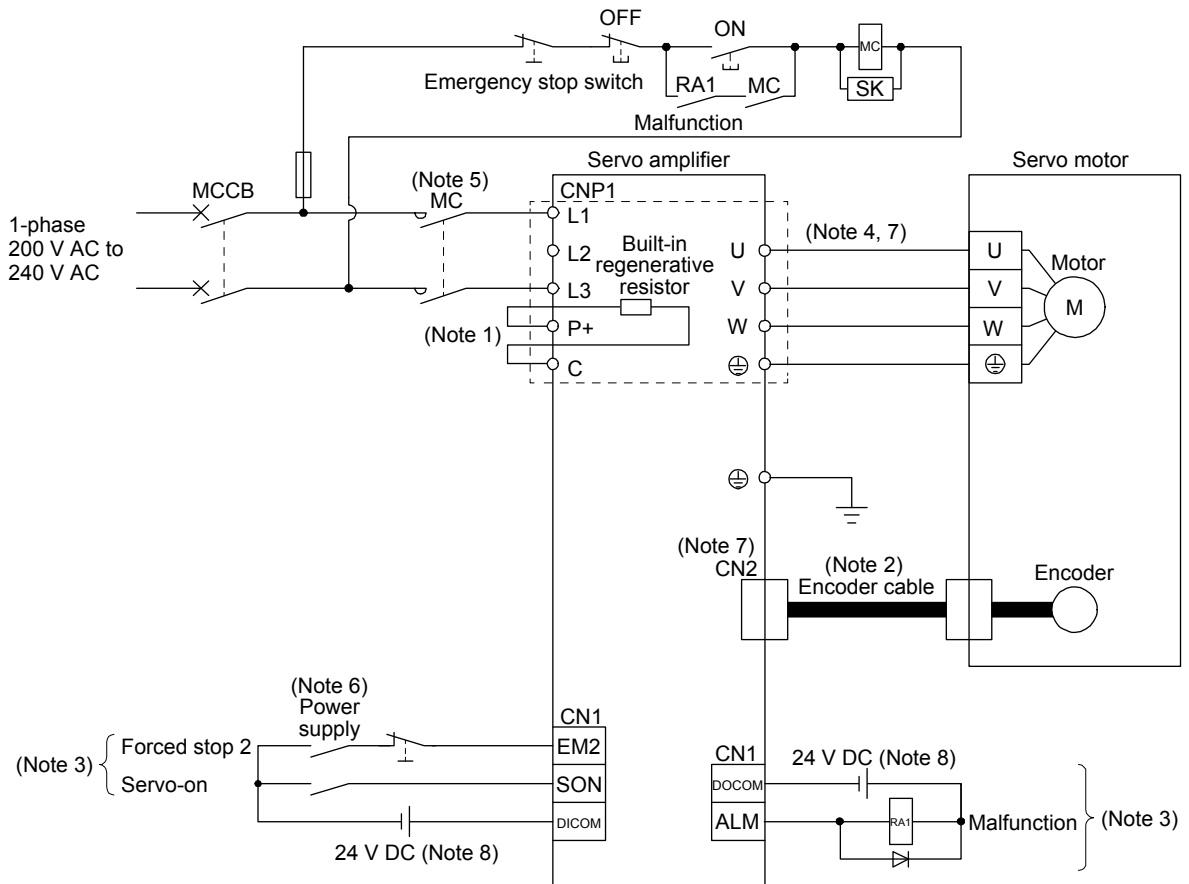
- Note 1. MR-JE-40A to MR-JE-100A have a built-in regenerative resistor. (factory-wired) When using the regenerative option, refer to section 11.2.
- Note 2. For the encoder cable, use of the option cable is recommended. For selecting cables, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 3. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.
- Note 4. For connecting servo motor power wires, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 5. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.
- Note 6. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 7. Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.
- Note 8. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.

### 3. SIGNALS AND WIRING

(2) For 1-phase 200 V AC to 240 V AC power supply of MR-JE-10A to MR-JE-100A

**POINT**

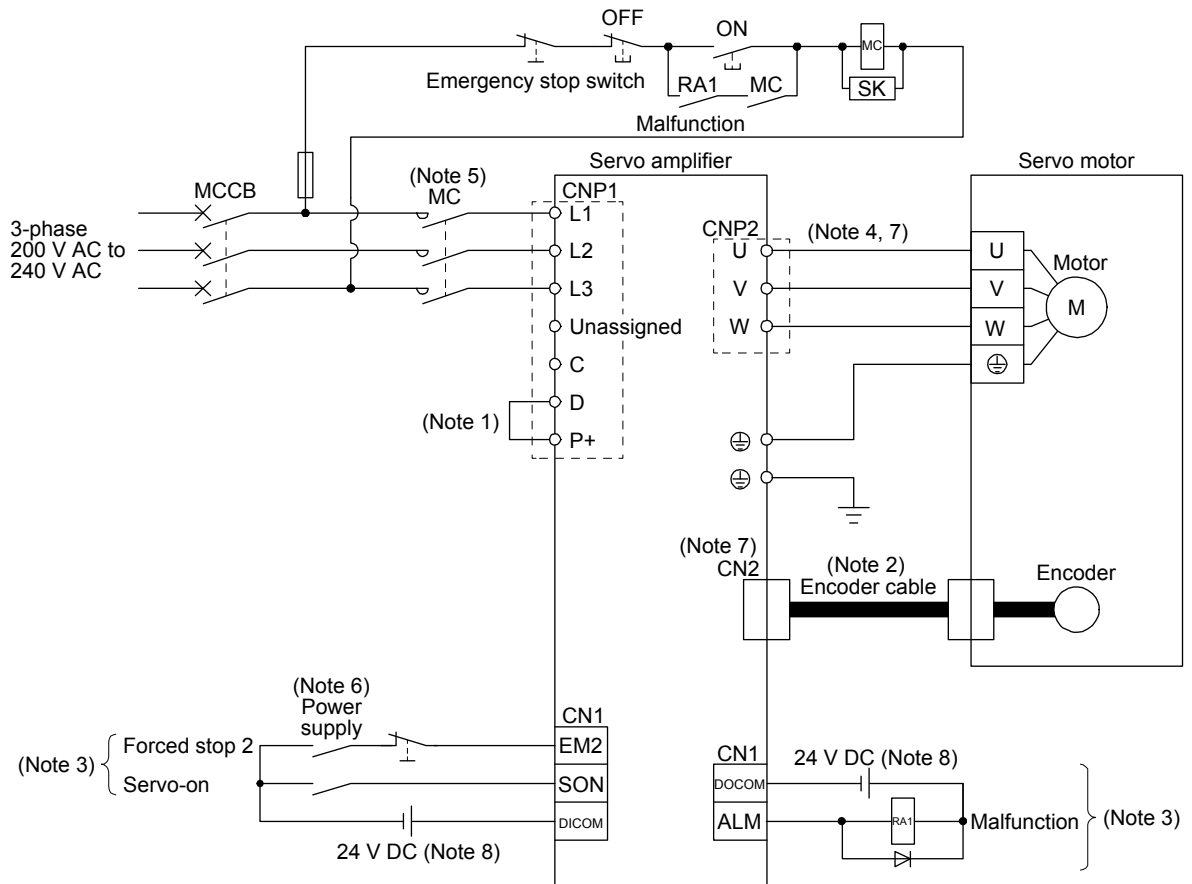
- Connect the 1-phase 200 V AC to 240 V AC power supply to L1 and L3. One of the connecting destinations is different from MR-JE-200A Servo Amplifier's.
- You can use the neutral point of a 3-phase 400 V AC class power supply to input a 1-phase 200 V AC class power supply to the servo amplifier. Refer to app. 7 for details.



- Note 1. MR-JE-40A and MR-JE-100A have a built-in regenerative resistor. (factory-wired) When using the regenerative option, refer to section 11.2.
- Note 2. For the encoder cable, use of the option cable is recommended. For selecting cables, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 3. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.
- Note 4. For connecting servo motor power wires, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 5. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.
- Note 6. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 7. Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.
- Note 8. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.

### 3. SIGNALS AND WIRING

(3) For 3-phase 200 V AC to 240 V AC power supply of MR-JE-200A or MR-JE-300A



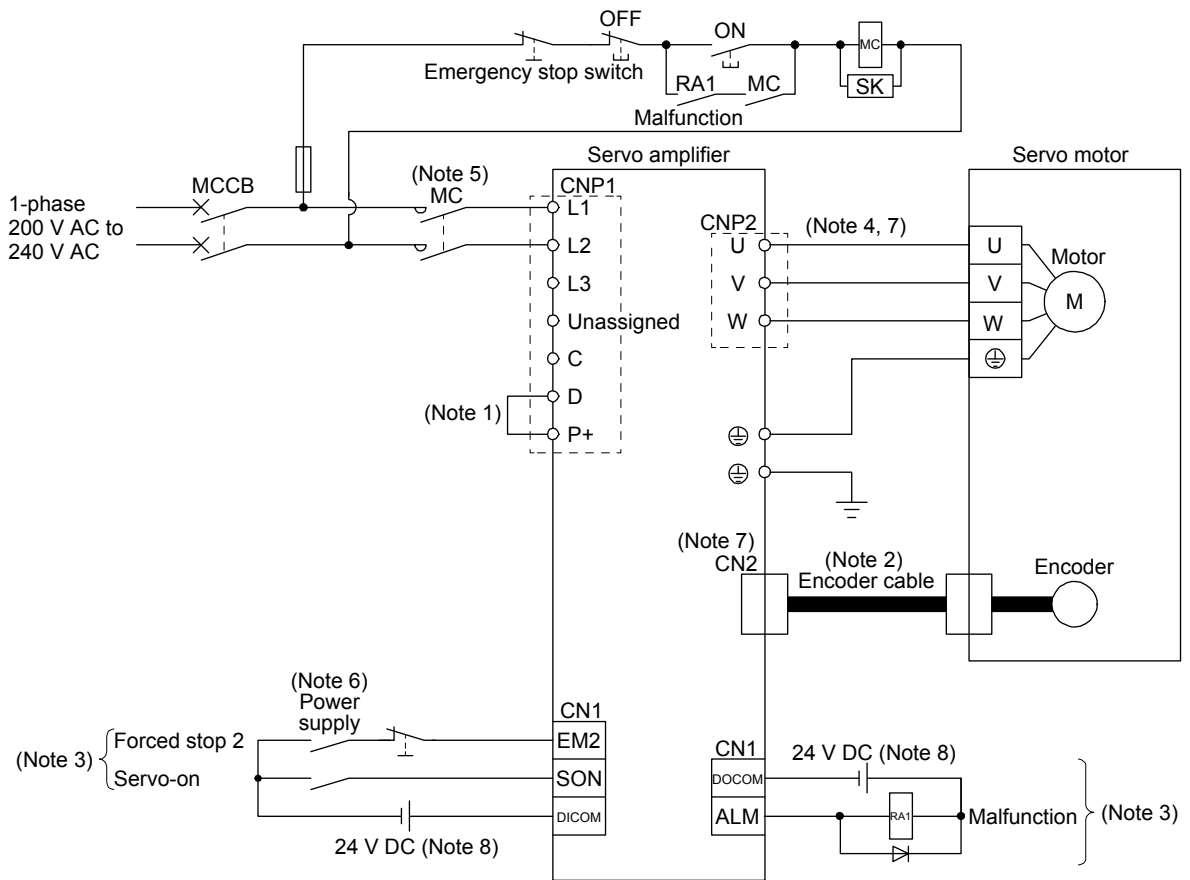
- Note 1. Always connect between P+ and D terminals. (factory-wired) When using the regenerative option, refer to section 11.2.
- Note 2. For the encoder cable, use of the option cable is recommended. For selecting cables, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 3. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.
- Note 4. For connecting servo motor power wires, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 5. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.
- Note 6. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 7. Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.
- Note 8. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.



### 3. SIGNALS AND WIRING

(4) For 1-phase 200 V AC to 240 V AC power supply of MR-JE-200A

POINT
<ul style="list-style-type: none"> <li>● Connect the 1-phase 200 V AC to 240 V AC power supply to L1 and L2. One of the connecting destinations is different from MR-JE-100A or less Servo Amplifier's.</li> <li>● You can use the neutral point of a 3-phase 400 V AC class power supply to input a 1-phase 200 V AC class power supply to the servo amplifier. Refer to app. 7 for details.</li> </ul>



- Note 1. Always connect between P+ and D terminals. (factory-wired) When using the regenerative option, refer to section 11.2.
- Note 2. For the encoder cable, use of the option cable is recommended. For cable selection, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 3. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.
- Note 4. For connection of servo motor power wires, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".
- Note 5. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, slow the time to turn off the magnetic contactor.
- Note 6. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 7. Connecting a servo motor of the wrong axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.
- Note 8. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.

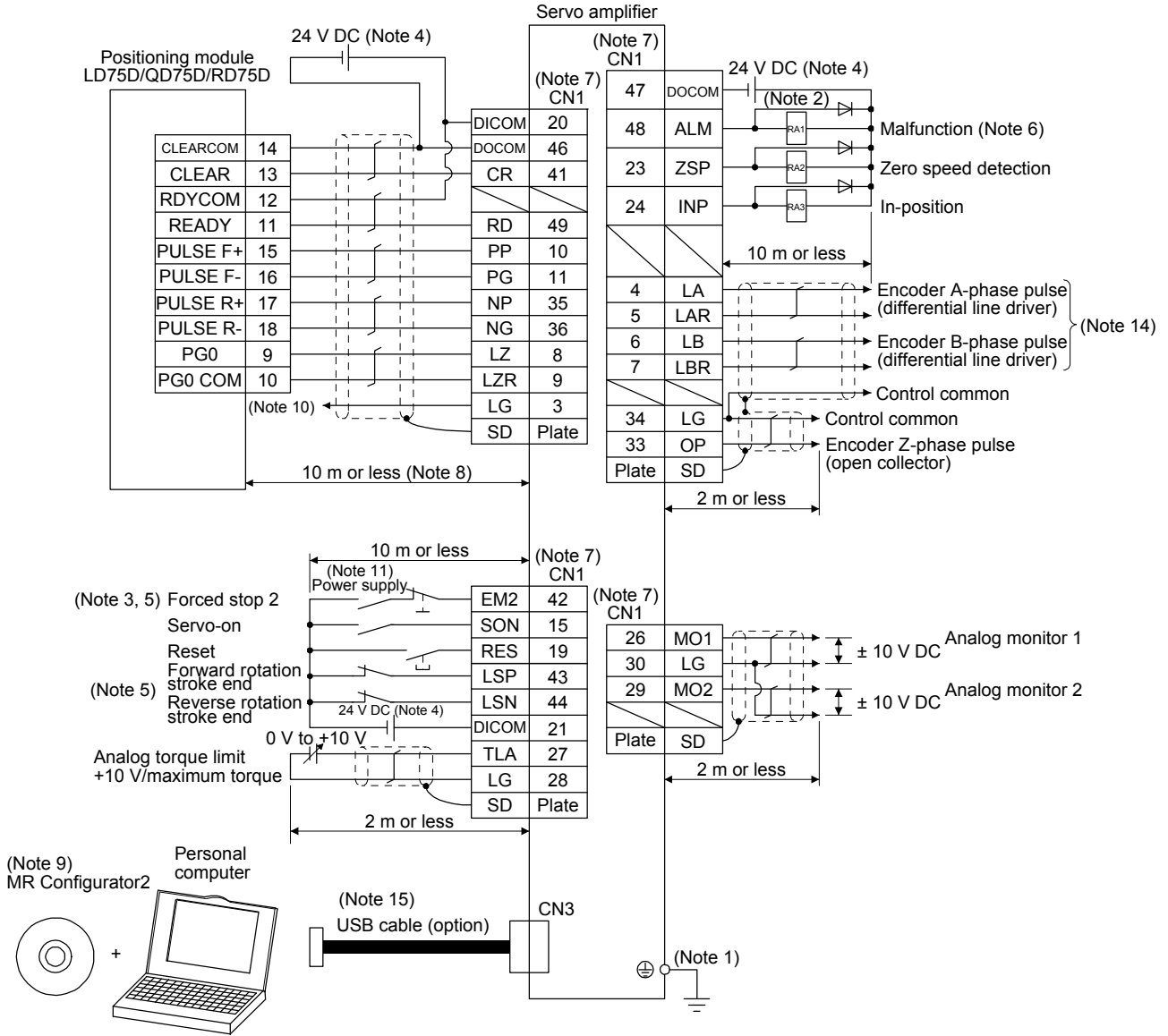
### 3. SIGNALS AND WIRING

#### 3.2 I/O signal connection example

##### 3.2.1 Position control mode

(1) When you use a positioning module LD75D/QD75D/RD75D

(a) For sink I/O interface



### 3. SIGNALS AND WIRING

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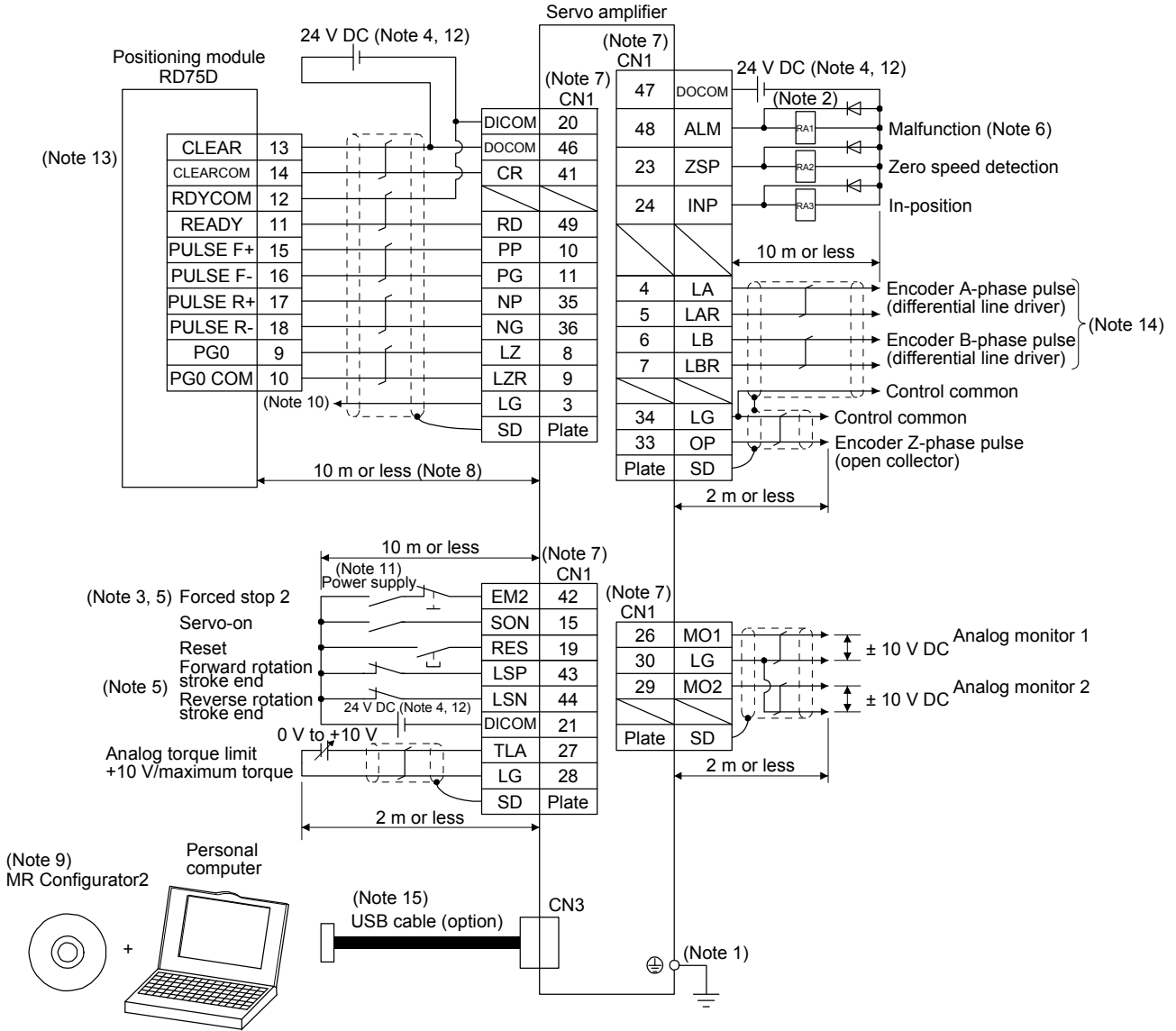
- Note
1. To prevent an electric shock, always connect the protective earth (PE) terminal (marked  $\oplus$ ) of the servo amplifier to the protective earth (PE) of the cabinet.
  2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will malfunction and will not output signals, disabling EM2 (Forced stop 2) and other protective circuits.
  3. The forced stop switch (normally closed contact) must be installed.
  4. Supply 24 V DC  $\pm$  10% to interfaces from outside. The total current capacity is up to 300 mA. 300 mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.9.2 (1) that gives the current value necessary for the interface. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.
  5. When starting operation, always turn on EM2 (Forced stop 2), LSP (Forward rotation stroke end) and LSN (Reverse rotation stroke end) (normally closed contact).
  6. ALM (Malfunction) turns on in normal alarm-free condition (normally closed contact). When this signal is switched off (at occurrence of an alarm), the output of the programmable controller should be stopped by the sequence program.
  7. The pins with the same signal name are connected in the servo amplifier.
  8. This length applies to the command pulse train input in the differential line driver type. It is 2 m or less in the open-collector type.
  9. Use SW1DNC-MRC2-\_. (Refer to section 11.4.)
  10. This connection is not necessary for RD75D. However, to enhance noise tolerance, it is recommended to connect LG of servo amplifier and control common depending on the positioning module.
  11. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
  12. Plus and minus of the power of source interface are the opposite of those of sink interface.
  13. CLEAR and CLEARCOM of source interface are interchanged to sink interface.
  14. When a command cable for connection with the controller side malfunctions due to disconnection or noise, a position mismatch can occur. To avoid position mismatch, it is recommended that Encoder A-phase pulse and Encoder B-phase pulse be checked.
  15. The USB communication function and RS-422/RS-485 communication function are mutually exclusive. They cannot be used together.

### 3. SIGNALS AND WIRING

(b) For source I/O interface

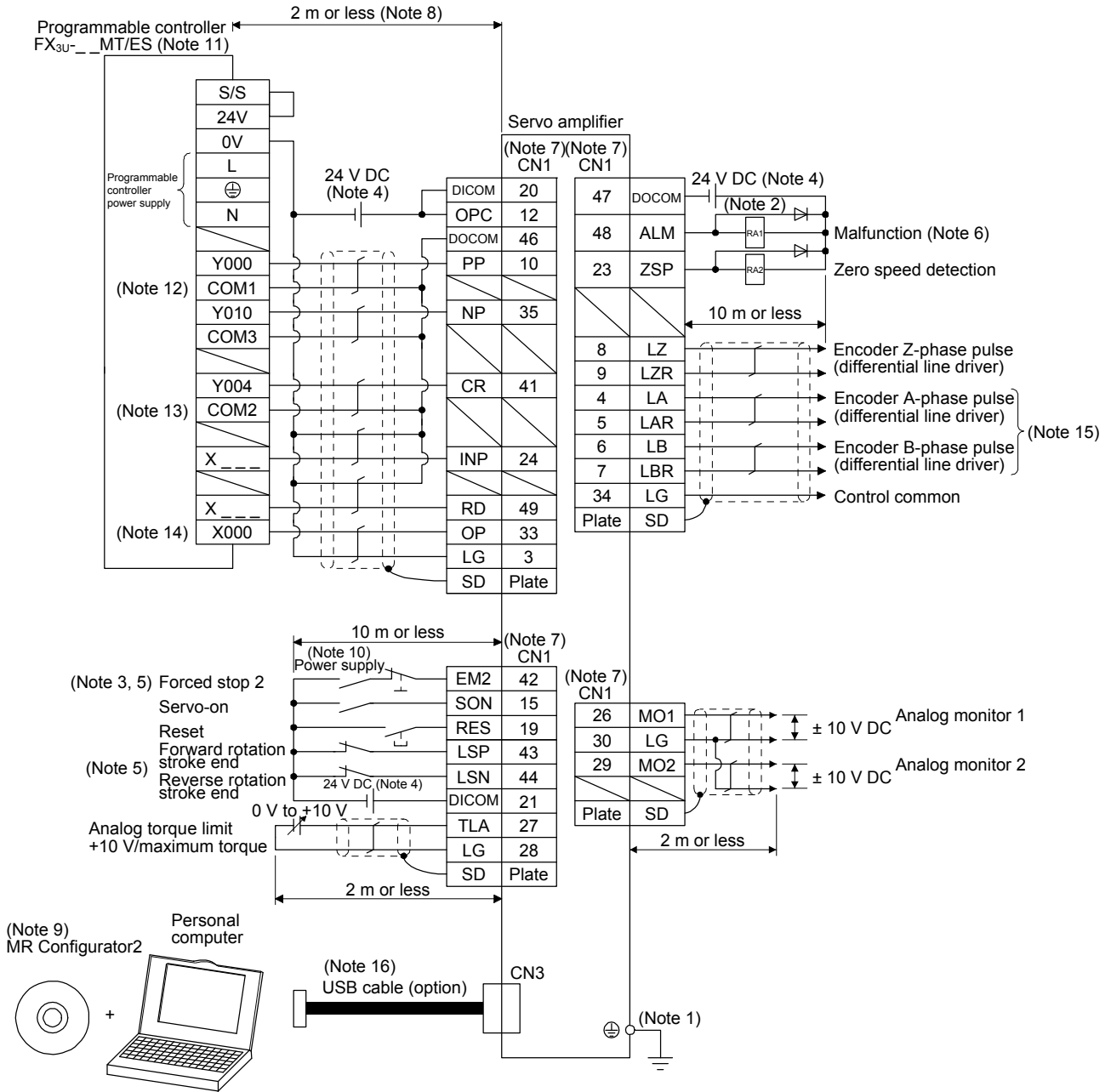
**POINT**

● For notes, refer to (1) (a) in this section.



### 3. SIGNALS AND WIRING

(2) When you use a positioning module FX<sub>3U</sub>-\_\_MT/ES (For sink I/O interface)



### 3. SIGNALS AND WIRING

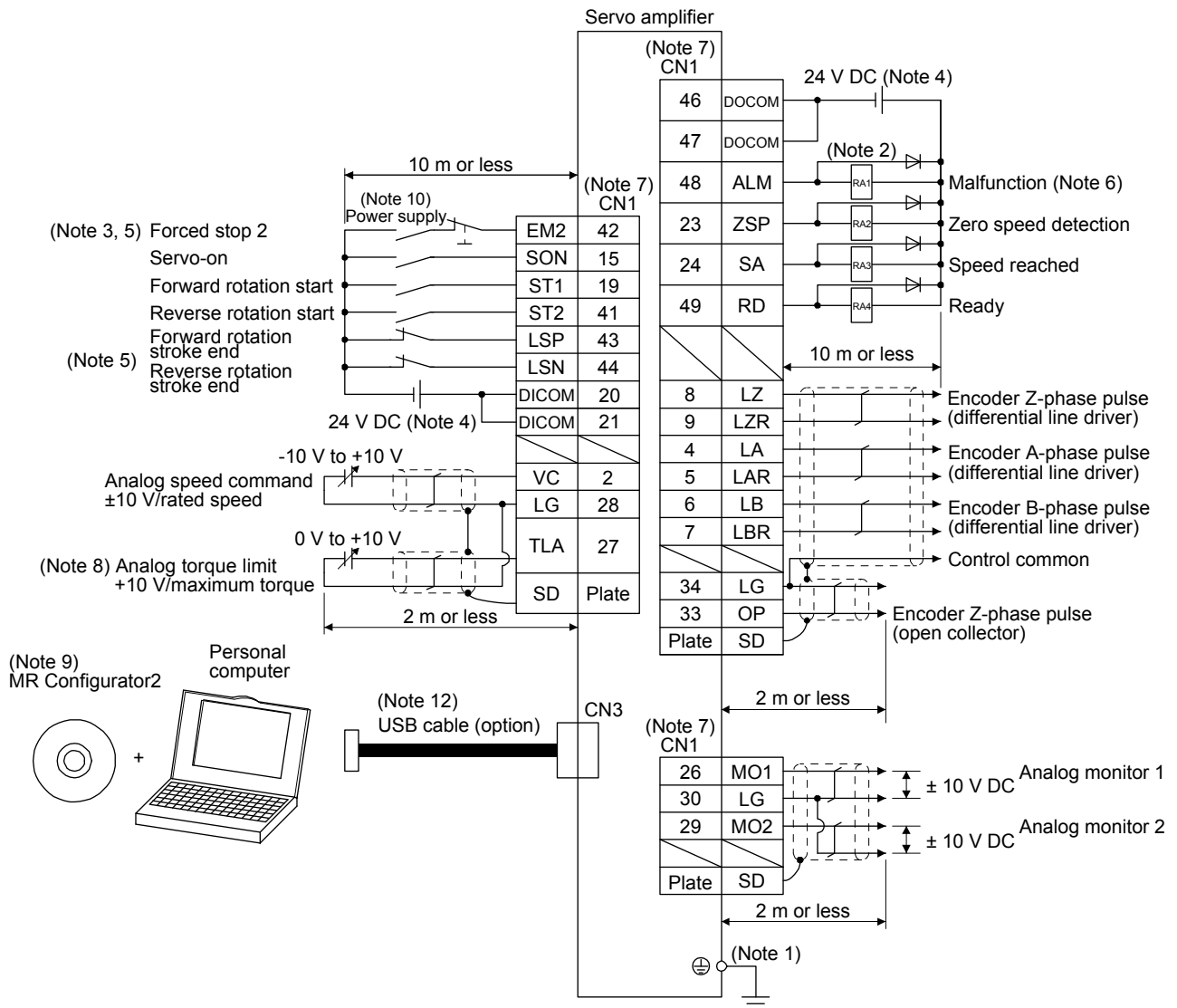
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- Note
1. To prevent an electric shock, always connect the protective earth (PE) terminal (marked  $\oplus$ ) of the servo amplifier to the protective earth (PE) of the cabinet.
  2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will malfunction and will not output signals, disabling EM2 (Forced stop 2) and other protective circuits.
  3. The forced stop switch (normally closed contact) must be installed.
  4. Supply 24 V DC  $\pm$  10% to interfaces from outside. The total current capacity is up to 300 mA. 300 mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.9.2 (1) that gives the current value necessary for the interface. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.
  5. When starting operation, always turn on EM2 (Forced stop 2), LSP (Forward rotation stroke end) and LSN (Reverse rotation stroke end) (normally closed contact).
  6. ALM (Malfunction) turns on in normal alarm-free condition (normally closed contact). When this signal is switched off (at occurrence of an alarm), the output of the programmable controller should be stopped by the sequence program.
  7. The pins with the same signal name are connected in the servo amplifier.
  8. Connect them within 2 m because of open-collector type.
  9. Use SW1DNC-MRC2-\_. (Refer to section 11.4.)
  10. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
  11. Select the number of I/O points of the programmable controller depending on your system.
  12. It will be COM0 for FX<sub>3U</sub>-16MT/ES.
  13. It will be COM4 for FX<sub>3U</sub>-16MT/ES.
  14. Select it within X000 to X007.
  15. When a command cable for connection with the controller side malfunctions due to disconnection or noise, a position mismatch can occur. To avoid position mismatch, it is recommended that Encoder A-phase pulse and Encoder B-phase pulse be checked.
  16. The USB communication function and RS-422/RS-485 communication function are mutually exclusive. They cannot be used together.

### 3. SIGNALS AND WIRING

#### 3.2.2 Speed control mode

##### (1) For sink I/O interface

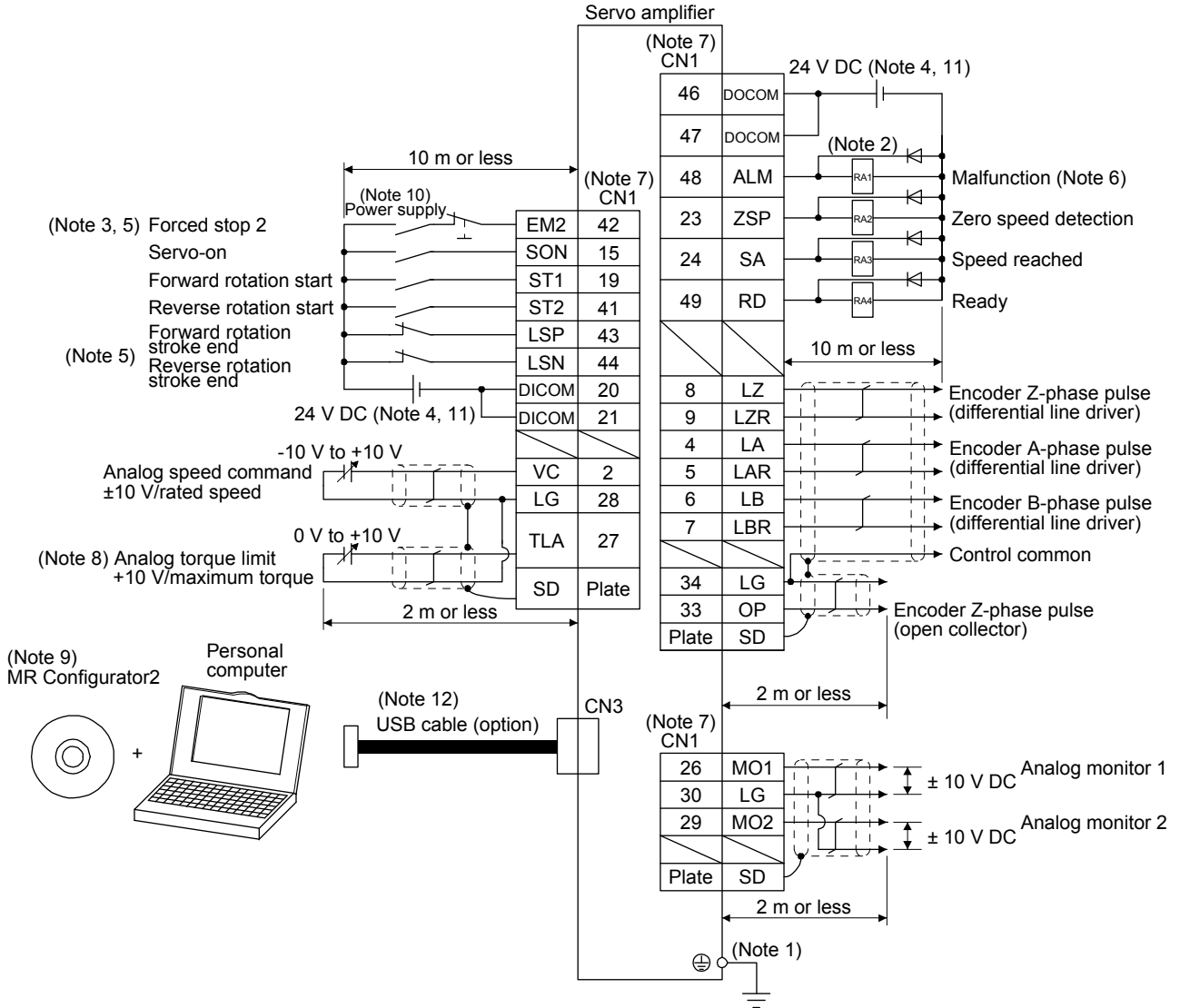


- Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal (marked ⊕) of the servo amplifier to the protective earth (PE) of the cabinet.
- Note 2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will malfunction and will not output signals, disabling EM2 (Forced stop 2) and other protective circuits.
- Note 3. The forced stop switch (normally closed contact) must be installed.
- Note 4. Supply 24 V DC ± 10% to interfaces from outside. The total current capacity is up to 300 mA. 300 mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.9.2 (1) that gives the current value necessary for the interface. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.
- Note 5. When starting operation, always turn on EM2 (Forced stop 2), LSP (Forward rotation stroke end) and LSN (Reverse rotation stroke end) (normally closed contact).
- Note 6. ALM (Malfunction) turns on in normal alarm-free condition (normally closed contact).
- Note 7. The pins with the same signal name are connected in the servo amplifier.
- Note 8. TLA will be available when TL (External torque limit selection) is enabled with [Pr. PD03], [Pr. PD11], [Pr. PD13], [Pr. PD17], and [Pr. PD19]. (Refer to section 3.6.1 (5).)
- Note 9. Use SW1DNC-MRC2-\_. (Refer to section 11.4.)
- Note 10. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 11. Plus and minus of the power of source interface are the opposite of those of sink interface.
- Note 12. The USB communication function and RS-422/RS-485 communication function are mutually exclusive. They cannot be used together.

### 3. SIGNALS AND WIRING

(2) For source I/O interface

POINT
● For notes, refer to (1) in this section.



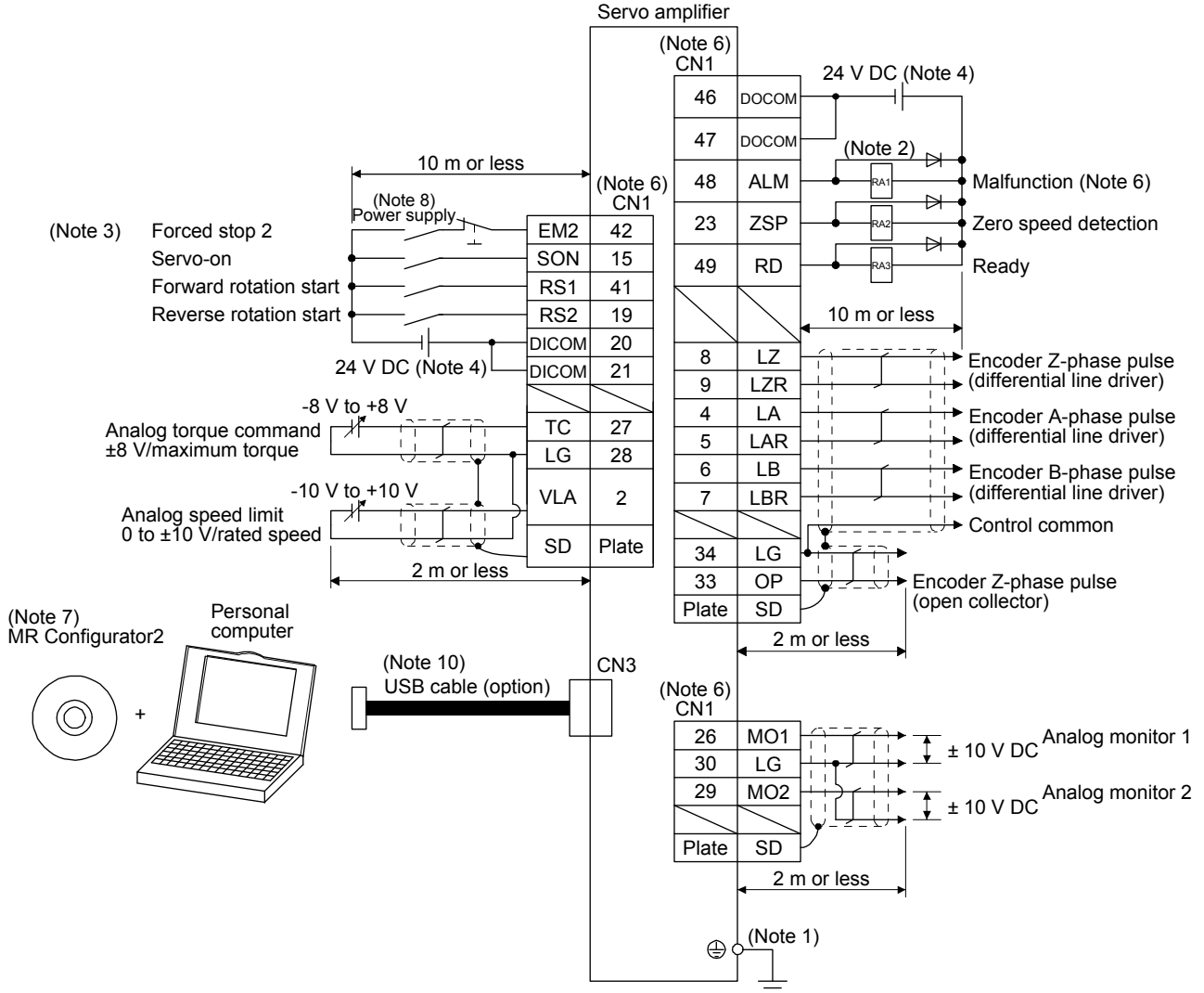


# 3. SIGNALS AND WIRING

## 3.2.3 Torque control mode

<b>POINT</b>
●EM2 has the same function as EM1 in the torque control mode.

### (1) For sink I/O interface

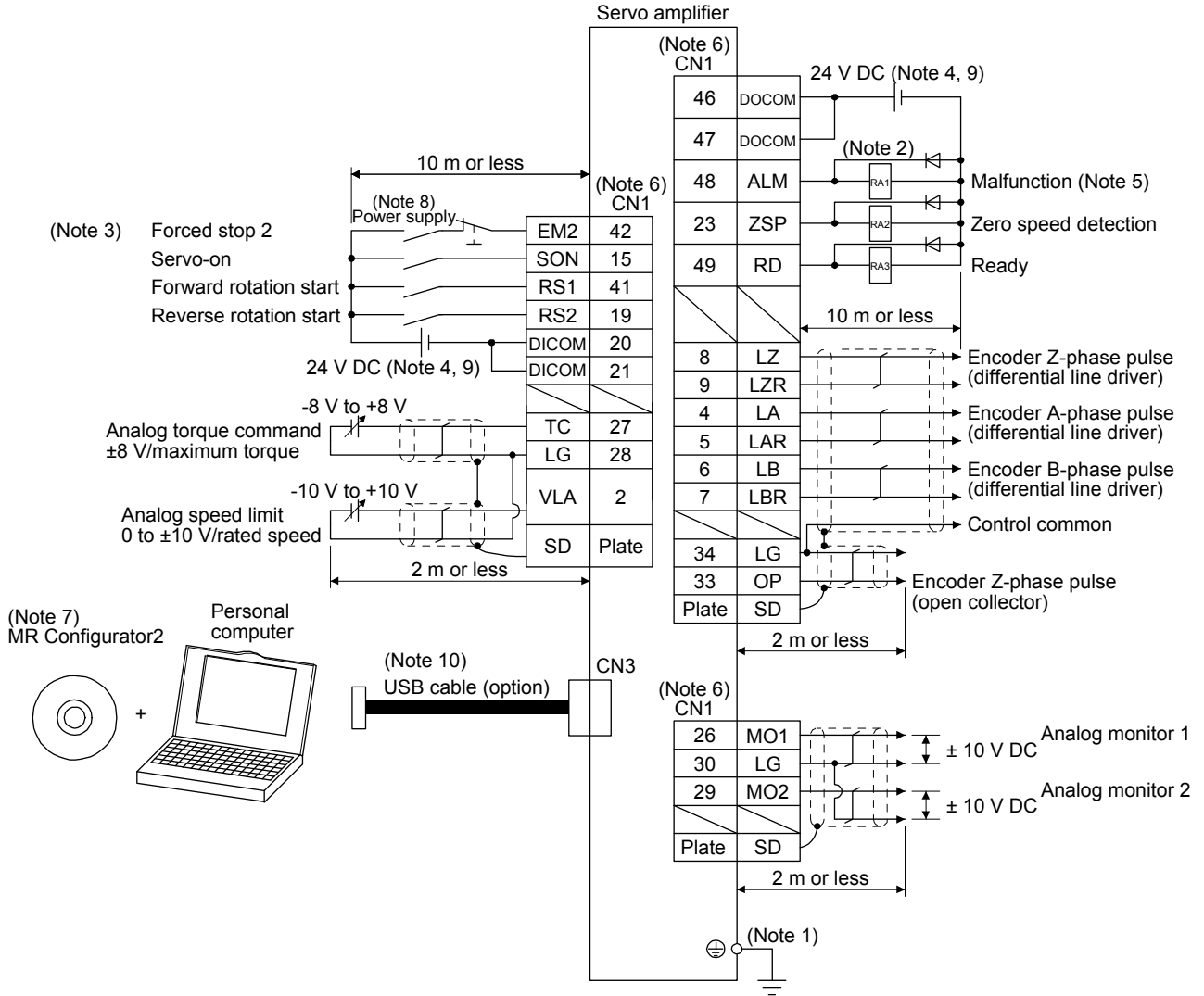


- Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal (marked  $\oplus$ ) of the servo amplifier to the protective earth (PE) of the cabinet.
- Note 2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will malfunction and will not output signals, disabling EM2 (Forced stop 2) and other protective circuits.
- Note 3. The forced stop switch (normally closed contact) must be installed.
- Note 4. Supply 24 V DC  $\pm 10\%$  to interfaces from outside. The total current capacity is up to 300 mA. 300 mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to section 3.9.2 (1) that gives the current value necessary for the interface. The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.
- Note 5. ALM (Malfunction) turns on in normal alarm-free condition (normally closed contact).
- Note 6. The pins with the same signal name are connected in the servo amplifier.
- Note 7. Use SW1DNC-MRC2-\_. (Refer to section 11.4.)
- Note 8. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 9. Plus and minus of the power of source interface are the opposite of those of sink interface.
- Note 10. The USB communication function and RS-422/RS-485 communication function are mutually exclusive. They cannot be used together.

### 3. SIGNALS AND WIRING

(2) For source I/O interface

POINT
● For notes, refer to (1) in this section.



### 3. SIGNALS AND WIRING

#### 3.3 Explanation of power supply system

##### 3.3.1 Signal explanations

POINT
● For the layout of connector and terminal block, refer to chapter 9 DIMENSIONS.

Symbol	Connection target (application)	Description																
L1/L2/L3	Power supply	<p>Supply the following power to L1/L2/L3. For 1-phase 200 V AC to 240 V AC, connect the power supply to L1 and L3. Leave L2 open. When using 1-phase 200 V AC to 240 V AC for MR-JE-200A, connect the power supply to L1 and L2. Leave L3 open.</p> <table border="1" style="width: 100%; border-collapse: collapse;"> <thead> <tr> <th style="width: 50%;">Servo amplifier</th> <th style="width: 16.6%;">MR-JE-10A to MR-JE-100A</th> <th style="width: 16.6%;">MR-JE-200A</th> <th style="width: 16.6%;">MR-JE-300A</th> </tr> </thead> <tbody> <tr> <td>Power supply</td> <td></td> <td></td> <td></td> </tr> <tr> <td>3-phase 200 V AC to 240 V AC, 50 Hz/60 Hz</td> <td colspan="3" style="text-align: center;">L1/L2/L3</td> </tr> <tr> <td>1-phase 200 V AC to 240 V AC, 50 Hz/60 Hz</td> <td style="text-align: center;">L1/L3</td> <td style="text-align: center;">L1/L2</td> <td style="text-align: center;">/</td> </tr> </tbody> </table>	Servo amplifier	MR-JE-10A to MR-JE-100A	MR-JE-200A	MR-JE-300A	Power supply				3-phase 200 V AC to 240 V AC, 50 Hz/60 Hz	L1/L2/L3			1-phase 200 V AC to 240 V AC, 50 Hz/60 Hz	L1/L3	L1/L2	/
Servo amplifier	MR-JE-10A to MR-JE-100A	MR-JE-200A	MR-JE-300A															
Power supply																		
3-phase 200 V AC to 240 V AC, 50 Hz/60 Hz	L1/L2/L3																	
1-phase 200 V AC to 240 V AC, 50 Hz/60 Hz	L1/L3	L1/L2	/															
P+/C/D	Regenerative option	<p>1) MR-JE-100A or less MR-JE-10A to MR-JE-100A do not have D. When using a servo amplifier built-in regenerative resistor, connect P+ and C. (factory-wired) MR-JE-10A and MR-JE-20A do not have a built-in regenerative resistor. When using a regenerative option, disconnect wires of P+ and C for the built-in regenerative resistor. And then connect wires of the regenerative option to P+ and C.</p> <p>2) MR-JE-200A or more When using a servo amplifier built-in regenerative resistor, connect P+ and D. (factory-wired) When using a regenerative option, disconnect P+ and D, and connect the regenerative option to P+ and C.</p> <p>Refer to section 11.2 for details.</p>																
U/V/W	Servo motor power output	Connect them to the servo motor power supply (U/V/W). Connect the servo amplifier power output (U/V/W) to the servo motor power input (U/V/W) directly. Do not let a magnetic contactor, etc. intervene. Otherwise, it may cause a malfunction.																
N-		<p>This is for manufacturer adjustment. Leave this open. MR-JE-10A to MR-JE-100A do not have N- terminal. MR-JE-200A and MR-JE-300A servo amplifiers without the N- terminal will be available sequentially from the December 2016 production.</p>																
⊕	Protective earth (PE)	Connect it to the grounding terminal of the servo motor and to the protective earth (PE) of the cabinet for grounding.																

### 3. SIGNALS AND WIRING

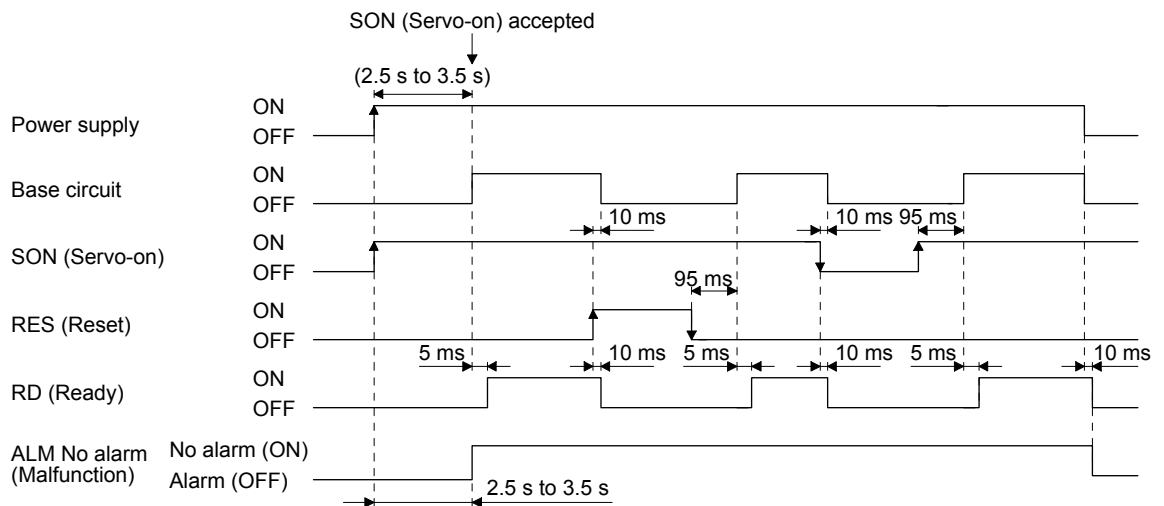
#### 3.3.2 Power-on sequence

POINT
<p>● The voltage of analog monitor output, output signal, etc. may be unstable at power-on.</p>

#### (1) Power-on procedure

- 1) Always wire the power supply as shown in above section 3.1 using the magnetic contactor with the power supply (L1/L2/L3). Configure an external sequence to switch off the magnetic contactor as soon as an alarm occurs.
- 2) The servo amplifier receives the SON (Servo-on) 2.5 s to 3.5 s after the power supply is switched on. Therefore, when SON (Servo-on) is switched on simultaneously with the power supply, the base circuit will switch on in about 2.5 s to 3.5 s, and the RD (Ready) will switch on in further about 5 ms, making the servo amplifier ready to operate. (Refer to (2) of this section.)
- 3) When RES (Reset) is switched on, the base circuit is shut off and the servo motor shaft coasts.

#### (2) Timing chart



### 3. SIGNALS AND WIRING

#### 3.3.3 Wiring CNP1 and CNP2

POINT
● For the wire sizes used for wiring, refer to section 11.5.

To wire to CNP1 and CNP2, use servo amplifier power connectors packed with the amplifier or optional connectors (refer to section 11.1.1).

(1) Connector

(a) MR-JE-10A to MR-JE-100A

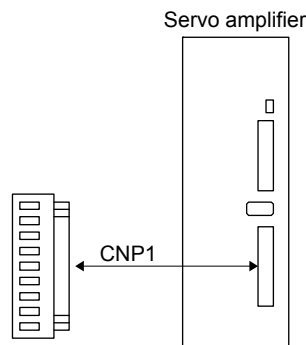


Table 3.1 Connector and applicable wire

Connector	Receptacle assembly	Applicable wire		Stripped length [mm]	Open tool	Manufacturer
		Size	Insulator OD			
CNP1	09JFAT-SAXGDK-H5.0	AWG 18 to 14	3.9 mm or shorter	9	J-FAT-OT (N) or J-FAT-OT	JST

(b) MR-JE-200A/MR-JE-300A

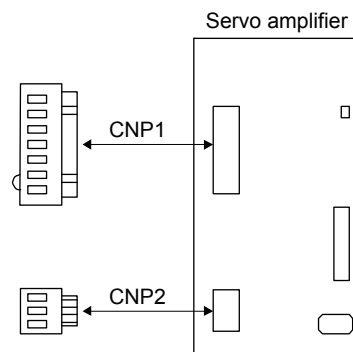


Table 3.2 Connector and applicable wire

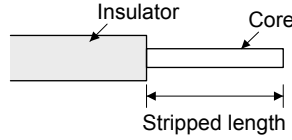
Connector	Receptacle assembly	Applicable wire		Stripped length [mm]	Open tool	Manufacturer
		Size	Insulator OD			
CNP1	06(7-4)JFAT-SAXGFK-XL	AWG 16 to 10	4.7 mm or shorter	11.5	J-FAT-OT-EXL	JST
CNP2	03JFAT-SAXGFK-XL					

### 3. SIGNALS AND WIRING

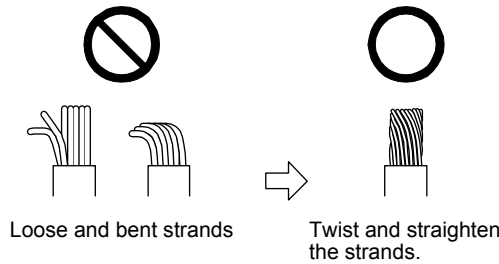
(2) Cable connection procedure

(a) Fabrication on cable insulator

Refer to table 3.1 and 3.2 for stripped length of cable insulator. The appropriate stripped length of cables depends on their type, etc. Set the length considering their status.



Twist strands lightly and straighten them as follows.



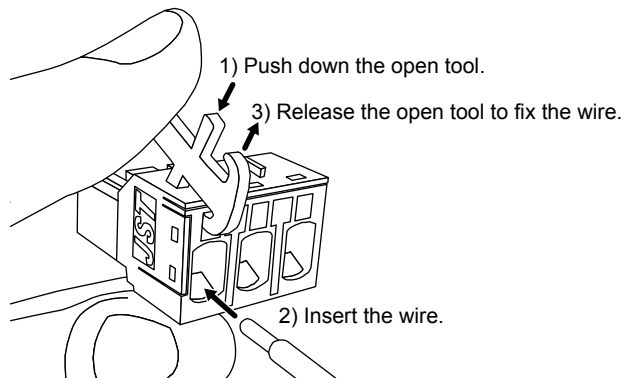
You can also use a ferrule to connect with the connectors. When you use a ferrule, use the following ferrules and crimp terminal.

Servo amplifier	Wire size	Ferrule model (Phoenix Contact)		Crimp terminal (Phoenix Contact)
		For one	For two	
MR-JE-10A to MR-JE-100A	AWG 16	AI1.5-10BK	AI-TWIN2×1.5-10BK	CRIMPFOX-ZA3
	AWG 14	AI2.5-10BU		
MR-JE-200A to MR-JE-300A	AWG 16	AI1.5-10BK	AI-TWIN2×1.5-10BK	
	AWG 14	AI2.5-10BU	AI-TWIN2×2.5-10BU	
	AWG 12	AI4-10GY		

(b) Inserting wire

Insert the open tool as follows and push down it to open the spring. While the open tool is pushed down, insert the stripped wire into the wire insertion hole. Check the insertion depth so that the wire insulator does not get caught by the spring.

Release the open tool to fix the wire. Pull the wire lightly to confirm that the wire is surely connected. The following shows a connection example of the CNP2 connector for 2 kW and 3 kW.

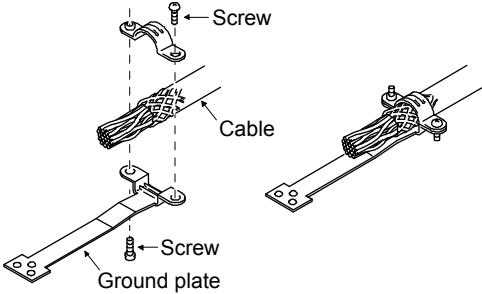


### 3. SIGNALS AND WIRING

#### 3.4 Connectors and pin assignment

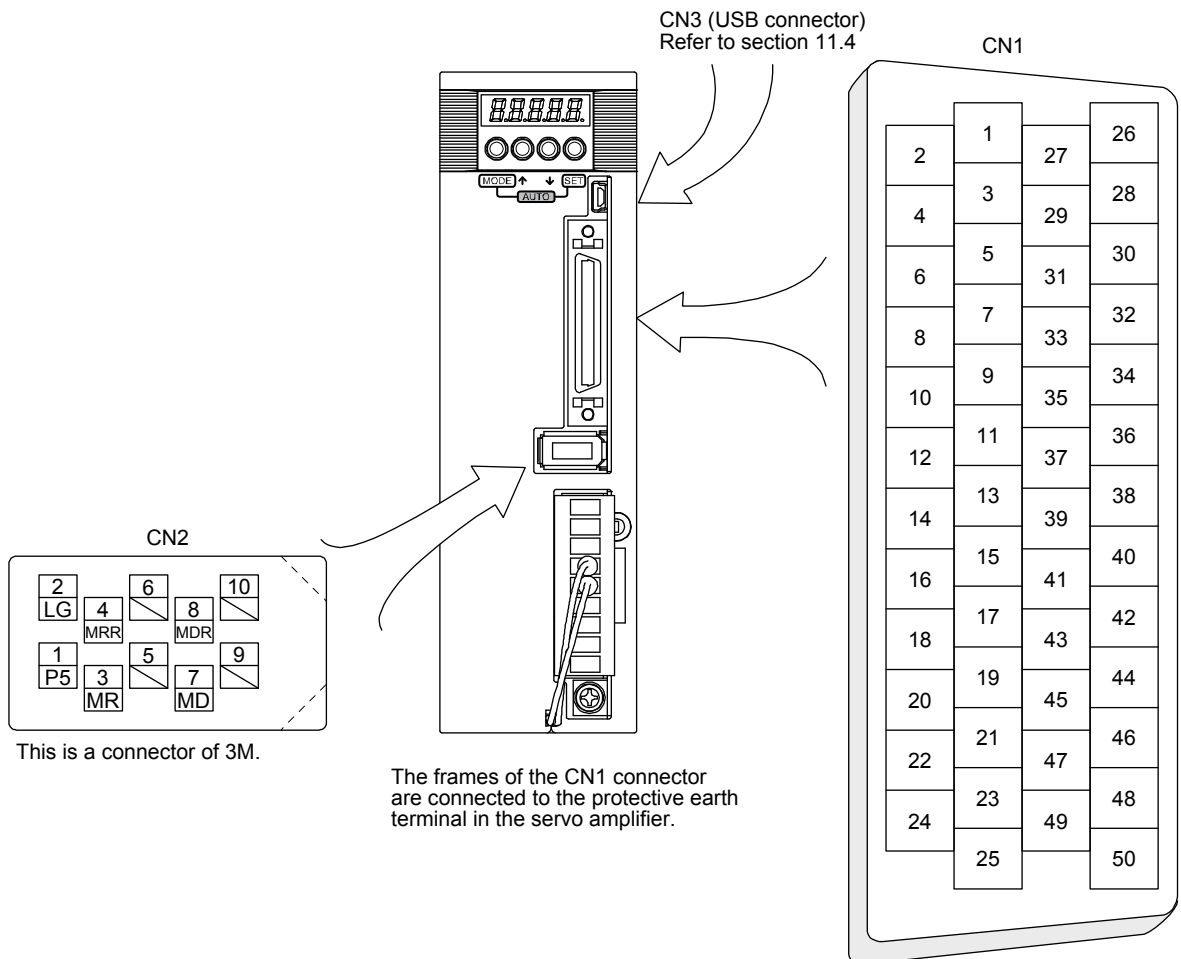
POINT
-------

- The pin assignment of the connectors is as viewed from the cable connector wiring section.
- For the CN1 connector, securely connect the external conductor of the shielded cable to the ground plate and fix it to the connector shell.



- PP (CN1-10 pin) and NP (CN1-35 pin) are mutually exclusive as well as PP2 (CN1-37 pin) and NP2 (CN1-38 pin). They cannot be used together.

The servo amplifier front view shown is that of the MR-JE-40A or less. Refer to chapter 9 DIMENSIONS for the appearances and connector layouts of the other servo amplifiers.



### 3. SIGNALS AND WIRING

The device assignment of CN1 connector pins changes depending on the control mode. For the pins which are given parameters in the related parameter column, their devices will be changed using those parameters.

Pin No.	(Note 1) I/O	(Note 2) I/O signals in control modes						Related parameter
		P	P/S	S	S/T	T	T/P	
1								
2	I		-/VC	VC	VC/VLA	VLA	VLA/-	
3		LG	LG	LG	LG	LG	LG	
4	O	LA	LA	LA	LA	LA	LA	
5	O	LAR	LAR	LAR	LAR	LAR	LAR	
6	O	LB	LB	LB	LB	LB	LB	
7	O	LBR	LBR	LBR	LBR	LBR	LBR	
8	O	LZ	LZ	LZ	LZ	LZ	LZ	
9	O	LZR	LZR	LZR	LZR	LZR	LZR	
10	I	PP	PP/-	(Note 5)	(Note 5)	(Note 5)	-/PP	PD43/PD44 (Note 4)
11	I	PG	PG/-				-/PG	
12		OPC	OPC/-				-/OPC	
13	O	SDP	SDP	SDP	SDP	SDP	SDP	
14	O	SDN	SDN	SDN	SDN	SDN	SDN	
15	I	SON	SON	SON	SON	SON	SON	PD03/PD04
16								
17								
18								
19	I	RES	RES/ST1	ST1	ST1/RS2	RS2	RS2/RES	PD11/PD12
20		DICOM	DICOM	DICOM	DICOM	DICOM	DICOM	
21		DICOM	DICOM	DICOM	DICOM	DICOM	DICOM	
22								
23	O	ZSP	ZSP	ZSP	ZSP	ZSP	ZSP	PD24
24	O	INP	INP/SA	SA	SA/-		-/INP	PD25
25								
26	O	MO1	MO1	MO1	MO1	MO1	MO1	PC14
27	I	TLA	(Note 3) TLA	(Note 3) TLA	(Note 3) TLA/TC	TC	(Note 3) TC/TLA	
28		LG	LG	LG	LG	LG	LG	
29	O	MO2	MO2	MO2	MO2	MO2	MO2	PC15
30		LG	LG	LG	LG	LG	LG	
31	I	TRE	TRE	TRE	TRE	TRE	TRE	
32								
33	O	OP	OP	OP	OP	OP	OP	
34		LG	LG	LG	LG	LG	LG	
35	I	NP	NP/-	(Note 5)	(Note 5)	(Note 5)	-/NP	PD43/PD44 (Note 4)
36	I	NG	NG/-				-/NG	
37 (Note 7)	I	PP2	PP2/-	(Note 6)	(Note 6)	(Note 6)	-/PP2	PD43/PD44 (Note 4)
38 (Note 7)	I	NP2	NP2/-	(Note 6)	(Note 6)	(Note 6)	-/NP2	PD45/PD46 (Note 4)
39	I	RDP	RDP	RDP	RDP	RDP	RDP	
40	I	RDN	RDN	RDN	RDN	RDN	RDN	
41	I	CR	CR/ST2	ST2	ST2/RS1	RS1	RS1/CR	PD13/PD14
42	I	EM2	EM2	EM2	EM2	EM2	EM2	
43	I	LSP	LSP	LSP	LSP/-		-/LSP	PD17/PD18
44	I	LSN	LSN	LSN	LSN/-		-/LSN	PD19/PD20
45								



### 3. SIGNALS AND WIRING

Pin No.	(Note 1) I/O	(Note 2) I/O signals in control modes						Related parameter
		P	P/S	S	S/T	T	T/P	
46		DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	
47		DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	DOCOM	
48	O	ALM	ALM	ALM	ALM	ALM	ALM	
49	O	RD	RD	RD	RD	RD	RD	PD28
50								

- Note
1. I: input signal, O: output signal
  2. P: position control mode, S: speed control mode, T: torque control mode, P/S: position/speed control switching mode, S/T: speed/torque control switching mode, T/P: torque/position control switching mode
  3. TLA will be available when TL (External torque limit selection) is enabled with [Pr. PD03], [Pr. PD11], [Pr. PD13], [Pr. PD17], and [Pr. PD19].
  4. This is available with servo amplifiers with software version B7 or later.
  5. This is available as an input device of sink interface. Input devices are not assigned by default. Assign the input devices with [Pr. PD43] to [Pr. PD46] as necessary. In addition, supply + of 24 DC V to the CN1-12 pin. This is available with servo amplifiers with software version B7 or later.
  6. This is available as an input device of source interface. Input devices are not assigned by default. Assign the input devices with [Pr. PD43] to [Pr. PD46] as necessary.
  7. These pins are available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later.

### 3. SIGNALS AND WIRING

#### 3.5 Signal (device) explanations

For the I/O interfaces (symbols in I/O division column in the table), refer to section 3.9.2. In the control mode field of the table

P: position control mode, S: speed control mode, T: torque control mode Torque control mode

○: devices used with initial setting status, △: devices used by setting [Pr. PA04] and [Pr. PD03] to [Pr. PD28]

The pin numbers in the connector pin No. column are those in the initial status.

#### (1) I/O device

##### (a) Input device

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode																
					P	S	T														
Forced stop 2	EM2	CN1-42	<p>Turn off EM2 (open between commons) to decelerate the servo motor to a stop with commands.</p> <p>Turn EM2 on (short between commons) in the forced stop state to reset that state.</p> <p>The following shows the setting of [Pr. PA04].</p> <table border="1" style="margin-left: 20px;"> <thead> <tr> <th rowspan="2">[Pr. PA04] setting</th> <th rowspan="2">EM2/EM1</th> <th colspan="2">Deceleration method</th> </tr> <tr> <th>EM2 or EM1 is off</th> <th>Alarm occurred</th> </tr> </thead> <tbody> <tr> <td>0 _ _ _</td> <td>EM1</td> <td>MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.</td> <td>MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.</td> </tr> <tr> <td>2 _ _ _</td> <td>EM2</td> <td>MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.</td> <td>MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.</td> </tr> </tbody> </table> <p>EM2 and EM1 are mutually exclusive. EM2 has the same function as EM1 in the torque control mode.</p>	[Pr. PA04] setting	EM2/EM1	Deceleration method		EM2 or EM1 is off	Alarm occurred	0 _ _ _	EM1	MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.	MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.	2 _ _ _	EM2	MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.	MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.	DI-1	○	○	○
[Pr. PA04] setting	EM2/EM1	Deceleration method																			
		EM2 or EM1 is off	Alarm occurred																		
0 _ _ _	EM1	MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.	MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.																		
2 _ _ _	EM2	MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.	MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.																		
Forced stop 1	EM1	(CN1-42)	<p>When using EM1, set [Pr. PA04] to "0 _ _ _" to enable EM1.</p> <p>When EM1 is turned off (open between commons), the base circuit shuts off, and the dynamic brake operates to decelerate the servo motor to a stop.</p> <p>The forced stop will be reset when EM1 is turned on (short between commons).</p>	DI-1	△	△	△														
Servo-on	SON	CN1-15	<p>Turn SON on to power on the base circuit and make the servo amplifier ready to operate. (servo-on status)</p> <p>Turn it off to shut off the base circuit and coast the servo motor.</p> <p>Set "_ _ _ 4" in [Pr. PD01] to switch this signal on (keep terminals connected) automatically in the servo amplifier.</p>	DI-1	○	○	○														
Reset	RES	CN1-19	<p>Turn on RES for more than 50 ms to reset the alarm.</p> <p>Some alarms cannot be deactivated by RES (Reset). Refer to section 8.1.</p> <p>Turning RES on in an alarm-free status shuts off the base circuit. The base circuit is not shut off when "_ _ 1 _" is set in [Pr. PD30].</p> <p>This device is not designed to make a stop. Do not turn it on during operation.</p>	DI-1	○	○	○														

### 3. SIGNALS AND WIRING

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode																																								
					P	S	T																																						
Forward rotation stroke end	LSP	CN1-43	To start operation, turn on LSP and LSN. Turn it off to bring the motor to a sudden stop and make it servo-locked. Setting [Pr. PD30] to "___ 1" will enable a slow stop.	DI-1	○	○																																							
Reverse rotation stroke end	LSN	CN1-44	<table border="1" style="margin-left: 20px;"> <thead> <tr> <th colspan="2">(Note) Input device</th> <th colspan="2">Operation</th> </tr> <tr> <th>LSP</th> <th>LSN</th> <th>CCW direction</th> <th>CW direction</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>1</td> <td>○</td> <td>○</td> </tr> <tr> <td>0</td> <td>1</td> <td></td> <td>○</td> </tr> <tr> <td>1</td> <td>0</td> <td>○</td> <td></td> </tr> <tr> <td>0</td> <td>0</td> <td></td> <td></td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p> <p>Set [Pr. PD01] as indicated below to switch on the signals (keep terminals connected) automatically in the servo amplifier.</p> <table border="1" style="margin-left: 20px;"> <thead> <tr> <th rowspan="2">[Pr. PD01]</th> <th colspan="2">Status</th> </tr> <tr> <th>LSP</th> <th>LSN</th> </tr> </thead> <tbody> <tr> <td>_ 4 _ _</td> <td>Automatic on</td> <td></td> </tr> <tr> <td>_ 8 _ _</td> <td></td> <td>Automatic on</td> </tr> <tr> <td>_ C _ _</td> <td>Automatic on</td> <td>Automatic on</td> </tr> </tbody> </table> <p>When LSP or LSN is turned off, [AL. 99 Stroke limit warning] occurs, and WNG (Warning) turns on. When using WNG, enable it by setting [Pr. PD24], [Pr. PD25] and [Pr. PD28].</p>	(Note) Input device		Operation		LSP	LSN	CCW direction	CW direction	1	1	○	○	0	1		○	1	0	○		0	0			[Pr. PD01]	Status		LSP	LSN	_ 4 _ _	Automatic on		_ 8 _ _		Automatic on	_ C _ _	Automatic on	Automatic on	DI-1			
(Note) Input device		Operation																																											
LSP	LSN	CCW direction	CW direction																																										
1	1	○	○																																										
0	1		○																																										
1	0	○																																											
0	0																																												
[Pr. PD01]	Status																																												
	LSP	LSN																																											
_ 4 _ _	Automatic on																																												
_ 8 _ _		Automatic on																																											
_ C _ _	Automatic on	Automatic on																																											
External torque limit selection	TL		Turning off TL will enable [Pr. PA11 Forward torque limit] and [Pr. PA12 Reverse torque limit], and turning on it will enable TLA (Analog torque limit). For details, refer to section 3.6.1 (5).	DI-1	△	△																																							
Internal torque limit selection	TL1		To select [Pr. PC35 Internal torque limit 2], enable TL1 with [Pr. PD03] to [Pr. PD20]. For details, refer to section 3.6.1 (5).	DI-1	△	△																																							
Forward rotation start	ST1		This is used to start the servo motor. The following shows the directions.	DI-1		△																																							
Reverse rotation start	ST2		<table border="1" style="margin-left: 20px;"> <thead> <tr> <th colspan="2">(Note) Input device</th> <th rowspan="2">Servo motor starting direction</th> </tr> <tr> <th>ST2</th> <th>ST1</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>Stop (servo-lock)</td> </tr> <tr> <td>0</td> <td>1</td> <td>CCW</td> </tr> <tr> <td>1</td> <td>0</td> <td>CW</td> </tr> <tr> <td>1</td> <td>1</td> <td>Stop (servo-lock)</td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p> <p>If both ST1 and ST2 are switched on or off during operation, the servo motor will be decelerated to a stop according to the [Pr. PC02] setting and servo-locked. When "___ 1" is set in [Pr. PC23], the servo motor is not servo-locked after deceleration to a stop.</p>	(Note) Input device		Servo motor starting direction	ST2	ST1	0	0	Stop (servo-lock)	0	1	CCW	1	0	CW	1	1	Stop (servo-lock)	DI-1																								
(Note) Input device		Servo motor starting direction																																											
ST2	ST1																																												
0	0	Stop (servo-lock)																																											
0	1	CCW																																											
1	0	CW																																											
1	1	Stop (servo-lock)																																											

### 3. SIGNALS AND WIRING

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode																																									
					P	S	T																																							
Forward rotation selection	RS1		Select a servo motor torque generation directions. The following shows the torque generation directions. <table border="1" style="margin: 10px auto;"> <thead> <tr> <th colspan="2">(Note) Input device</th> <th rowspan="2">Torque generation direction</th> </tr> <tr> <th>RS2</th> <th>RS1</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>Torque is not generated.</td> </tr> <tr> <td>0</td> <td>1</td> <td>Forward rotation in power running mode/reverse rotation in regenerative mode</td> </tr> <tr> <td>1</td> <td>0</td> <td>Reverse rotation in power running mode/forward rotation in regenerative mode</td> </tr> <tr> <td>1</td> <td>1</td> <td>Torque is not generated.</td> </tr> </tbody> </table> Note. 0: Off 1: On	(Note) Input device		Torque generation direction	RS2	RS1	0	0	Torque is not generated.	0	1	Forward rotation in power running mode/reverse rotation in regenerative mode	1	0	Reverse rotation in power running mode/forward rotation in regenerative mode	1	1	Torque is not generated.	DI-1			△																						
(Note) Input device				Torque generation direction																																										
RS2	RS1																																													
0	0	Torque is not generated.																																												
0	1	Forward rotation in power running mode/reverse rotation in regenerative mode																																												
1	0	Reverse rotation in power running mode/forward rotation in regenerative mode																																												
1	1	Torque is not generated.																																												
Reverse rotation selection	RS2																																													
Speed selection 1	SP1		1. For speed control mode Select the command speed for operation. <table border="1" style="margin: 10px auto;"> <thead> <tr> <th colspan="3">(Note) Input device</th> <th rowspan="2">Speed command</th> </tr> <tr> <th>SP3</th> <th>SP2</th> <th>SP1</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0</td> <td>VC (Analog speed command)</td> </tr> <tr> <td>0</td> <td>0</td> <td>1</td> <td>Pr. PC05 Internal speed command 1</td> </tr> <tr> <td>0</td> <td>1</td> <td>0</td> <td>Pr. PC06 Internal speed command 2</td> </tr> <tr> <td>0</td> <td>1</td> <td>1</td> <td>Pr. PC07 Internal speed command 3</td> </tr> <tr> <td>1</td> <td>0</td> <td>0</td> <td>Pr. PC08 Internal speed command 4</td> </tr> <tr> <td>1</td> <td>0</td> <td>1</td> <td>Pr. PC09 Internal speed command 5</td> </tr> <tr> <td>1</td> <td>1</td> <td>0</td> <td>Pr. PC10 Internal speed command 6</td> </tr> <tr> <td>1</td> <td>1</td> <td>1</td> <td>Pr. PC11 Internal speed command 7</td> </tr> </tbody> </table> Note. 0: Off 1: On	(Note) Input device			Speed command	SP3	SP2	SP1	0	0	0	VC (Analog speed command)	0	0	1	Pr. PC05 Internal speed command 1	0	1	0	Pr. PC06 Internal speed command 2	0	1	1	Pr. PC07 Internal speed command 3	1	0	0	Pr. PC08 Internal speed command 4	1	0	1	Pr. PC09 Internal speed command 5	1	1	0	Pr. PC10 Internal speed command 6	1	1	1	Pr. PC11 Internal speed command 7	DI-1		△	△
(Note) Input device				Speed command																																										
SP3	SP2				SP1																																									
0	0	0	VC (Analog speed command)																																											
0	0	1	Pr. PC05 Internal speed command 1																																											
0	1	0	Pr. PC06 Internal speed command 2																																											
0	1	1	Pr. PC07 Internal speed command 3																																											
1	0	0	Pr. PC08 Internal speed command 4																																											
1	0	1	Pr. PC09 Internal speed command 5																																											
1	1	0	Pr. PC10 Internal speed command 6																																											
1	1	1	Pr. PC11 Internal speed command 7																																											
Speed selection 2	SP2			DI-1		△	△																																							
Speed selection 3	SP3		2. For the torque control mode Select the limited speed for operation. <table border="1" style="margin: 10px auto;"> <thead> <tr> <th colspan="3">(Note) Input device</th> <th rowspan="2">Speed limit</th> </tr> <tr> <th>SP3</th> <th>SP2</th> <th>SP1</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>0</td> <td>VLA (Analog speed limit)</td> </tr> <tr> <td>0</td> <td>0</td> <td>1</td> <td>Pr. PC05 Internal speed limit 1</td> </tr> <tr> <td>0</td> <td>1</td> <td>0</td> <td>Pr. PC06 Internal speed limit 2</td> </tr> <tr> <td>0</td> <td>1</td> <td>1</td> <td>Pr. PC07 Internal speed limit 3</td> </tr> <tr> <td>1</td> <td>0</td> <td>0</td> <td>Pr. PC08 Internal speed limit 4</td> </tr> <tr> <td>1</td> <td>0</td> <td>1</td> <td>Pr. PC09 Internal speed limit 5</td> </tr> <tr> <td>1</td> <td>1</td> <td>0</td> <td>Pr. PC10 Internal speed limit 6</td> </tr> <tr> <td>1</td> <td>1</td> <td>1</td> <td>Pr. PC11 Internal speed limit 7</td> </tr> </tbody> </table> Note. 0: Off 1: On	(Note) Input device			Speed limit	SP3	SP2	SP1	0	0	0	VLA (Analog speed limit)	0	0	1	Pr. PC05 Internal speed limit 1	0	1	0	Pr. PC06 Internal speed limit 2	0	1	1	Pr. PC07 Internal speed limit 3	1	0	0	Pr. PC08 Internal speed limit 4	1	0	1	Pr. PC09 Internal speed limit 5	1	1	0	Pr. PC10 Internal speed limit 6	1	1	1	Pr. PC11 Internal speed limit 7	DI-1		△	△
(Note) Input device			Speed limit																																											
SP3	SP2	SP1																																												
0	0	0	VLA (Analog speed limit)																																											
0	0	1	Pr. PC05 Internal speed limit 1																																											
0	1	0	Pr. PC06 Internal speed limit 2																																											
0	1	1	Pr. PC07 Internal speed limit 3																																											
1	0	0	Pr. PC08 Internal speed limit 4																																											
1	0	1	Pr. PC09 Internal speed limit 5																																											
1	1	0	Pr. PC10 Internal speed limit 6																																											
1	1	1	Pr. PC11 Internal speed limit 7																																											

### 3. SIGNALS AND WIRING

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode																			
					P	S	T																	
Proportion control	PC		<p>Turn PC on to switch the speed amplifier from the proportional integral type to the proportional type.</p> <p>If the servo motor at a stop is rotated even one pulse due to any external factor, it generates torque to compensate for a position shift. When the servo motor shaft is to be locked mechanically after positioning completion (stop), switching on the PC (Proportion control) upon positioning completion will suppress the unnecessary torque generated to compensate for a position shift.</p> <p>When the shaft is to be locked for a long time, switch on the PC (Proportion control) and TL (External torque limit selection) at the same time to make the torque less than the rated by TLA (Analog torque limit). Do not use PC (Proportional control) in the torque control. When PC (Proportional control) is used in the torque control, operation may be performed at a speed exceeding the speed limit value.</p>	DI-1	△	△																		
Clear	CR	CN1-41	<p>Turn CR on to clear the position control counter droop pulses on its leading edge. The pulse width should be 10 ms or longer.</p> <p>The delay amount set in [Pr. PB03 Position command acceleration/deceleration time constant] is also cleared. When "___1" is set to [Pr. PD32], the pulses are always cleared while CR is on.</p>	DI-1	○																			
Electronic gear selection 1	CM1		<p>The combination of CM1 and CM2 enables you to select four different electronic gear numerators set in the parameters.</p> <table border="1" style="margin: 10px auto;"> <thead> <tr> <th colspan="2">(Note) Input device</th> <th rowspan="2">Electronic gear numerator</th> </tr> <tr> <th>CM2</th> <th>CM1</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>0</td> <td>Pr. PA06</td> </tr> <tr> <td>0</td> <td>1</td> <td>Pr. PC32</td> </tr> <tr> <td>1</td> <td>0</td> <td>Pr. PC33</td> </tr> <tr> <td>1</td> <td>1</td> <td>Pr. PC34</td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p>	(Note) Input device		Electronic gear numerator	CM2	CM1	0	0	Pr. PA06	0	1	Pr. PC32	1	0	Pr. PC33	1	1	Pr. PC34	DI-1	△		
(Note) Input device		Electronic gear numerator																						
CM2	CM1																							
0	0	Pr. PA06																						
0	1	Pr. PC32																						
1	0	Pr. PC33																						
1	1	Pr. PC34																						
Electronic gear selection 2	CM2			DI-1	△																			
Gain switching	CDP		Turn on CDP to use the values of [Pr. PB29] to [Pr. PB36] and [Pr. PB56] to [Pr. PB60] as the load to motor inertia ratio and gain values.	DI-1	△	△	△																	

### 3. SIGNALS AND WIRING

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode																					
					P	S	T																			
Control switching	LOP		<p>«Position/speed control switching mode» This is used to select the control mode in the position/speed control switching mode.</p> <table border="1"> <thead> <tr> <th>(Note) LOP</th> <th>Control mode</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>Position</td> </tr> <tr> <td>1</td> <td>Speed</td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p> <p>«Speed/torque control switch mode» This is used to select the control mode in the speed/torque control switching mode.</p> <table border="1"> <thead> <tr> <th>(Note) LOP</th> <th>Control mode</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>Speed</td> </tr> <tr> <td>1</td> <td>Torque</td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p> <p>«Torque/position control switch mode» This is used to select the control mode in the torque/position control switching mode.</p> <table border="1"> <thead> <tr> <th>(Note) LOP</th> <th>Control mode</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>Torque</td> </tr> <tr> <td>1</td> <td>Position</td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p>	(Note) LOP	Control mode	0	Position	1	Speed	(Note) LOP	Control mode	0	Speed	1	Torque	(Note) LOP	Control mode	0	Torque	1	Position	DI-1				Refer to Function and application.
(Note) LOP	Control mode																									
0	Position																									
1	Speed																									
(Note) LOP	Control mode																									
0	Speed																									
1	Torque																									
(Note) LOP	Control mode																									
0	Torque																									
1	Position																									
Second acceleration/ deceleration selection	STAB2		<p>The device allows selection of the acceleration/deceleration time constants at servo motor rotation in the speed control mode or torque control mode. The s-pattern acceleration/deceleration time constant is always uniform.</p> <table border="1"> <thead> <tr> <th>(Note) STAB2</th> <th>Acceleration/deceleration time constant</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>Pr. PC01 Acceleration time constant Pr. PC02 Deceleration time constant</td> </tr> <tr> <td>1</td> <td>Pr. PC30 Acceleration time constant 2 Pr. PC31 Deceleration time constant 2</td> </tr> </tbody> </table> <p>Note. 0: Off 1: On</p>	(Note) STAB2	Acceleration/deceleration time constant	0	Pr. PC01 Acceleration time constant Pr. PC02 Deceleration time constant	1	Pr. PC30 Acceleration time constant 2 Pr. PC31 Deceleration time constant 2	DI-1		△	△													
(Note) STAB2	Acceleration/deceleration time constant																									
0	Pr. PC01 Acceleration time constant Pr. PC02 Deceleration time constant																									
1	Pr. PC30 Acceleration time constant 2 Pr. PC31 Deceleration time constant 2																									

### 3. SIGNALS AND WIRING

#### (b) Output device

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode		
					P	S	T
Malfunction	ALM	CN1-48	When an alarm occurs, ALM will turn off. When an alarm does not occur, ALM will turn on after 2.5 s to 3.5 s after power-on. When [Pr. PD34] is "_ _ 1 _", an alarming or warning will turn off ALM.	DO-1	○	○	○
Ready	RD	CN1-49	Enabling servo-on to make the servo amplifier ready to operate will turn on RD.	DO-1	○	○	○
In-position	INP	CN1-24	When the number of droop pulses is in the preset in-position range, INP will turn on. The in-position range can be changed using [Pr. PA10]. When the in-position range is increased, INP may be on during low-speed rotation. INP turns on when servo-on turns on.	DO-1	○	△	△
Speed reached	SA		When the servo motor speed reaches the following range, SA will turn on. Set speed $\pm ((\text{Set speed} \times 0.05) + 20)$ r/min When the preset speed is 20 r/min or less, SA always turns on. SA does not turn on even when the SON (Servo-on) is turned off or the servo motor speed by the external force reaches the preset speed while both ST1 (Forward rotation start) and ST2 (reverse rotation start) are off.	DO-1	○	△	△
Limiting speed	VLC		VLC turns on when speed reaches a value limited with any of [Pr. PC05 Internal speed limit 1] to [Pr. PC11 Internal speed limit 7] or VLA (Analog speed limit). This turns off when SON (Servo-on) turns off.	DO-1	○	△	△
Limiting torque	TLC		TLC turns on when a generated torque reaches a value set with any of [Pr. PA11 Forward torque limit], [Pr. PA12 Reverse torque limit], or TLA (Analog torque limit).	DO-1	△	△	△
Zero speed detection	ZSP	CN1-23	ZSP turns on when the servo motor speed is zero speed (50 r/min) or less. Zero speed can be changed with [Pr. PC17].  <div style="display: flex; align-items: flex-start;"> <div style="margin-right: 20px;"> <p>Forward rotation direction ↑</p> <p>OFF level 70 r/min</p> <p>ON level 50 r/min</p> </div> <div style="margin-right: 20px;"> <p>Servo motor speed</p> <p>0 r/min</p> </div> <div style="margin-right: 20px;"> <p>Reverse rotation direction ↓</p> <p>ON level -50 r/min</p> <p>OFF level -70 r/min</p> </div> <div style="margin-right: 20px;"> <p>ZSP (Zero speed detection)</p> <p>ON</p> <p>OFF</p> </div> </div> <p>ZSP will turn on when the servo motor is decelerated to 50 r/min (at 1), and will turn off when the servo motor is accelerated to 70 r/min again (at 2)). ZSP will turn on when the servo motor is decelerated again to 50 r/min (at 3)), and will turn off when the servo motor speed has reached -70 r/min (at 4)). The range from the point when the servo motor speed has reached on level, and ZSP turns on, to the point when it is accelerated again and has reached off level is called hysteresis width. Hysteresis width is 20 r/min for this servo amplifier.</p>	DO-1	○	○	○
Electromagnetic brake interlock	MBR		When using the device, set operation delay time of the electromagnetic brake in [Pr. PC16]. When a servo-off status or alarm occurs, MBR will turn off.	DO-1	△	△	△
Warning	WNG		When warning has occurred, WNG turns on. When a warning is not occurring, turning on the power will turn off WNG after 2.5 s to 3.5 s.	DO-1	△	△	△

### 3. SIGNALS AND WIRING

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode		
					P	S	T
Alarm code	ACD0	(CN1-24)	To use these signals, set " __ _ 1" in [Pr. PD34]. This signal is outputted when an alarm occurs.	DO-1	△	△	△
	ACD1	(CN1-23)	When an alarm is not occurring, respective ordinary signals are outputted. For details of the alarm codes, refer to chapter 8.				
	ACD2	(CN1-49)	When you select alarm code output while MBR or ALM is selected for CN1-23, CN1-24, or CN1-49 pin, [AL. 37 Parameter error] will occur.				
Variable gain selection	CDPS		CDPS turns on during gain switching.	DO-1	△	△	△
During tough drive	MTTR		When a tough drive is enabled in [Pr. PA20], activating the instantaneous power failure tough drive will turn on MTTR.	DO-1	△	△	△

#### (2) Input signal

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode		
					P	S	T
Analog torque limit	TLA	CN1-27	To use the signal, enable TL (External torque limit selection) with [Pr. PD03] to [Pr. PD20]. When TLA is enabled, torque is limited in the full servo motor output torque range. Apply 0 V to +10 V DC between TLA and LG. Connect the positive terminal of the power supply to TLA. The maximum torque is generated at +10 V. (Refer to section 3.6.1 (5).) If a value equal to or larger than the maximum torque is inputted to TLA, the value is clamped at the maximum torque. Resolution: 10 bits	Analog input	△	△	
Analog torque command	TC		This is used to control torque in the full servo motor output torque range. Apply 0 V to ±8 V DC between TC and LG. The maximum torque is generated at ±8 V. (Refer to section 3.6.3 (1).) The speed at ±8 V can be changed with [Pr. PC13]. If a value equal to or larger than the maximum torque is inputted to TC, the value is clamped at the maximum torque.		Analog input		
Analog speed command	VC	CN1-2	Apply 0 V to ±10 V DC between VC and LG. Speed set in [Pr. PC12] is provided at ±10 V. (Refer to section 3.6.2 (1).) If a value equal to or larger than the permissible speed is inputted to VC, the value is clamped at the permissible speed. Resolution: 14 bits or equivalent	Analog input		○	
Analog speed limit	VLA		Apply 0 V to ±10 V DC between VLA and LG. Speed set in [Pr. PC12] is provided at ±10 V. (Refer to section 3.6.3 (3).) If a limited value equal to or larger than the permissible speed is inputted to VLA, the value is clamped at the permissible speed.		Analog input		
Forward rotation pulse train Reverse rotation pulse train	PP NP PP2 NP2 PG NG	CN1-10 CN1-35 CN1-37 CN1-38 CN1-11 CN1-36	This is used to enter a command pulse train. The command input pulse train form, pulse train logic, and command input pulse train filter are changed in [Pr. PA13]. For open-collector type, set [Pr. PA13] to "_ 3 _". For differential receiver type, set [Pr. PA13] depending on the maximum input frequency. 1) For open-collector type (sink input interface) The maximum input frequency is 200 kpulses/s. For A-phase/B-phase pulse train, 200 kpulses/s will be the frequency after multiplication by four. a) Sink input interface Input the forward rotation pulse train between PP and DOCOM. Input the reverse rotation pulse train between NP and DOCOM. b) Source input interface Input the forward rotation pulse train between PP2 and PG. Input the reverse rotation pulse train between NP2 and NG. 2) For differential receiver type The maximum input frequency is 4 Mpulses/s. For A-phase/B-phase pulse train, 4 Mpulses/s will be the frequency after multiplication by four. Input the forward rotation pulse train between PG and PP. Input the reverse rotation pulse train between NG and NP.	DI-2	○		



### 3. SIGNALS AND WIRING

#### (3) Output signal

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode		
					P	S	T
Encoder A-phase pulse (differential line driver)	LA	CN1-4	These devices output pulses of encoder output pulse set in [Pr. PA15] in the differential line driver type. In CCW rotation of the servo motor, the encoder B-phase pulse lags the encoder A-phase pulse by a phase angle of $\pi/2$ . The relation between rotation direction and phase difference of the A-phase and B-phase pulses can be changed with [Pr. PC19].	DO-2	○	○	○
	LAR	CN1-5					
Encoder B-phase pulse (differential line driver)	LB	CN1-6					
	LBR	CN1-7					
Encoder Z-phase pulse (differential line driver)	LZ	CN1-8	The encoder zero-point signal is outputted in the differential line driver type. One pulse is outputted per servo motor revolution. This turns on when the zero-point position is reached. (negative logic) The minimum pulse width is about 400 $\mu$ s. For home position return using this pulse, set the creep speed to 100 r/min or less.	DO-2	○	○	○
	LZR	CN1-9					
Encoder Z-phase pulse (open-collector)	OP	CN1-33	The encoder zero-point signal is outputted in the open-collector type.	DO-2	○	○	○
Analog monitor 1	MO1	CN1-26	This is used to output the data set in [Pr. PC14] to between MO1 and LG in terms of voltage. Output voltage: $\pm 10$ V Resolution: 10 bits or equivalent	Analog output	○	○	○
Analog monitor 2	MO2	CN1-29	This signal outputs the data set in [Pr. PC15] to between MO2 and LG in terms of voltage. Output voltage: $\pm 10$ V Resolution: 10 bits or equivalent	Analog output	○	○	○

#### (4) Communication

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode		
					P	S	T
RS-422/RS-485 I/F	SDP SDN RDP RDN TRE	CN1-13 CN1-14 CN1-39 CN1-40 CN1-31	These are terminals for RS-422/RS-485 communication.		○	○	○

### 3. SIGNALS AND WIRING

#### (5) Power supply

Device	Symbol	Connector pin No.	Function and application	I/O division	Control mode		
					P	S	T
Digital I/F power supply input	DICOM	CN1-20 CN1-21	Input 24 V DC (24 V DC $\pm$ 10% 300 mA) for I/O interface. The power supply capacity changes depending on the number of I/O interface points to be used. For sink interface, connect + of 24 V DC external power supply. For source interface, connect - of 24 V DC external power supply.	/	○	○	○
Open-collector sink interface power supply input	OPC	CN1-12	When inputting a pulse train in the open-collector type with sink interface, supply this terminal with the positive (+) power of 24 V DC.	/	○	/	/
Digital I/F common	DOCOM	CN1-46 CN1-47	Common terminal of input signal such as EM2 of the servo amplifier. This is separated from LG. For sink interface, connect - of 24 V DC external power supply. For source interface, connect + of 24 V DC external power supply.	/	○	○	○
Control common	LG	CN1-3 CN1-28 CN1-30 CN1-34	This is a common terminal for TLA, TC, VC, VLA, OP, MO1, and MO2. Pins are connected internally.	/	○	○	○
Shield	SD	Plate	Connect the external conductor of the shielded wire.	/	○	○	○

### 3. SIGNALS AND WIRING

#### 3.6 Detailed explanation of signals

##### 3.6.1 Position control mode

**POINT**

- Adjust the logic of a positioning module and command pulse as follows.
  - MELSEC iQ-R series/MELSEC-Q series/MELSEC-L series positioning module

Signal type	Command pulse logic setting	
	Positioning module Pr. 23 setting	MR-JE-_A servo amplifier [Pr. PA13] setting
Open-collector type	Positive logic	Positive logic ( _ _ 0 _ )
	Negative logic	Negative logic ( _ _ 1 _ )
Differential line driver type	Positive logic (Note)	Negative logic ( _ _ 1 _ )
	Negative logic (Note)	Positive logic ( _ _ 0 _ )

Note. For MELSEC iQ-R series/MELSEC-Q series/MELSEC-L series, the logic means N-side waveform. Therefore, reverse the input pulse logic of the servo amplifier.

- MELSEC-F series positioning module

Signal type	Command pulse logic setting	
	Positioning module (fixed)	MR-JE-_A servo amplifier [Pr. PA13] setting
Open-collector type Differential line driver type	Negative logic	Negative logic ( _ _ 1 _ )

#### (1) Pulse train input

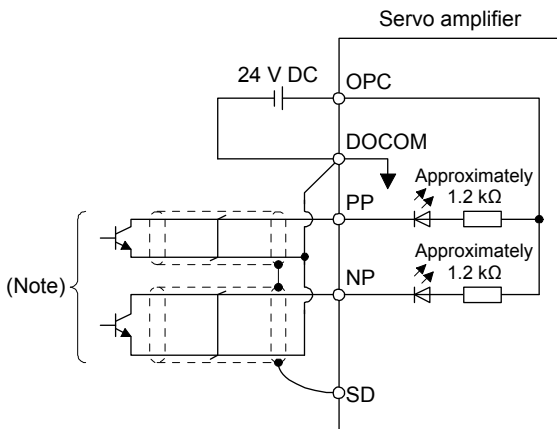
##### (a) Input pulse waveform selection

You can input command pulses in any of three different forms, and can choose positive or negative logic. Set the command pulse train form in [Pr. PA13]. Refer to section 5.2.1 for details.

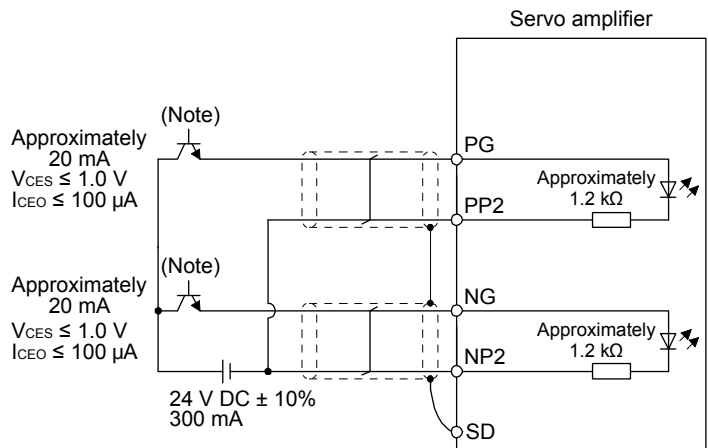
##### (b) Connection and waveform

###### 1) Open-collector type

Connect as follows.



For sink input interface



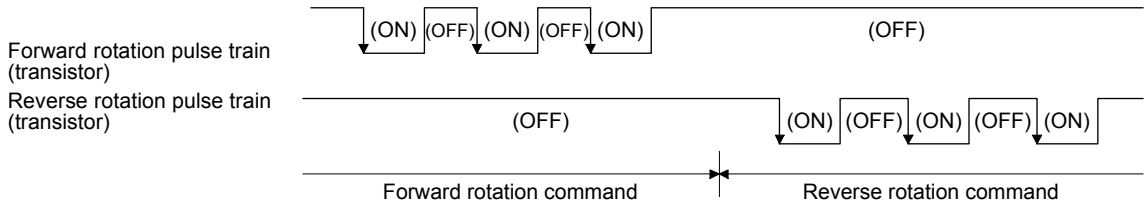
For source input interface

Note. Pulse train input interface is comprised of a photocopier.

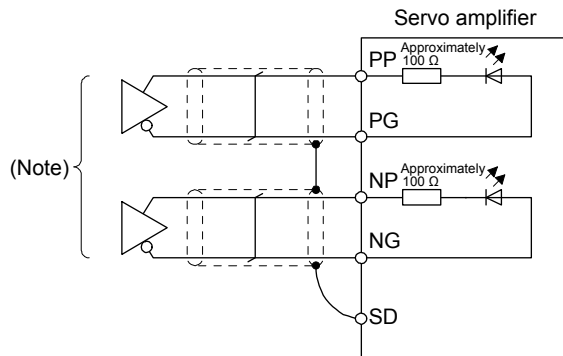
If a resistor is connected to the pulse train signal line, it may malfunction due to reduction in current.

### 3. SIGNALS AND WIRING

The following section explains about the case where the negative logic and the forward/reverse rotation pulse trains are set to " \_\_ 1 0" in [Pr. PA13].

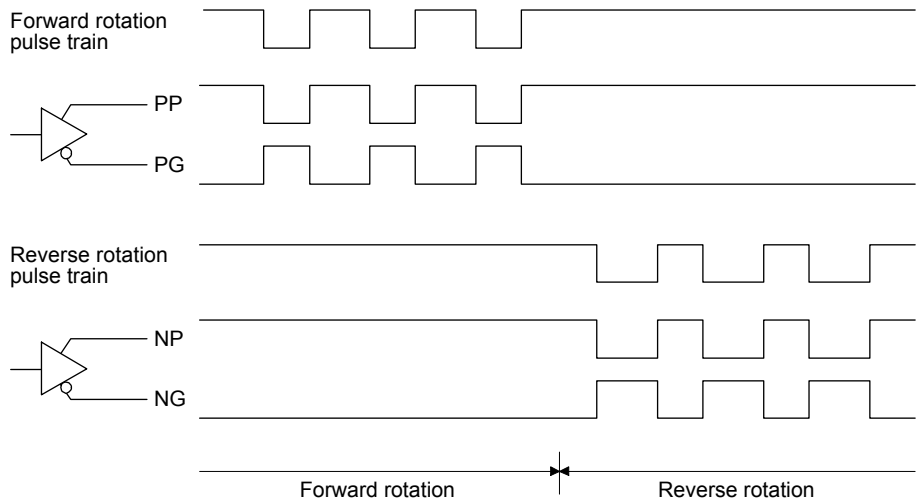


- 2) Differential line driver type  
Connect as follows.



Note. Pulse train input interface is comprised of a photocoupler.  
If a resistor is connected to the pulse train signal line, it may malfunction due to reduction in current.

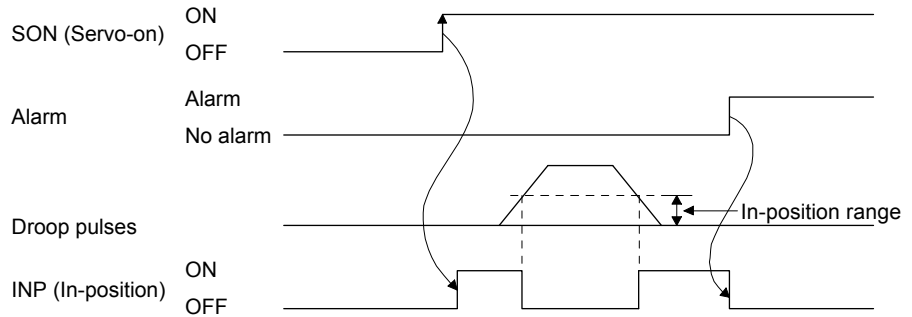
The following example shows that an input waveform has been set to the negative logic and forward/reverse rotation pulse trains by setting " \_\_ 1 0" in [Pr. PA13]. The waveforms of PP, PG, NP, and NG are based on LG.



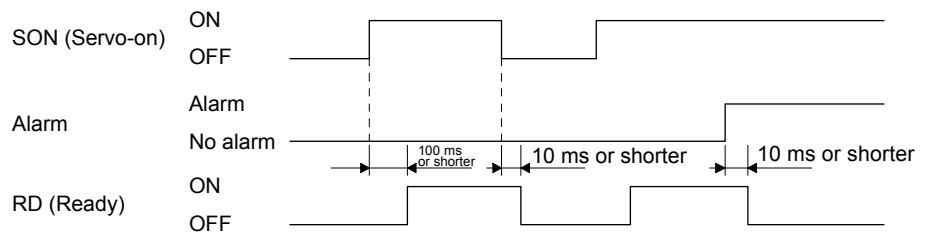
### 3. SIGNALS AND WIRING

#### (2) INP (In-position)

INP turns on when the number of droop pulses in the deviation counter falls within the preset in-position range ([Pr. PA10]). INP may turn on continuously during a low-speed operation with a large value set as the in-position range.



#### (3) RD (Ready)



#### (4) Electronic gear switching

The combination of CM1 and CM2 enables you to select four different electronic gear numerators set in the parameters.


As soon as CM1/CM2 is turned on or off, the numerator of the electronic gear changes. Therefore, if a shock occurs at switching, use the position smoothing ([Pr. PB03]) to relieve the shock.

(Note) Input device		Electronic gear numerator
CM2	CM1	
0	0	Pr. PA06
0	1	Pr. PC32
1	0	Pr. PC33
1	1	Pr. PC34

Note. 0: Off  
1: On

### 3. SIGNALS AND WIRING

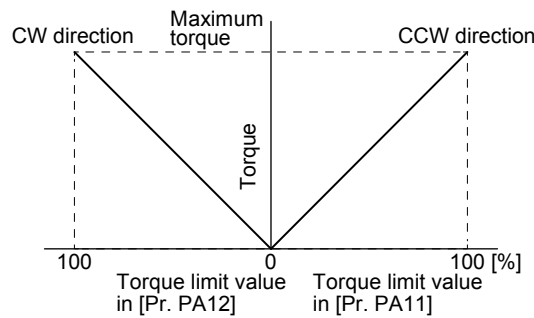
#### (5) Torque limit


**CAUTION**

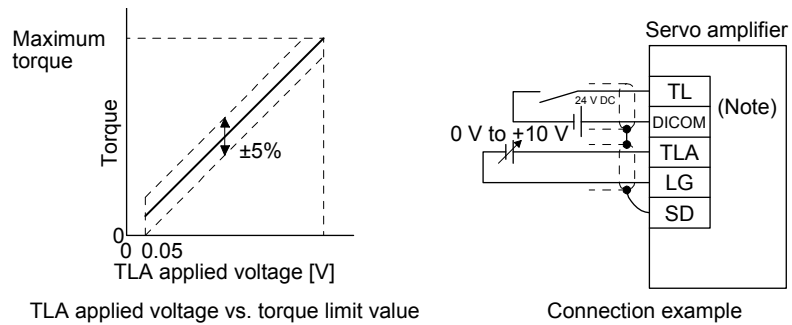
- If the torque limit is canceled during servo-lock, the servo motor may suddenly rotate according to position deviation in respect to the command position.
- When using the torque limit, check that [Pr. PB06 Load to motor inertia ratio] is set properly. Improper settings may cause an unexpected operation such as an overshoot.

#### (a) Torque limit and torque

By setting [Pr. PA11 Forward rotation torque limit] or [Pr. PA12 Reverse rotation torque limit], torque is always limited to the maximum value during operation. A relation between the limit value and servo motor torque is as follows.



A relation between the applied voltage of TLA (Analog torque limit) and the torque limit value of the servo motor is as follows. Torque limit values will vary about 5% relative to the voltage depending on products. At the voltage of less than 0.05 V, torque may vary as it may not be limited sufficiently. Therefore, use this function at the voltage of 0.05 V or more.



Note. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.

#### (b) Torque limit value selection

The following shows how to select a torque limit using TL (External torque limit selection) from [Pr. PA11 Forward torque limit] or [Pr. PA12 Reverse torque limit] and TLA (Analog torque limit). When TL1 (Internal torque limit selection) is enabled with [Pr. PD03] to [Pr. PD22], select [Pr. PC35 Internal torque limit 2]. However, if [Pr. PA11] and [Pr. PA12] value is less than the limit value selected by TL/TL1, [Pr. PA11] and [Pr. PA12] value will be enabled.

### 3. SIGNALS AND WIRING

(Note) Input device		Limit value status	Enabled torque limit value	
TL1	TL		CCW power running/CW regeneration	CW power running/CCW regeneration
0	0		Pr. PA11	Pr. PA12
0	1	TLA > Pr. PA11 Pr. PA12	Pr. PA11	Pr. PA12
		TLA < Pr. PA11 Pr. PA12	TLA	TLA
1	0	Pr. PC35 > Pr. PA11 Pr. PA12	Pr. PA11	Pr. PA12
		Pr. PC35 < Pr. PA11 Pr. PA12	Pr. PC35	Pr. PC35
1	1	TLA > Pr. PC35	Pr. PC35	Pr. PC35
		TLA < Pr. PC35	TLA	TLA

Note. 0: Off

1: On

(c) TLC (Limiting torque)

TLC turns on when the servo motor torque reaches the torque limited using the forward rotation torque limit, reverse rotation torque limit or analog torque limit.

### 3. SIGNALS AND WIRING

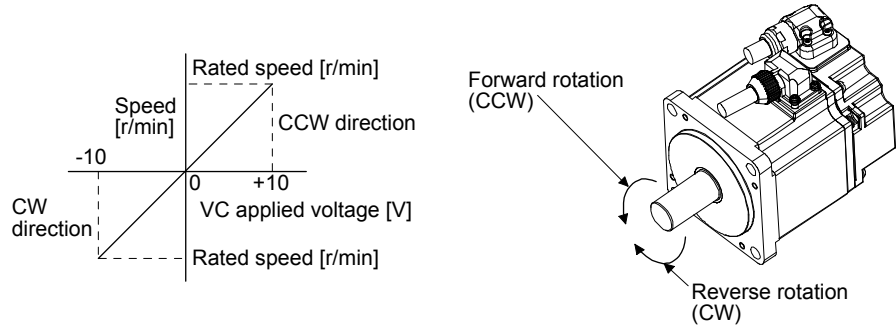
#### 3.6.2 Speed control mode

##### (1) Speed setting

###### (a) Speed command and speed

The servo motor is run at the speeds set in the parameters or at the speed set in the applied voltage of VC (Analog speed command). A relation between VC (Analog speed command) applied voltage and the servo motor speed is as follows.

Rated speed is achieved at  $\pm 10$  V with initial setting. The speed at  $\pm 10$  V can be changed with [Pr. PC12].



The following table indicates the rotation direction according to ST1 (Forward rotation start) and ST2 (Reverse rotation start) combination.

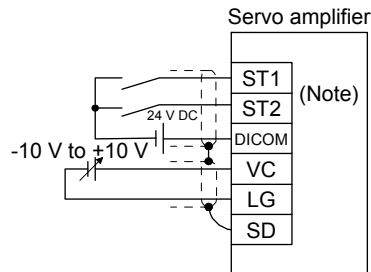
(Note 1) Input device		(Note 2) Rotation direction			
ST2	ST1	VC (Analog speed command)			Internal speed command
		Polarity: +	0 V	Polarity: -	
0	0	Stop (servo-lock)	Stop (servo-lock)	Stop (servo-lock)	Stop (servo-lock)
0	1	CCW	Stop (no servo-lock)	CW	CCW
1	0	CW		CCW	CW
1	1	Stop (servo-lock)	Stop (servo-lock)	Stop (servo-lock)	Stop (servo-lock)

Note 1. 0: Off

1: On

2. If the torque limit is canceled during servo-lock, the servo motor may suddenly rotate according to position deviation in respect to the command position.

Normally, connect as follows.



Note. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.



### 3. SIGNALS AND WIRING

(b) Speed command value selection

To select VC (Analog speed command) and a speed command value of internal speed commands 1 to 7, enable SP1 (Speed selection 1), SP2 (Speed selection 2), and SP3 (Speed selection 3) with [Pr. PD03] to [Pr. PD20].

(Note) Input device			Speed command value
SP3	SP2	SP1	
0	0	0	VC (Analog speed command)
0	0	1	Pr. PC05 Internal speed command 1
0	1	0	Pr. PC06 Internal speed command 2
0	1	1	Pr. PC07 Internal speed command 3
1	0	0	Pr. PC08 Internal speed command 4
1	0	1	Pr. PC09 Internal speed command 5
1	1	0	Pr. PC10 Internal speed command 6
1	1	1	Pr. PC11 Internal speed command 7

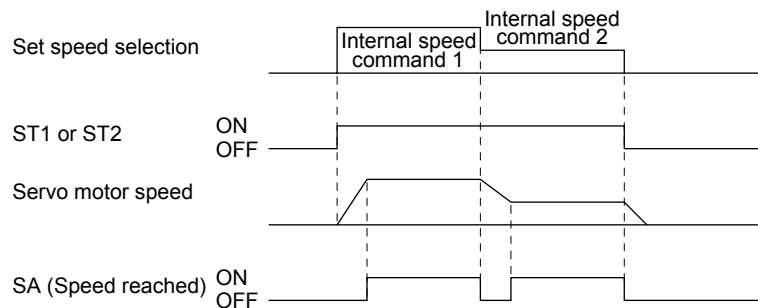
Note. 0: Off  
1: On

You can change the speed during rotation. To accelerate/decelerate, set acceleration/deceleration time constant in [Pr. PC01] or [Pr. PC02].

When the internal speed commands are used to command a speed, the speed does not vary with the ambient temperature.

(2) SA (Speed reached)

SA turns on when the servo motor speed has nearly reached the speed set to the internal speed command or analog speed command.



(3) Torque limit

As in section 3.6.1 (5)

### 3. SIGNALS AND WIRING

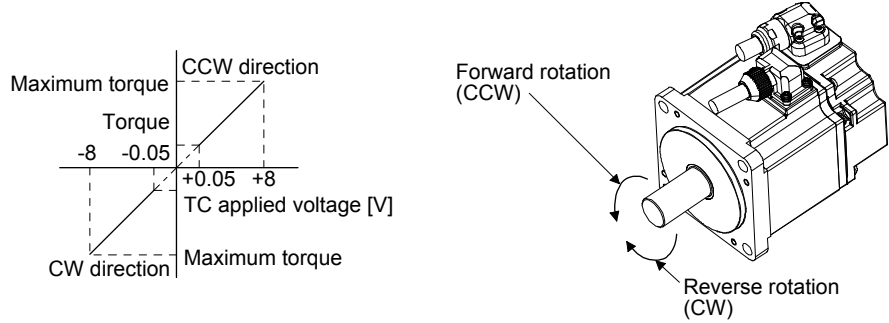
#### 3.6.3 Torque control mode

##### (1) Torque limit

##### (a) Torque command and torque

The following shows a relation between the applied voltage of TC (Analog torque command) and the torque by the servo motor.

The maximum torque is generated at  $\pm 8$  V. The speed at  $\pm 8$  V can be changed with [Pr. PC13].



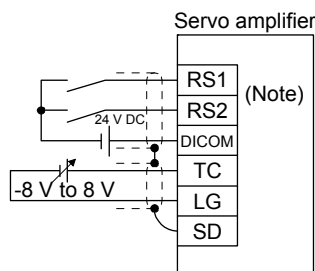
Generated torque command values will vary about 5% relative to the voltage depending on products. The torque may vary if the voltage is low (-0.05 V to 0.05 V) and the actual speed is close to the limit value. In such a case, increase the speed limit value.

The following table indicates the torque generation directions determined by RS1 (Forward rotation selection) and RS2 (Reverse rotation selection) when TC (Analog torque command) is used.

(Note) Input device		Rotation direction		
RS2	RS1	TC (Analog torque command)		
		Polarity: +	0 V	Polarity: -
0	0	Torque is not generated.	Torque is not generated.	Torque is not generated.
0	1	CCW (Forward rotation in power running mode/reverse rotation in regenerative mode)		CW (Reverse rotation in power running mode/forward rotation in regenerative mode)
		1		
1	1	Torque is not generated.		Torque is not generated.

Note. 0: Off  
1: On

Normally, connect as follows.

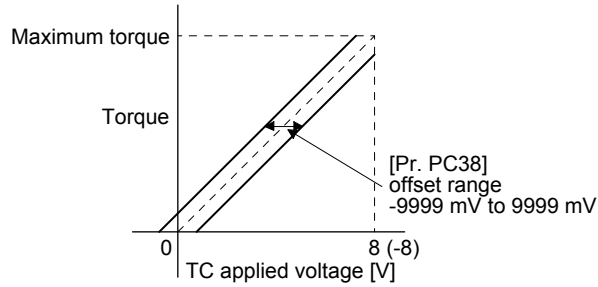


Note. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.

### 3. SIGNALS AND WIRING

(b) Analog torque command offset

Using [Pr. PC38], the offset voltage of -9999 mV to 9999 mV can be added to the TC applied voltage as follows.



(2) Torque limit

By setting [Pr. PA11 Forward rotation torque limit] or [Pr. PA12 Reverse rotation torque limit], torque is always limited to the maximum value during operation. A relation between limit value and servo motor torque is as in section 3.6.1 (5).

Note that TLA (Analog torque limit) is unavailable.

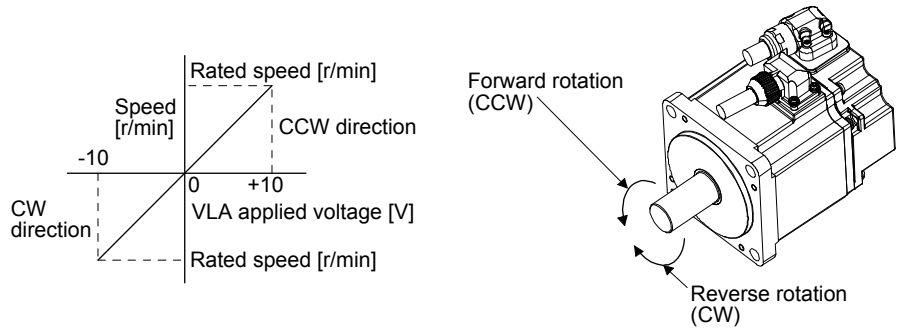
(3) Speed limit

(a) Speed limit value and speed

The speed is limited to the values set with [Pr. PC05 Internal speed limit 0] to [Pr. PC11 Internal speed limit 7] or the value set in the applied voltage of VLA (Analog speed limit). A relation between VLA (Analog speed limit) applied voltage and the servo motor speed is as follows.

When the servo motor speed reaches the speed limit value, torque control may become unstable.

Make the set value more than 100 r/min greater than the desired speed limit value.



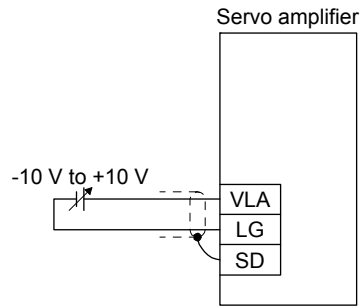
The following table indicates the limit direction according to RS1 (Forward rotation selection) and RS2 (Reverse rotation selection) combination.

(Note) Input device		Speed limit direction		
RS1	RS2	VLA (Analog speed limit)		Internal speed command
		Polarity: +	Polarity: -	
1	0	CCW	CW	CCW
0	1	CW	CCW	CW

Note. 0: Off  
1: On

### 3. SIGNALS AND WIRING

Normally, connect as follows.



(b) Speed limit value selection

To select VLA (Analog speed limit) and a speed limit value of internal speed limit 1 to 7, enable SP1 (Speed selection 1), SP2 (Speed selection 2), and SP3 (Speed selection 3) with [Pr. PD03] to [Pr. PD20].

(Note) Input device			Speed limit
SP3	SP2	SP1	
0	0	0	VLA (Analog speed limit)
0	0	1	Pr. PC05 Internal speed limit 1
0	1	0	Pr. PC06 Internal speed limit 2
0	1	1	Pr. PC07 Internal speed limit 3
1	0	0	Pr. PC08 Internal speed limit 4
1	0	1	Pr. PC09 Internal speed limit 5
1	1	0	Pr. PC10 Internal speed limit 6
1	1	1	Pr. PC11 Internal speed limit 7

Note. 0: Off  
1: On

When the internal speed limits 1 to 7 are used to limit a speed, the speed does not vary with the ambient temperature.

(c) VLC (Limiting speed)

VLC turns on when the servo motor speed reaches a speed limited with internal speed limits 1 to 7 or analog speed limit.

### 3. SIGNALS AND WIRING

#### 3.6.4 Position/speed control switching mode

Set " \_\_\_ 1" in [Pr. PA01] to switch to the position/speed control switching mode.

##### (1) LOP (control switching)

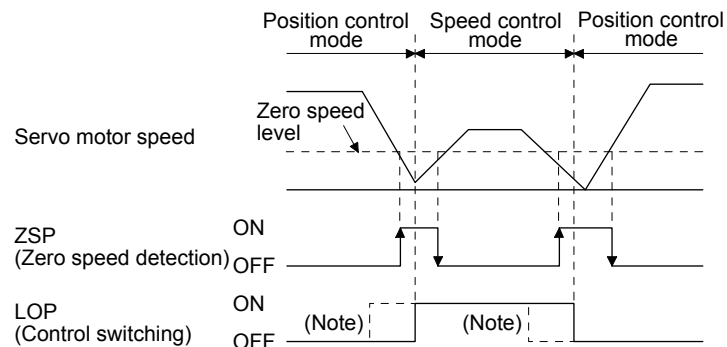
Use LOP (Control switching) to switch between the position control mode and the speed control mode with an external contact. The following shows a relation between LOP and control modes.

(Note) LOP	Control mode
0	Position control mode
1	Speed control mode

Note. 0: Off  
1: On

You can switch the control mode in the zero speed status. To ensure safety, switch modes after the servo motor has stopped. When position control mode is switched to speed control mode, droop pulses will be reset.

If LOP is switched on/off at the speed higher than the zero speed, the control mode cannot be changed regardless of the speed. The following shows a switching timing chart.



Note. When ZSP is not turned on, the control mode is not switched even if LOP is turned on/off. After LOP is turned on/off, even if ZSP is turned on, the control mode is not switched.

##### (2) Torque limit in position control mode

As in section 3.6.1 (5)

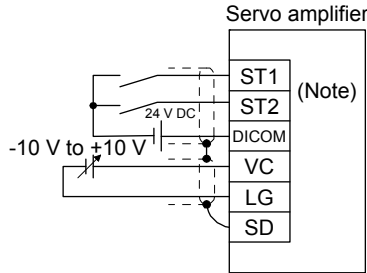
### 3. SIGNALS AND WIRING

(3) Speed setting in speed control mode

(a) Speed command and speed

The servo motor is run at the speeds set in the parameters or at the speed set in the applied voltage of VC (Analog speed command). The relation between an applied voltage of VC (Analog speed command) and servo motor speed, and the rotation direction with turning on ST1/ST2 are the same as section 3.6.2 (1) (a).

Normally, connect as follows.



Note. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.

(b) Speed command value selection

To select VC (Analog speed command) and a speed command value of internal speed commands 1 to 7, enable SP1 (Speed selection 1), SP2 (Speed selection 2), and SP3 (Speed selection 3) with [Pr. PD03] to [Pr. PD20].

(Note) Input device			Speed command value
SP3	SP2	SP1	
0	0	0	VC (Analog speed command)
0	0	1	Pr. PC05 Internal speed command 1
0	1	0	Pr. PC06 Internal speed command 2
0	1	1	Pr. PC07 Internal speed command 3
1	0	0	Pr. PC08 Internal speed command 4
1	0	1	Pr. PC09 Internal speed command 5
1	1	0	Pr. PC10 Internal speed command 6
1	1	1	Pr. PC11 Internal speed command 7

Note. 0: Off  
1: On

You can change the speed during rotation. Acceleration/deceleration is performed with the setting values of [Pr. PC01] and [Pr. PC02].

When the internal speed commands 1 to 7 are used to command a speed, the speed does not vary with the ambient temperature.

(c) SA (Speed reached)

As in section 3.6.2 (2)

### 3. SIGNALS AND WIRING

#### 3.6.5 Speed/torque control switching mode

Set " \_\_\_ 3" in [Pr. PA01] to switch to the speed/torque control switching mode.

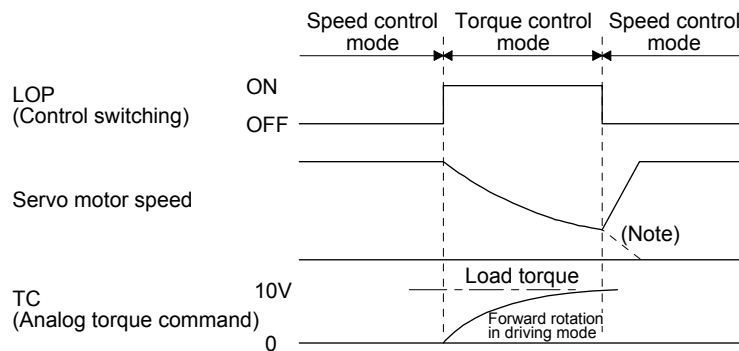
(1) LOP (control switching)

Use LOP (Control switching) to switch between the speed control mode and the torque control mode with an external contact. The following shows a relation between LOP and control modes.

(Note) LOP	Control mode
0	Speed control mode
1	Torque control mode

Note. 0: Off  
1: On

The control mode may be switched at any time. The following shows a switching timing chart.



Note. When ST1 (Forward rotation start) and ST2 (Reverse rotation start) are switched off as soon as a mode is switched to the speed control, the servo motor comes to a stop according to the deceleration time constant. A shock may occur at switching control modes.

(2) Speed setting in speed control mode

As in section 3.6.2 (1)

(3) Torque limit in speed control mode

As in section 3.6.1 (5)

(4) Speed limit in torque control mode

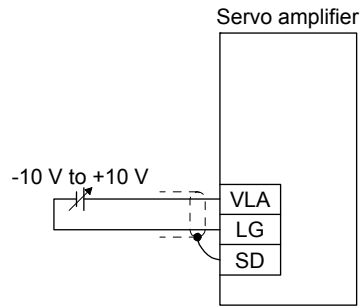
(a) Speed limit value and speed

The speed is limited to the limit value of the parameter or the value set in the applied voltage of VLA (Analog speed limit).

A relation between the VLA (Analog speed limit) applied voltage and the limit value is as in section 3.6.3 (3) (a).

### 3. SIGNALS AND WIRING

Normally, connect as follows.



(b) Speed limit value selection

To select VLA (Analog speed limit) and a speed limit value of internal speed limit 1 to 7, enable SP1 (Speed selection 1), SP2 (Speed selection 2), and SP3 (Speed selection 3) with [Pr. PD03] to [Pr. PD20].

(Note) Input device			Speed limit
SP3	SP2	SP1	
0	0	0	VLA (Analog speed limit)
0	0	1	Pr. PC05 Internal speed limit 1
0	1	0	Pr. PC06 Internal speed limit 2
0	1	1	Pr. PC07 Internal speed limit 3
1	0	0	Pr. PC08 Internal speed limit 4
1	0	1	Pr. PC09 Internal speed limit 5
1	1	0	Pr. PC10 Internal speed limit 6
1	1	1	Pr. PC11 Internal speed limit 7

Note. 0: Off  
1: On

When the internal speed command 1 is used to command a speed, the speed does not vary with the ambient temperature.

(c) VLC (Limiting speed)

As in section 3.6.3 (3) (c)

(5) Torque control in torque control mode

As in section 3.6.3 (1)

(6) Torque limit in torque control mode

As in section 3.6.3 (2)



### 3. SIGNALS AND WIRING

#### 3.6.6 Torque/position control switching mode

Set "\_\_\_5" in [Pr. PA01] to switch to the torque/position control switching mode.

##### (1) LOP (control switching)

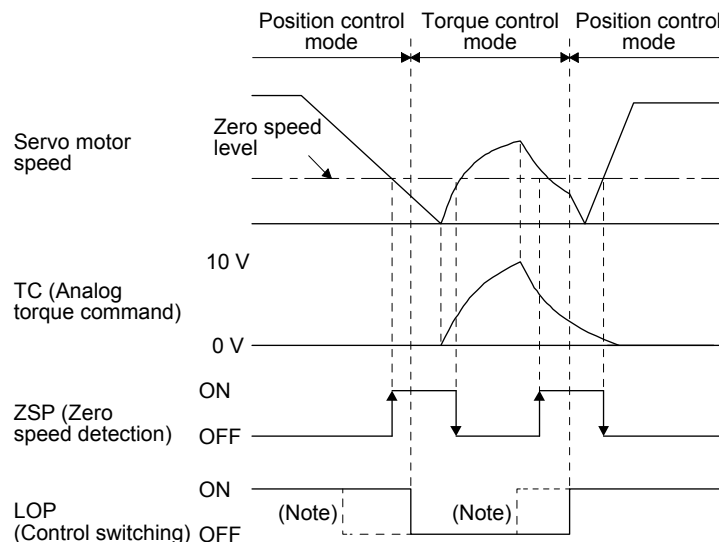
Use LOP (Control switching) to switch between the torque control mode and the position control mode with an external contact. The following shows a relation between LOP and control modes.

(Note) LOP	Control mode
0	Torque control mode
1	Position control mode

Note. 0: Off  
1: On

You can switch the control mode in the zero speed status. To ensure safety, switch modes after the servo motor has stopped. When position control mode is switched to torque control mode, droop pulses will be reset.

If LOP is switched on/off at the speed higher than the zero speed, the control mode cannot be changed regardless of the speed. The following shows a switching timing chart.



Note. When ZSP is not turned on, the control mode is not switched even if LOP is turned on/off. After LOP is turned on/off, even if ZSP is turned on, the control mode is not switched.

##### (2) Speed limit in torque control mode

As in section 3.6.3 (3)

##### (3) Torque control in torque control mode

As in section 3.6.3 (1)

##### (4) Torque limit in torque control mode

As in section 3.6.3 (2)

##### (5) Torque limit in position control mode

As in section 3.6.1 (5)

### 3. SIGNALS AND WIRING

---

#### 3.7 Forced stop deceleration function

POINT
●When alarms not related to the forced stop function occur, control of motor deceleration cannot be guaranteed. (Refer to chapter 8.)
●In the torque control mode, the forced stop deceleration function is not available.

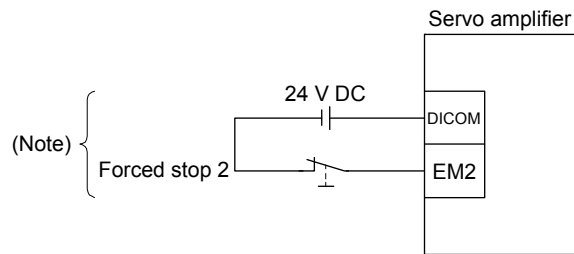
##### 3.7.1 Forced stop deceleration function

When EM2 is turned off, dynamic brake will start to stop the servo motor after forced stop deceleration.

During this sequence, the display shows [AL. E6 Servo forced stop warning].

During normal operation, do not use EM2 (Forced stop 2) to alternate stop and drive. The servo amplifier life may be shortened.

##### (1) Connection diagram



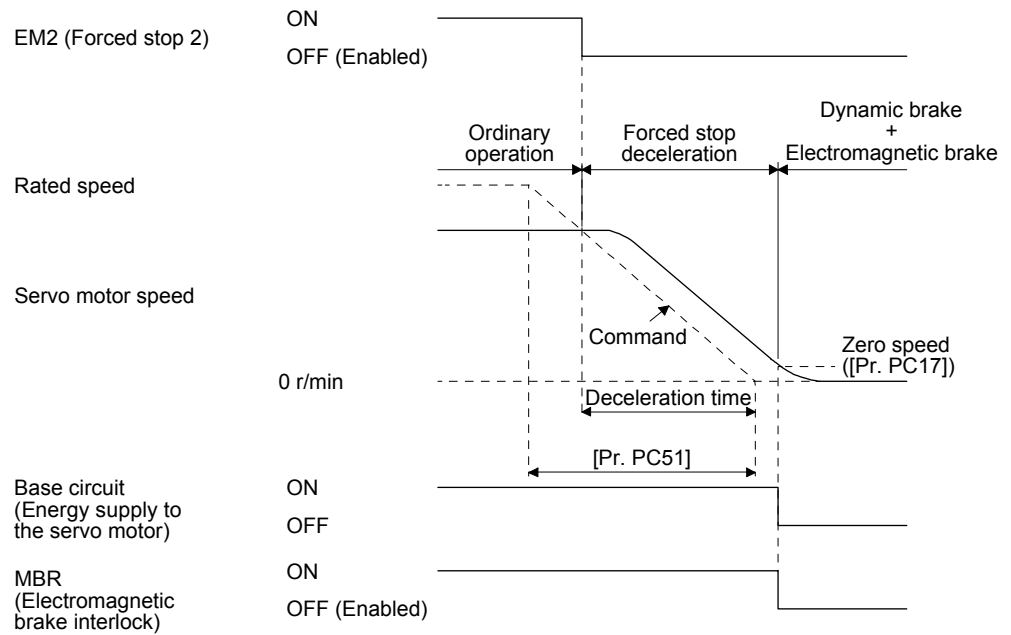
Note. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.

### 3. SIGNALS AND WIRING

#### (2) Timing chart

POINT	
● When LSP/LSN is turned on during a forced stop deceleration, the motor will stop depending on the setting of [Pr. PD30] as follows.	
[Pr. PD30]	Stop system
___ 0	Switching to sudden stop
___ 1	Continuing forced stop deceleration

When EM2 (Forced stop 2) is turned off, the motor will decelerate according to [Pr. PC51 Forced stop deceleration time constant]. Once the motor speed is below [Pr. PC17 Zero speed] after completion of the deceleration command, base power is cut and the dynamic brake activates.

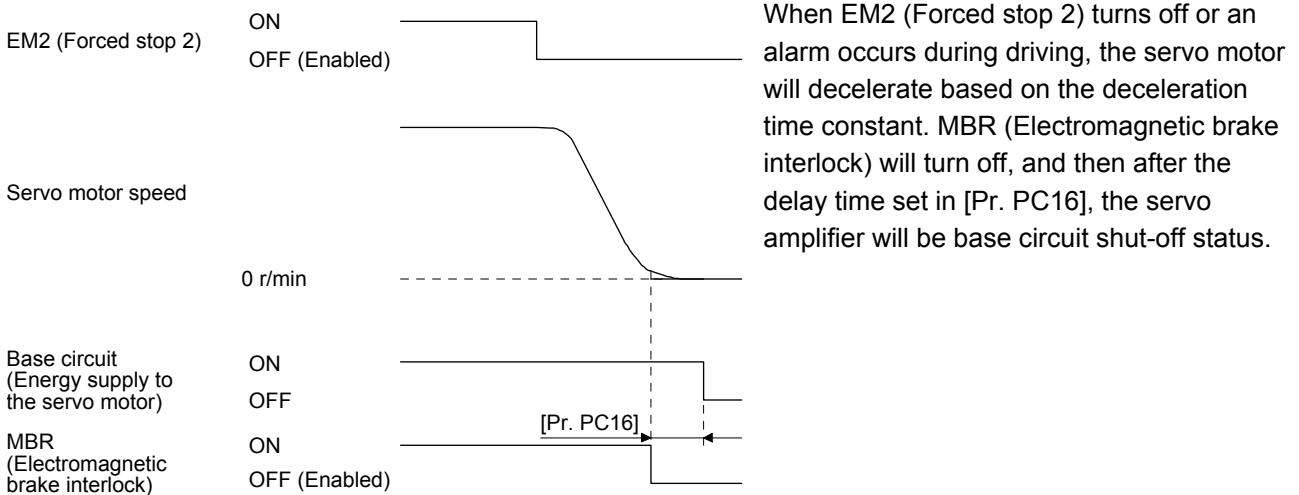


### 3. SIGNALS AND WIRING

#### 3.7.2 Base circuit shut-off delay time function

The base circuit shut-off delay time function is used to prevent vertical axis from dropping at a forced stop (EM2 goes off) or alarm occurrence due to delay time of the electromagnetic brake. Use [Pr. PC16] to set the delay time between completion of EM2 (Forced stop 2) or activation of MBR (Electromagnetic brake interlock) due to an alarm occurrence, and shut-off of the base circuit.

##### (1) Timing chart



##### (2) Adjustment

While the servo motor is stopped, turn off EM2 (Forced stop 2), adjust the base circuit shut-off delay time in [Pr. PC16], and set the value to approximately 1.5 times of the smallest delay time in which the servo motor shaft does not freefall.

### 3. SIGNALS AND WIRING

#### 3.7.3 Vertical axis freefall prevention function

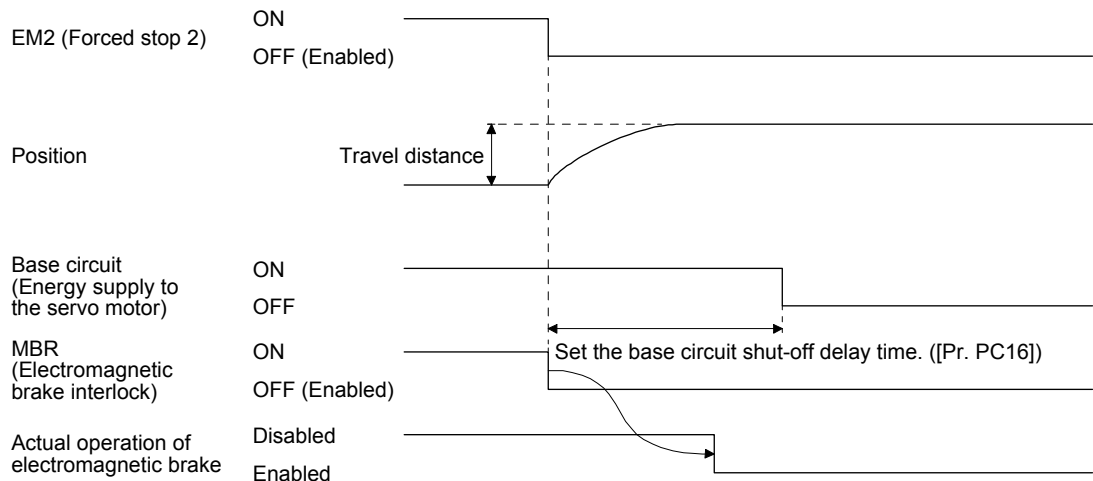
The vertical axis freefall prevention function avoids machine damage by pulling up the shaft slightly like the following case.

When the servo motor is used for operating vertical axis, the servo motor electromagnetic brake and the base circuit shut-off delay time function avoid dropping axis at forced stop. However, the functions may not avoid dropping axis a few  $\mu\text{m}$  due to the backlash of the servo motor electromagnetic brake.

The vertical axis freefall prevention function is enabled with the following conditions.

- Other than "0" is set to [Pr. PC54 Vertical axis freefall prevention compensation amount].
- The servo motor speed decelerates lower than the value of zero speed by turning off EM2 (Forced stop 2) or by an alarm occurrence.
- The base circuit shut-off delay time function is enabled.
- EM2 (Forced stop 2) turned off or an alarm occurred while the servo motor speed is zero speed or less.

##### (1) Timing chart



##### (2) Adjustment


- Set the freefall prevention compensation amount in [Pr. PC54].
- While the servo motor is stopped, turn off the EM2 (Forced stop 2). Adjust the base circuit shut-off delay time in [Pr. PC16] in accordance with the travel distance ([Pr. PC54]). Adjust it considering the freefall prevention compensation amount by checking the servo motor speed, torque ripple, etc.

#### 3.7.4 Residual risks of the forced stop function (EM2)

- (1) The forced stop function is not available for alarms that activate the dynamic brake when the alarms occur.
- (2) When an alarm that activates the dynamic brake during forced stop deceleration occurs, the braking distance until the servo motor stops will be longer than that of normal forced stop deceleration without the dynamic brake.

### 3. SIGNALS AND WIRING

#### 3.8 Alarm occurrence timing chart

 <b>CAUTION</b>	<p>● When an alarm has occurred, remove its cause, make sure that the operation signal is not being input, ensure safety, and reset the alarm before restarting operation.</p>
--	--

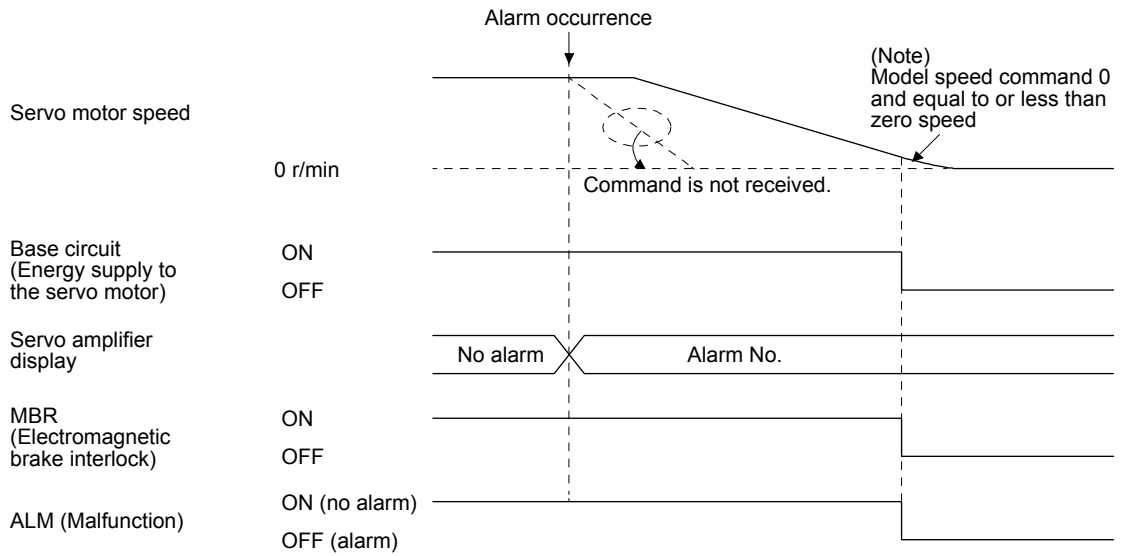
POINT	<p>● In the torque control mode, the forced stop deceleration function is not available.</p>
-------	--

To deactivate an alarm, cycle the power, push the "SET" button in the current alarm window, or cycle the RES (Reset) However, the alarm cannot be deactivated unless its cause is removed.

#### 3.8.1 When you use the forced stop deceleration function

POINT	<p>● To enable the function, set "2 _ _ _ (initial value)" in [Pr. PA04].</p>
-------	---

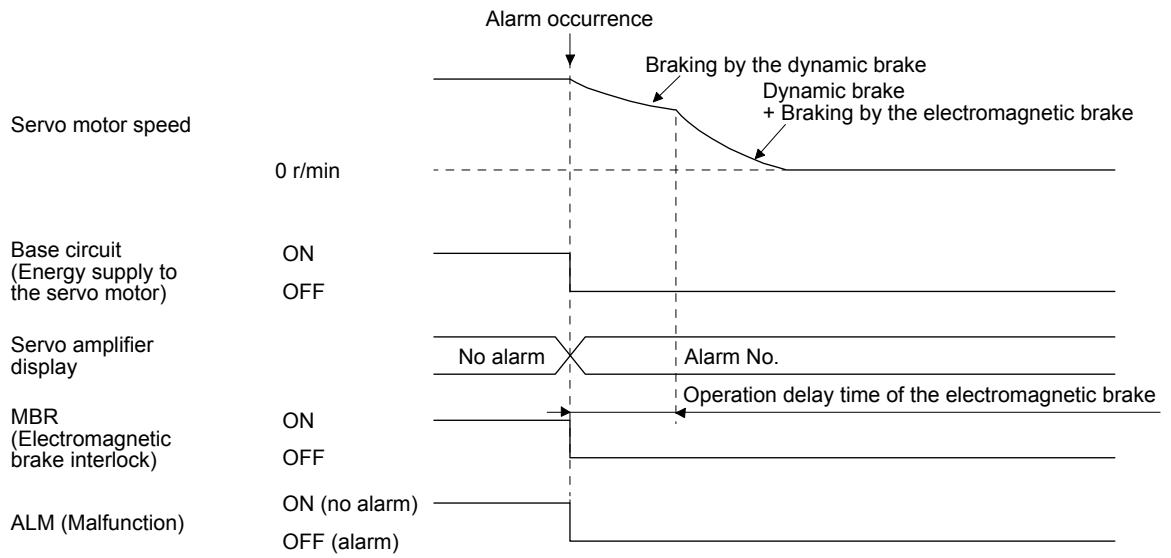
#### (1) When the forced stop deceleration function is enabled



Note. The model speed command is a speed command generated in the servo amplifier for forced stop deceleration of the servo motor.

### 3. SIGNALS AND WIRING

(2) When the forced stop deceleration function is not enabled



3.8.2 When you do not use the forced stop deceleration function

POINT
● To disable the function, set "0 _ _ _" in [Pr. PA04].

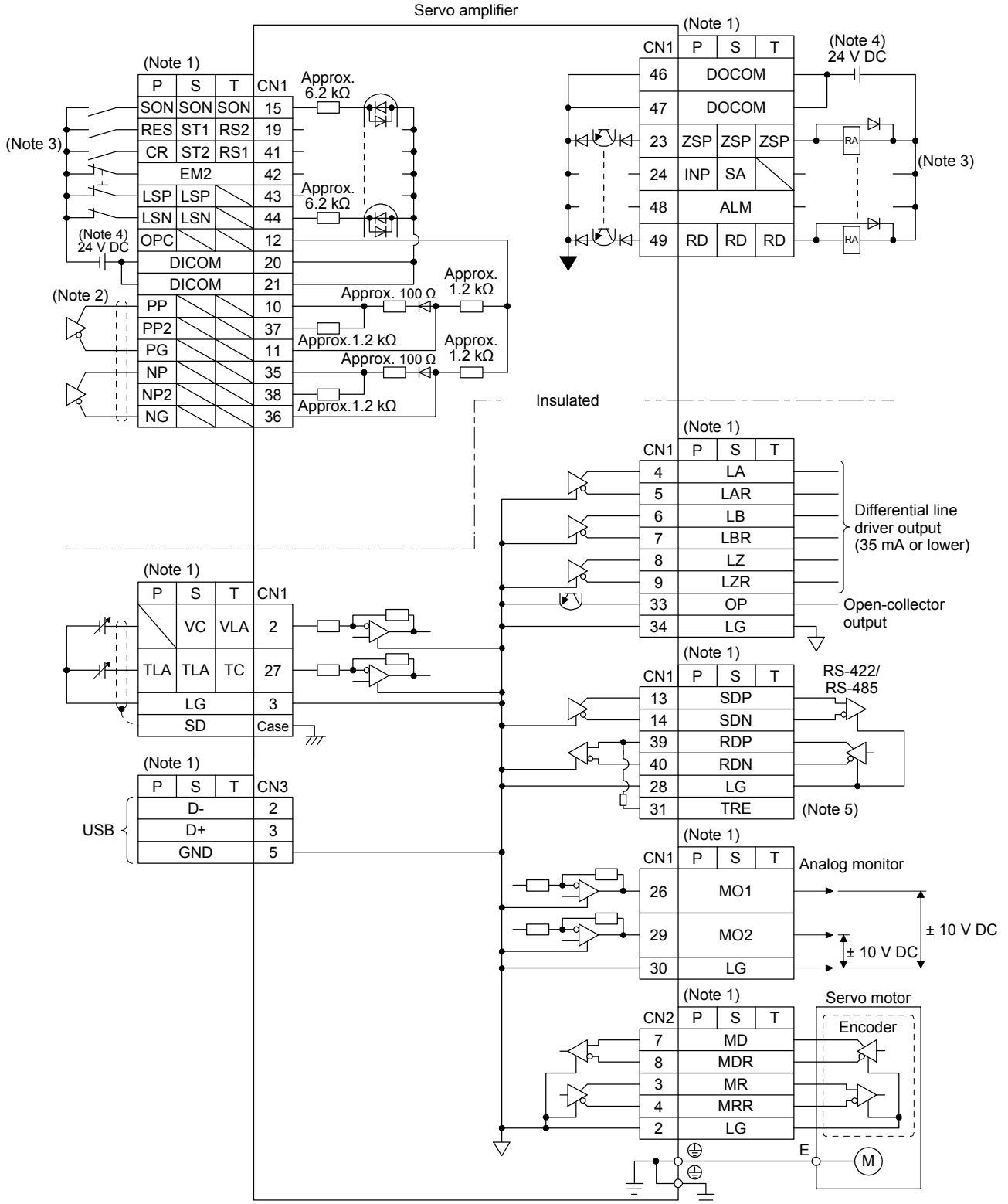
The operation status during an alarm is the same as section 3.8.1 (2).

# 3. SIGNALS AND WIRING

## 3.9 Interfaces

### 3.9.1 Internal connection diagram

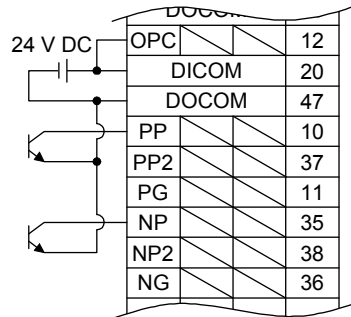
The following diagram is for sink I/O interface when command pulse train input is differential line driver type.



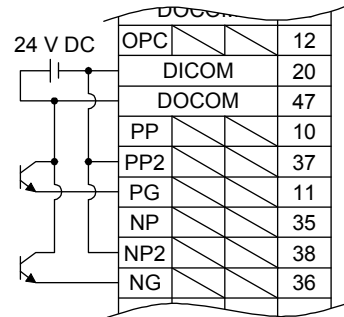


### 3. SIGNALS AND WIRING

- Note 1. P: position control mode, S: speed control mode, T: torque control mode  
 2. This is for the differential line driver pulse train input. For the open-collector pulse train input, connect as follows.



For sink input interface



For source input interface

- This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.
- The illustration of the 24 V DC power supply is divided between input signal and output signal for convenience. However, they can be configured by one.
- To use the RS-422/RS-485 communication function, connect between TRE and RDN of the final axis servo amplifier. (Refer to section 12.1.1.)

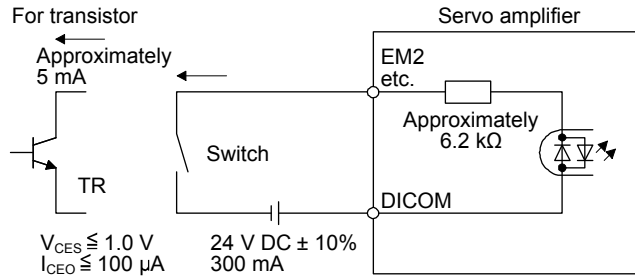
### 3. SIGNALS AND WIRING

#### 3.9.2 Detailed explanation of interfaces

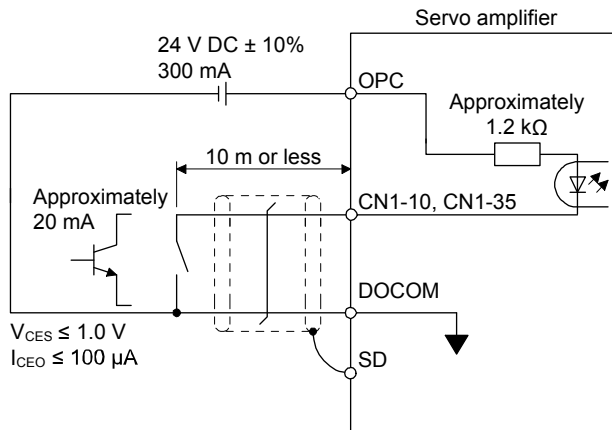
This section provides the details of the I/O signal interfaces (refer to the I/O division in the table) given in section 3.5. Refer to this section and make connection with the external device.

##### (1) Digital input interface DI-1

This is an input circuit whose photocoupler cathode side is input terminal. Transmit signals from sink (open-collector) type transistor output, relay switch, etc. The following is a connection diagram for sink input. Refer to section 3.9.3 for source input.



The following shows when the CN1-10 pin and the CN1-35 pin are used as digital input interface:



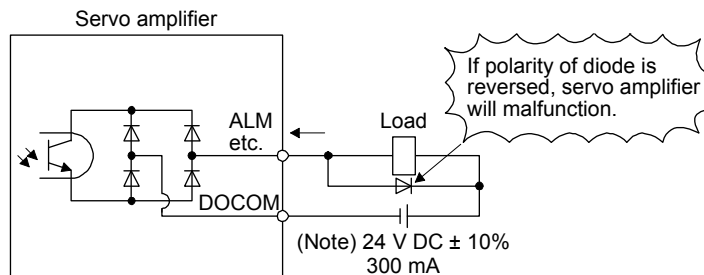
##### (2) Digital output interface DO-1

This is a circuit in which the collector of the output transistor is the output terminal. When the output transistor is turned on, the current will flow to the collector terminal.

A lamp, relay or photocoupler can be driven. Install a diode (D) for an inductive load, or install an inrush current suppressing resistor (R) for a lamp load.

(Rated current: 40 mA or less, maximum current: 50 mA or less, inrush current: 100 mA or less) A maximum of 2.6 V voltage drop occurs in the servo amplifier.

The following shows a connection diagram for sink output. Refer to section 3.9.3 for source output.



Note. If the voltage drop (maximum of 2.6 V) interferes with the relay operation, apply high voltage (maximum of 26.4 V) from external source.

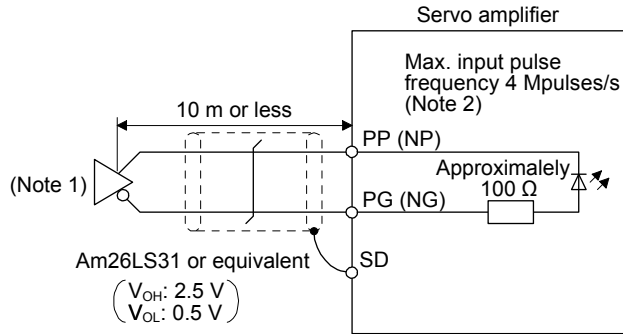
### 3. SIGNALS AND WIRING

(3) Pulse train input interface DI-2

Give a pulse train signal in the differential line driver type or open-collector type.

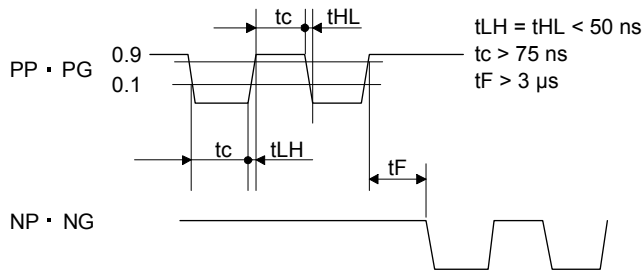
(a) Differential line driver type

1) Interface



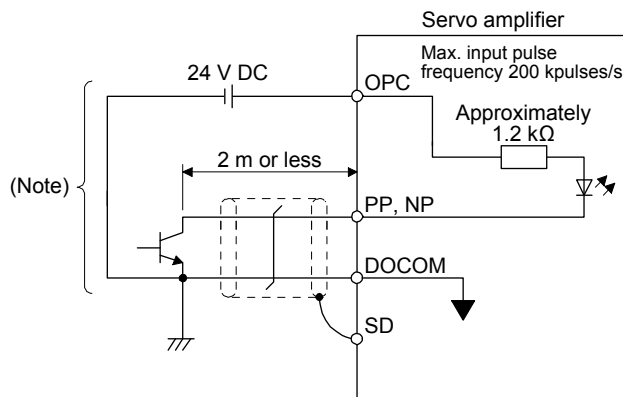
- Note 1. Pulse train input interface is comprised of a photocoupler.  
If a resistor is connected to the pulse train signal line, it may malfunction due to reduction in current.
2. When the input pulse frequency is 4 Mpulses/s, set [Pr. PA13] to "\_ 0 \_ \_".

2) Input pulse condition



(b) Open-collector type

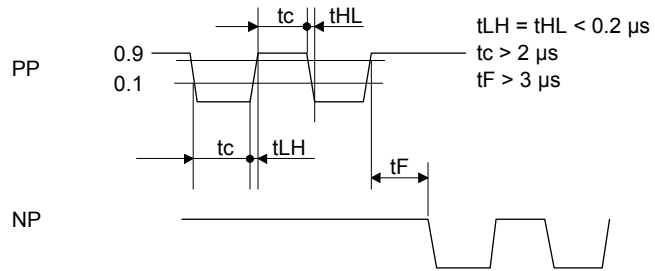
1) Interface



- Note. Pulse train input interface is comprised of a photocoupler.  
If a resistor is connected to the pulse train signal line, it may malfunction due to reduction in current.

### 3. SIGNALS AND WIRING

#### 2) Input pulse condition

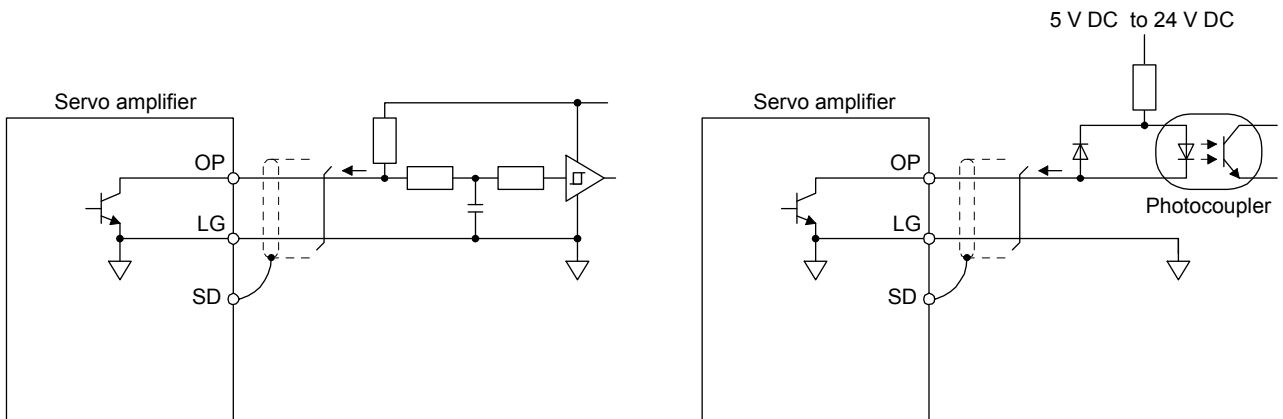


#### (4) Encoder output pulse DO-2

##### (a) Open-collector type

Interface

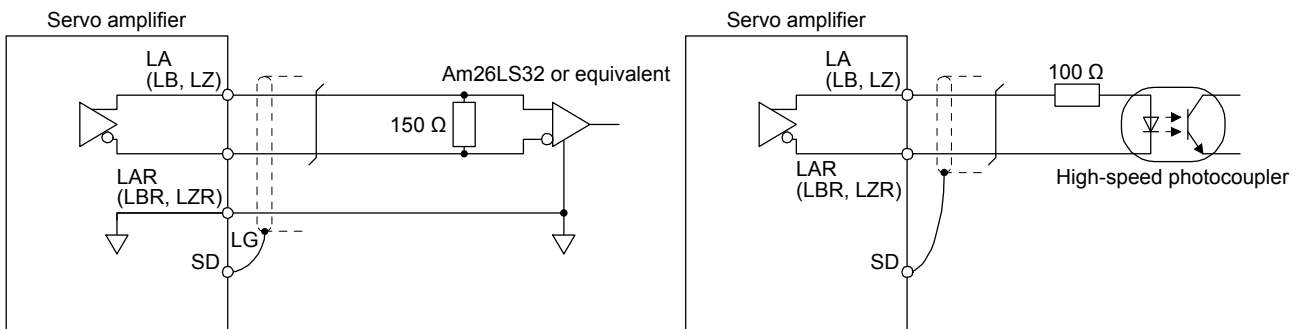
Maximum sink current: 35 mA



##### (b) Differential line driver type

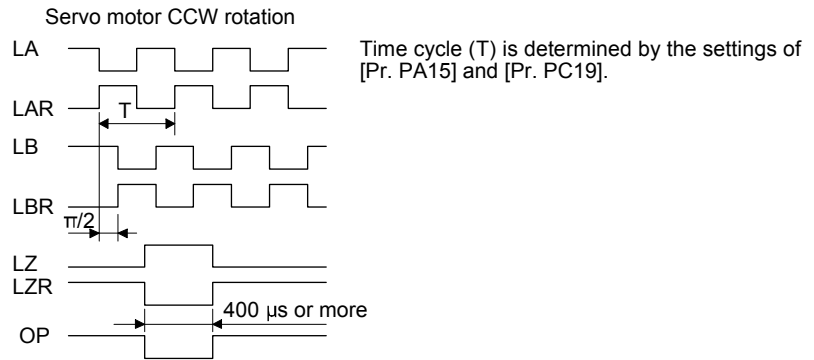
##### 1) Interface

Maximum output current: 35 mA

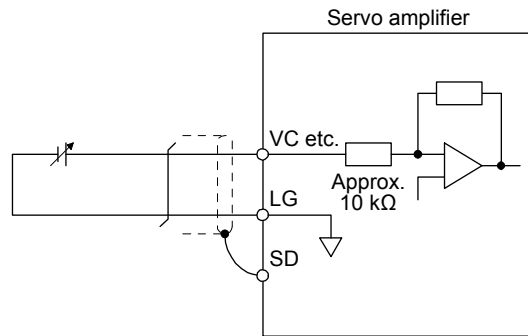


### 3. SIGNALS AND WIRING

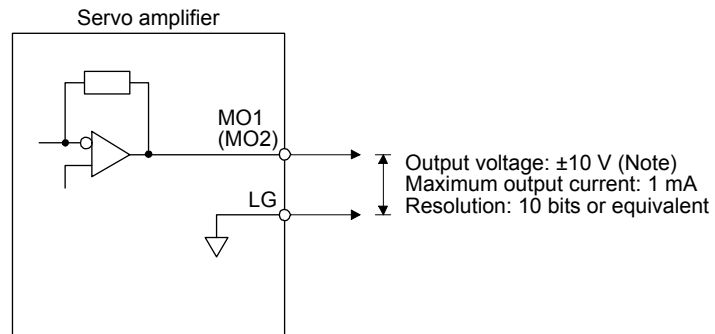
#### 2) Output pulse



- (5) Analog input  
 Input impedance  
 10 kΩ to 12 kΩ



- (6) Analog output



Note. Output voltage range varies depending on the monitored signal.

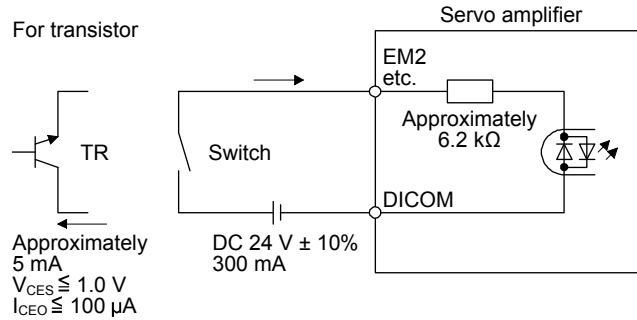
### 3. SIGNALS AND WIRING

#### 3.9.3 Source I/O interfaces

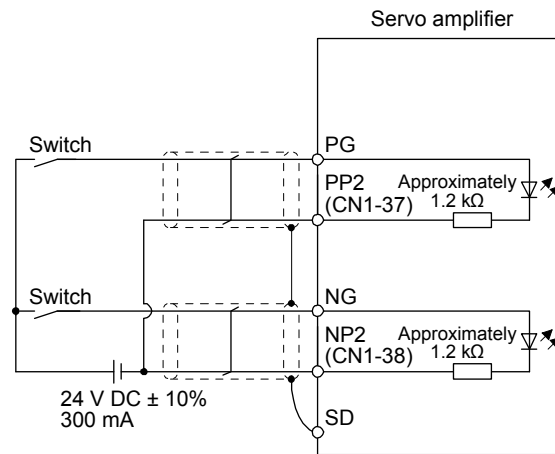
In this servo amplifier, source type I/O interfaces can be used.

##### (1) Digital input interface DI-1

This is an input circuit whose photocoupler anode side is the input terminal. Transmit signals from source (open-collector) type transistor output, relay switch, etc.

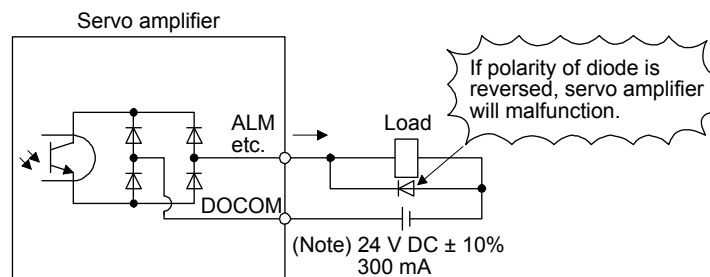


The following shows when the CN1-37 pin and the CN1-38 pin are used as digital input interface:



##### (2) Digital output interface DO-1

This is a circuit in which the emitter of the output transistor is the output terminal. When the output transistor is turned on, the current will flow from the output terminal to a load. A maximum of 2.6 V voltage drop occurs in the servo amplifier.



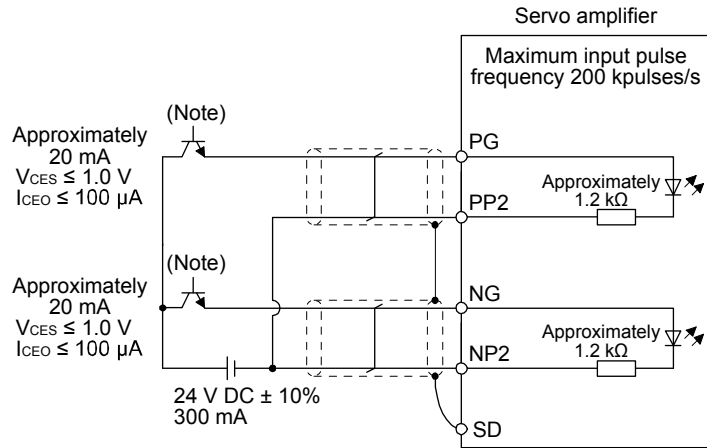
Note. If the voltage drop (maximum of 2.6 V) interferes with the relay operation, apply high voltage (maximum of 26.4 V) from external source.

### 3. SIGNALS AND WIRING

(3) Pulse train input interface DI-2

Give a pulse train signal in the open-collector type.

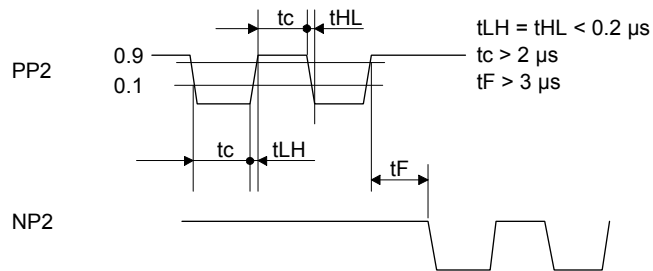
1) Interface



Note. Pulse train input interface is comprised of a photocopier.

If a resistor is connected to the pulse train signal line, it may malfunction due to reduction in current.

2) Input pulse condition

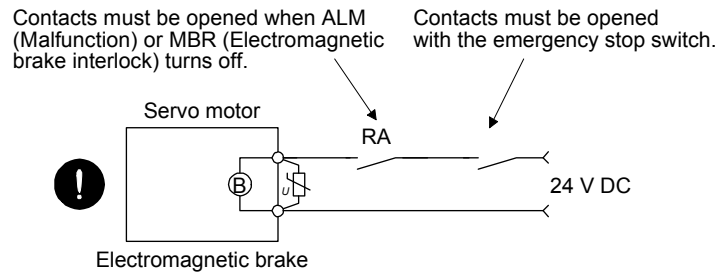


### 3. SIGNALS AND WIRING

#### 3.10 Servo motor with an electromagnetic brake

##### 3.10.1 Safety precautions

- Configure an electromagnetic brake circuit which is interlocked with an external emergency stop switch.



### ⚠ CAUTION

- The electromagnetic brake is provided for holding purpose and must not be used for ordinary braking.
- Before operating the servo motor, be sure to confirm that the electromagnetic brake operates properly.
- Do not use the 24 V DC interface power supply for the electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake. Otherwise, it may cause a malfunction.
- When using EM2 (Forced stop 2), use MBR (Electromagnetic brake interlock) for operating the electromagnetic brake. Operating the electromagnetic brake without using MBR during deceleration to a stop will saturate servo motor torques at the maximum value due to brake torques of the electromagnetic brake and can result in delay of the deceleration to a stop from a set value.

#### POINT

- Refer to "HG-KN/HG-SN Servo Motor Instruction Manual" for specifications such as the power supply capacity and operation delay time of the electromagnetic brake.
- Refer to "HG-KN/HG-SN Servo Motor Instruction Manual" for the selection of a surge absorber for the electromagnetic brake.

Note the following when the servo motor with an electromagnetic brake is used.

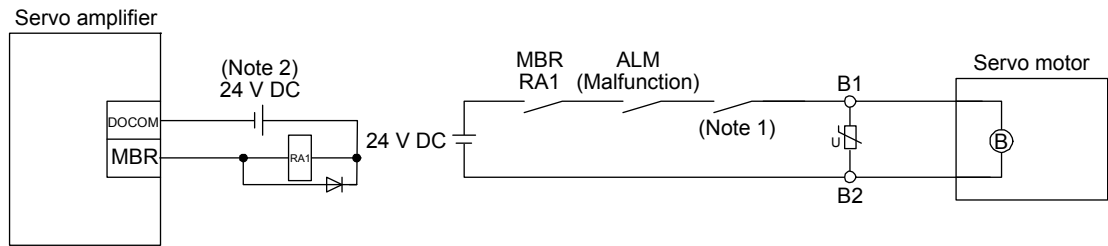
- 1) The brake will operate when the power (24 V DC) turns off.
- 2) The status is base circuit shut-off during RES (Reset) on. When you use the motor in vertical axis system, use MBR (Electromagnetic brake interlock).
- 3) Turn off SON (Servo-on) after the servo motor stopped.



### 3. SIGNALS AND WIRING

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#### (1) Connection diagram



- Note 1. Create the circuit in order to shut off by interlocking with the emergency stop switch.  
2. Do not use the 24 V DC interface power supply for the electromagnetic brake.

#### (2) Setting

- (a) Enable MBR (Electromagnetic brake interlock) with [Pr. PD03] to [Pr. PD20].
- (b) In [Pr. PC16 Electromagnetic brake sequence output], set a delay time ( $T_b$ ) from MBR (Electromagnetic brake interlock) off to base circuit shut-off at a servo-off as in the timing chart in section 3.10.2 (1).

### 3. SIGNALS AND WIRING

#### 3.10.2 Timing chart

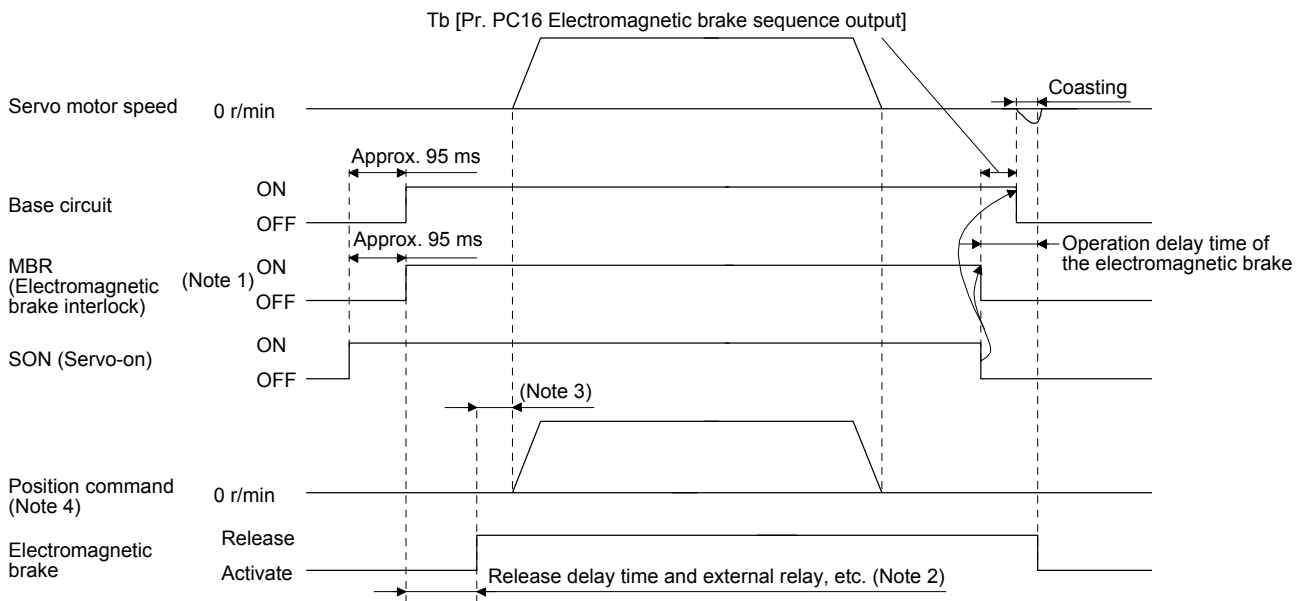
(1) When you use the forced stop deceleration function

**POINT**

● To enable the function, set "2 \_ \_ \_ (initial value)" in [Pr. PA04].

(a) SON (Servo-on) on/off

When SON (Servo-on) is turned off, the servo lock will be released after  $T_b$  [ms], and the servo motor will coast. If the electromagnetic brake is enabled during servo-lock, the brake life may be shorter. Therefore, set  $T_b$  about 1.5 times of the minimum delay time where the moving part will not drop down for a vertical axis system, etc.



Note 1. ON: Electromagnetic brake is not activated.

OFF: Electromagnetic brake has been activated.

Note 2. Electromagnetic brake is released after the release delay time of electromagnetic brake and operation time of external circuit relay, etc. For the release delay time of electromagnetic brake, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".

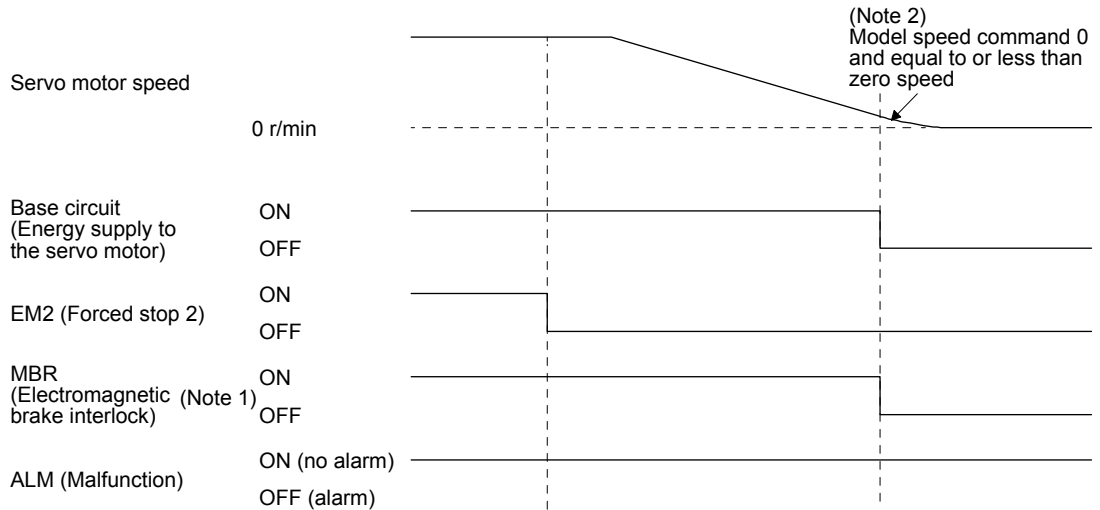
Note 3. Give a position command after the electromagnetic brake is released.

Note 4. This is in position control mode.

### 3. SIGNALS AND WIRING

(b) Forced stop 2 on/off

POINT
● In the torque control mode, the forced stop deceleration function is not available.

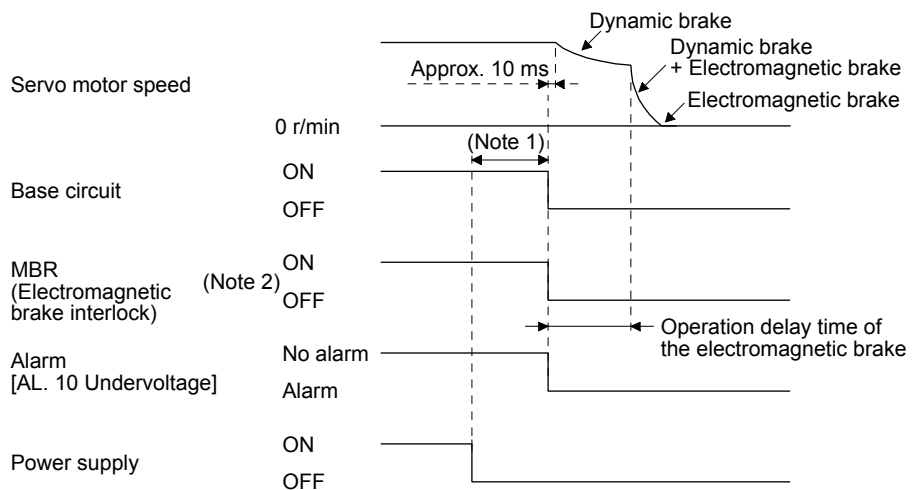


- Note 1. ON: Electromagnetic brake is not activated.  
 OFF: Electromagnetic brake has been activated.
- Note 2. The model speed command is a speed command generated in the servo amplifier for forced stop deceleration of the servo motor.

(c) Alarm occurrence

The operation status during an alarm is the same as section 3.8.

(d) Power off



- Note 1. Variable according to the operation status.
- Note 2. ON: Electromagnetic brake is not activated.  
 OFF: Electromagnetic brake has been activated.

### 3. SIGNALS AND WIRING

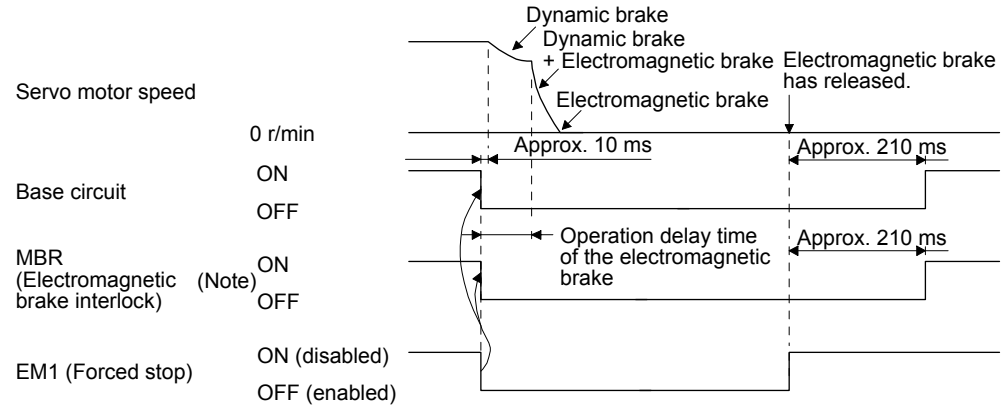
(2) When you do not use the forced stop deceleration function

POINT
● To disable the function, set "0 _ _ _" in [Pr. PA04].

(a) SON (Servo-on) on/off

It is the same as (1) (a) in this section.

(b) EM1 (Forced stop 1) on/off



Note. ON: Electromagnetic brake is not activated.

OFF: Electromagnetic brake has been activated.

(c) Alarm occurrence

The operation status during an alarm is the same as section 3.8.

(d) Power off

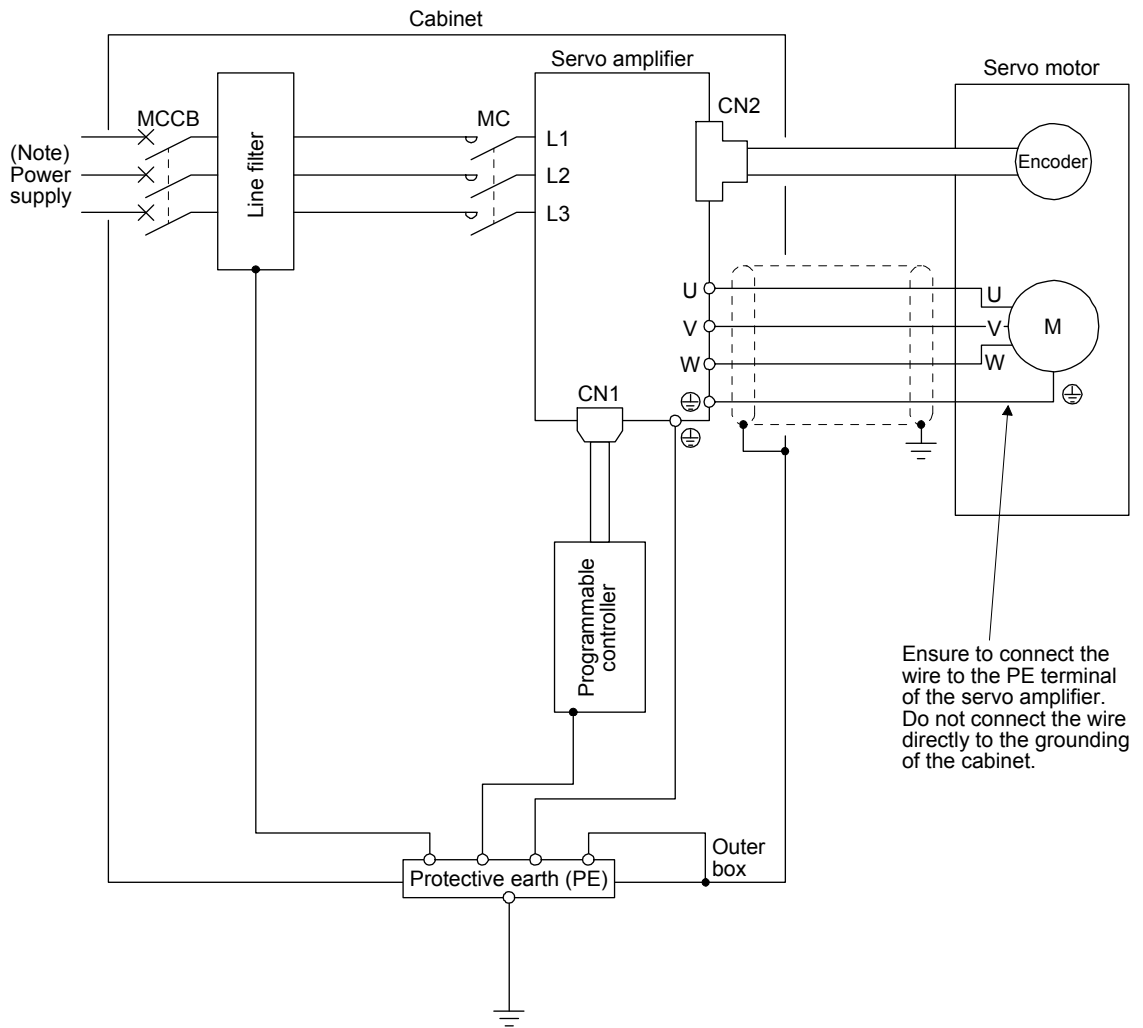
It is the same as (1) (d) of this section.

### 3. SIGNALS AND WIRING

#### 3.11 Grounding

**WARNING** ● Ground the servo amplifier and servo motor securely.  
● To prevent an electric shock, always connect the protective earth (PE) terminal (marked ⊕) of the servo amplifier to the protective earth (PE) of the cabinet.

The servo amplifier switches the power transistor on-off to supply power to the servo motor. Depending on the wiring and ground cable routing, the servo amplifier may be affected by the switching noise (due to di/dt and dv/dt) of the transistor. To prevent such a fault, refer to the following diagram and always ground. To conform to the EMC Directive, refer to "EMC Installation Guidelines".



Note. For the power supply specifications, refer to section 1.3.

## 4. STARTUP

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### 4. STARTUP

**⚠ WARNING** ● Do not operate the switches with wet hands. Otherwise, it may cause an electric shock.

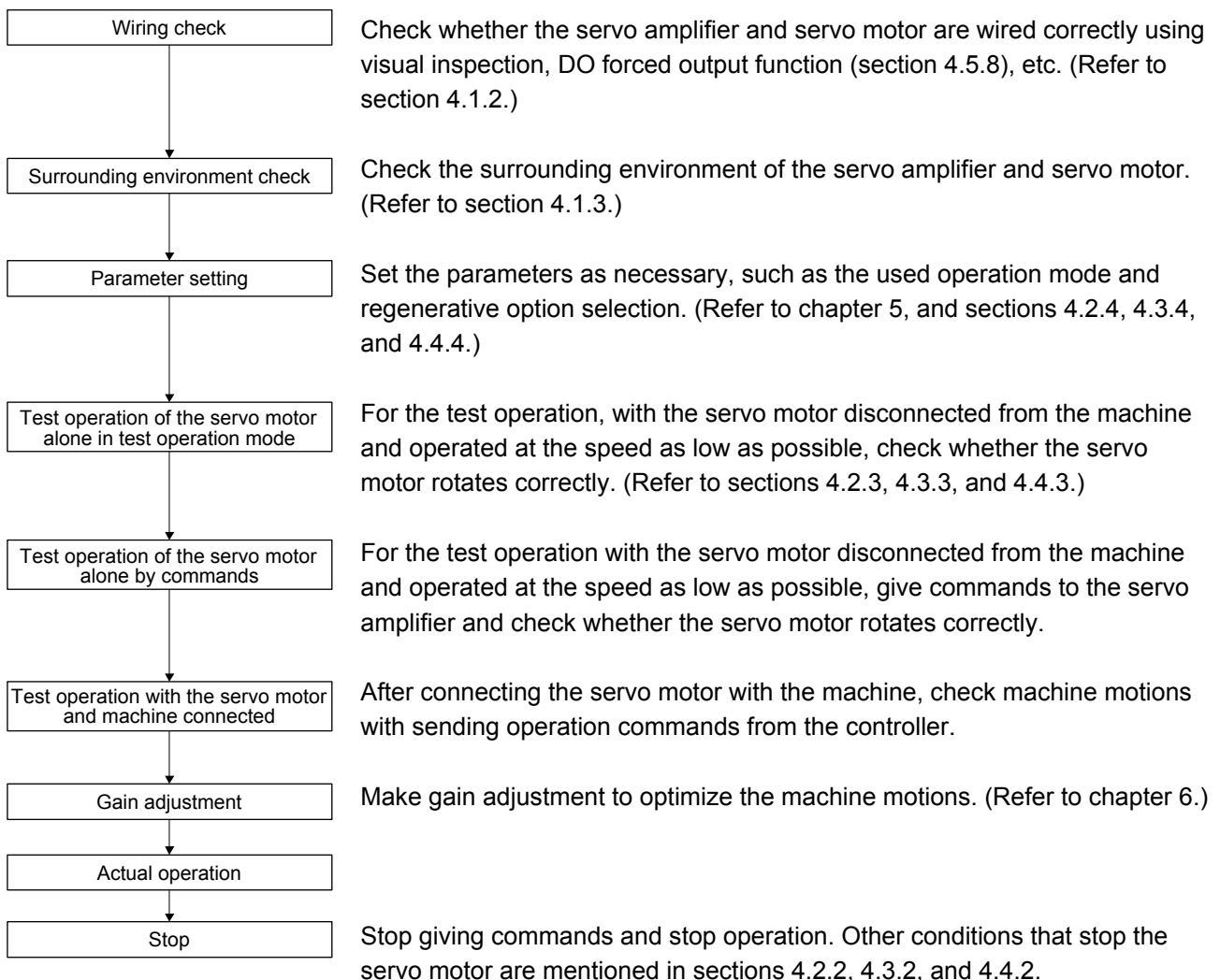
**⚠ CAUTION**

- Before starting operation, check the parameters. Improper settings may cause some machines to operate unexpectedly.
- The servo amplifier heat sink, regenerative resistor, servo motor, etc., may be hot while the power is on and for some time after power-off. Take safety measures such as providing covers to avoid accidentally touching them by hands and parts such as cables.
- During operation, never touch the rotor of the servo motor. Otherwise, it may cause injury.

#### 4.1 Switching power on for the first time

When switching power on for the first time, follow this section to make a startup.

##### 4.1.1 Startup procedure



## 4. STARTUP

### 4.1.2 Wiring check

#### (1) Power supply system wiring

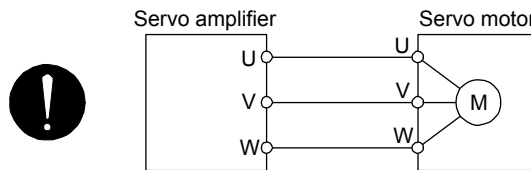
Before switching on the power supply, check the following items.

##### (a) Power supply system wiring

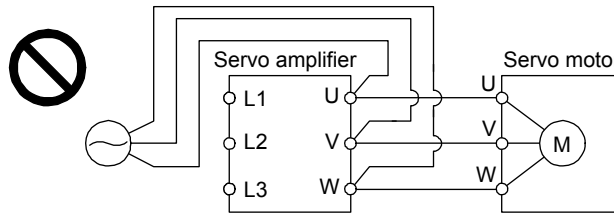
The power supplied to the power input terminals (L1/L2/L3) of the servo amplifier should satisfy the defined specifications. (Refer to section 1.3.)

##### (b) Connection of servo amplifier and servo motor

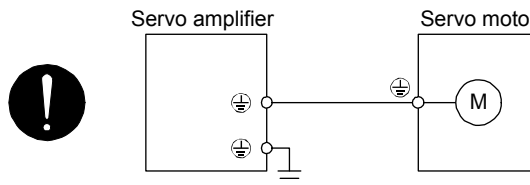
- 1) The servo amplifier power output (U/V/W) should match in phase with the servo motor power input terminals (U/V/W).



- 2) The power supplied to the servo amplifier should not be connected to the power outputs (U/V/W). Otherwise, the servo amplifier and servo motor will fail.



- 3) The grounding terminal of the servo motor is connected to the PE terminal of the servo amplifier.



- 4) The CN2 connector of the servo amplifier should be connected to the encoder of the servo motor securely using the encoder cable.

##### (c) When you use an option and peripheral equipment

##### 1) When you use a regenerative option for 1 kW or less servo amplifiers

- The built-in regenerative resistor and wirings should be removed from the servo amplifier.
- The lead wire of built-in regenerative resistor connected to P+ terminal and C terminal should not be connected.
- The regenerative option should be connected to P+ terminal and C terminal.
- Twisted wires should be used. (Refer to section 11.2.4.)

##### 2) When you use a regenerative option for 2 kW or more servo amplifiers

- The lead wire between P+ terminal and D terminal should not be connected.
- The regenerative option should be connected to P+ terminal and C terminal.
- Twisted wires should be used. (Refer to section 11.2.4.)

## 4. STARTUP

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### (2) I/O signal wiring

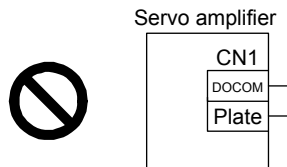
#### (a) The I/O signals should be connected correctly.

Use DO forced output to forcibly turn on/off the pins of the CN1 connector. You can use the function to check the wiring. Switch off SON (Servo-on) to enable the function.

Refer to section 3.2 for details of I/O signal connection.

#### (b) A voltage exceeding 24 V DC is not applied to the pins of the CN1 connector.

#### (c) Between Plate and Docom of the CN1 connector should not be shorted.



### 4.1.3 Surrounding environment

#### (1) Cable routing

##### (a) The wiring cables should not be stressed.

(b) The encoder cable should not be used in excess of its bending life. (Refer to section 10.4.)

##### (c) The connector of the servo motor should not be stressed.

#### (2) Environment

Signal cables and power cables are not shorted by wire offcuts, metallic dust or the like.



## 4. STARTUP

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### 4.2 Startup in position control mode

Make a startup in accordance with section 4.1. This section provides descriptions specific to the position control mode.

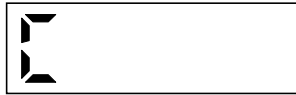
#### 4.2.1 Power on and off procedures

##### (1) Power-on

Switch power on in the following procedure. Always follow this procedure at power-on.

- 1) Switch off SON (Servo-on).
- 2) Make sure that a command pulse train is not input.
- 3) Turn on the power.

The display shows "C (Cumulative feedback pulses)", and in 2 s later, shows data.



##### (2) Power-off

- 1) Make sure that a command pulse train is not input.
- 2) Switch off SON (Servo-on).
- 3) Shut off the power.

#### 4.2.2 Stop

If any of the following situations occurs, the servo amplifier suspends the running of the servo motor and brings it to a stop. Refer to section 3.10 for the servo motor with an electromagnetic brake.

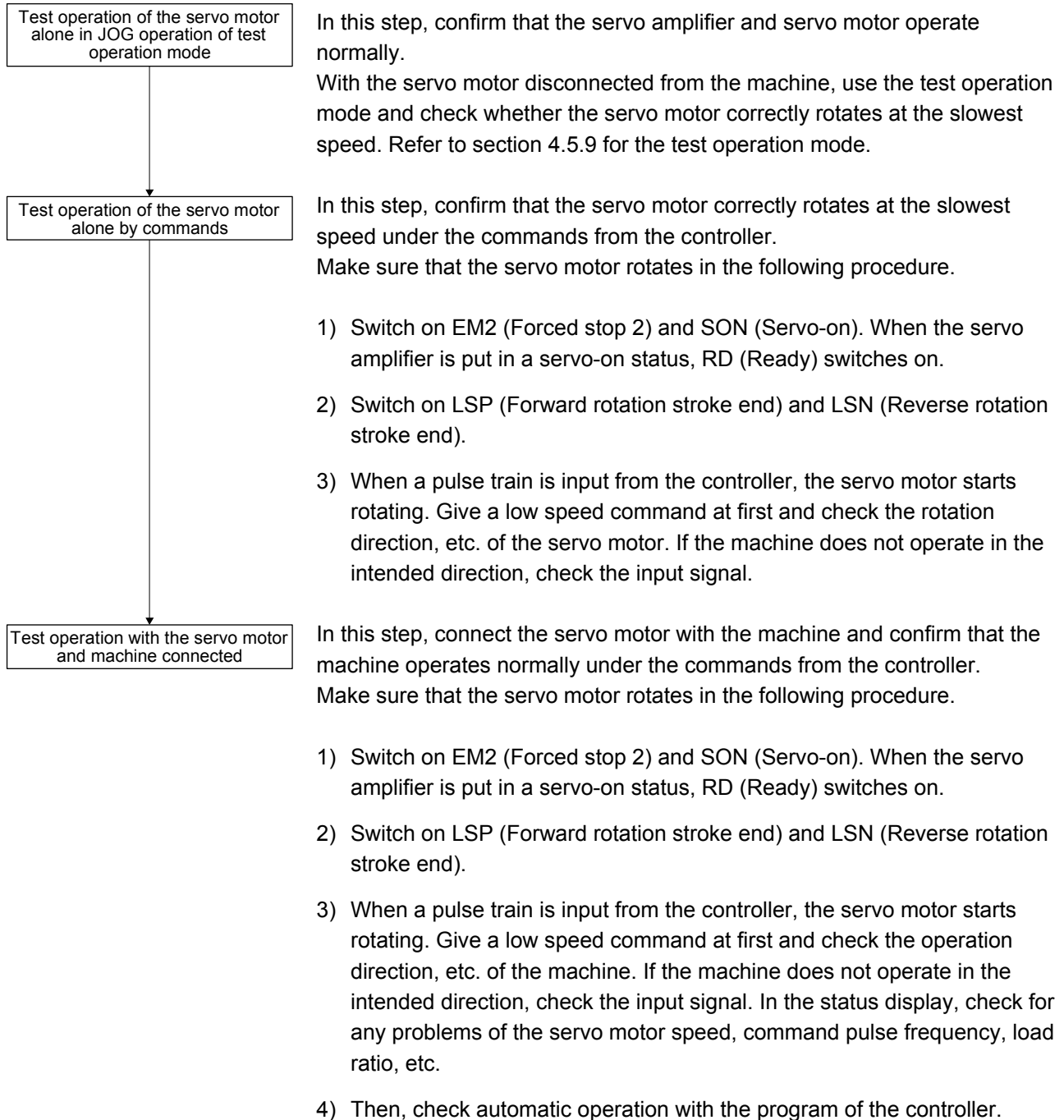
Operation/command	Stopping condition
Switch off SON (Servo-on).	The base circuit is shut off and the servo motor coasts.
Alarm occurrence	The servo motor decelerates to a stop with the command. With some alarms, however, the dynamic brake operates to bring the servo motor to a stop. (Refer to chapter 8.)
EM2 (Forced stop 2) off	The servo motor decelerates to a stop with the command. [AL. E6 Servo forced stop warning] occurs. EM2 has the same function as EM1 in the torque control mode. Refer to section 3.5 for EM1.
LSP (Forward rotation stroke end) off, LSN (Reverse rotation stroke end) off	It will bring the motor to a sudden stop and make it servo-locked. It can be run in the opposite direction.

## 4. STARTUP

---

### 4.2.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally. Refer to section 4.2.1 for how to power on and off the servo amplifier.



## 4. STARTUP

---

### 4.2.4 Parameter setting

POINT
●The following encoder cables are of four-wire type. When using any of these encoder cables, set [Pr. PC22] to "1 _ _ _" to select the four-wire type. Incorrect setting will result in [AL. 16 Encoder initial communication error 1]. MR-EKCBL30M-L MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H

In the position control mode, the servo amplifier can be used by merely changing the basic setting parameters ([Pr. PA \_ \_ ]) mainly.

As necessary, set other parameters.

### 4.2.5 Actual operation

Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings. Perform a home position return as necessary.

## 4. STARTUP

### 4.2.6 Trouble at start-up



#### CAUTION

● Never make a drastic adjustment or change to the parameter values as doing so will make the operation unstable.

#### POINT

● Using the optional MR Configurator2, you can refer to reason for rotation failure, etc.

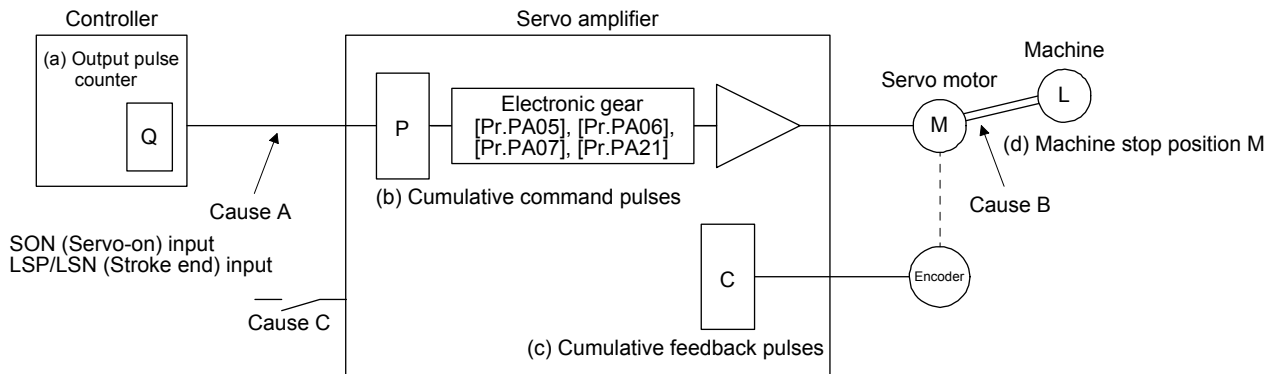
The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

#### (1) Troubleshooting

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	<ul style="list-style-type: none"> <li>• 7-segment LED is not lit.</li> <li>• 7-segment LED flickers.</li> </ul>	Not improved even if CN1 and CN2 connectors are disconnected.	<ol style="list-style-type: none"> <li>1. Power supply voltage fault</li> <li>2. The servo amplifier is malfunctioning.</li> </ol>	/
			Improved when CN1 connector is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when CN2 connector is disconnected.	<ol style="list-style-type: none"> <li>1. Power supply of encoder cabling is shorted.</li> <li>2. Encoder is malfunctioning.</li> </ol>	
		Alarm occurs.	Refer to chapter 8 and remove cause.	Chapter 8	
2	Switch on SON (Servo-on).	Alarm occurs.	Refer to chapter 8 and remove cause.		Chapter 8
		Servo motor shaft is not servo-locked. (Servo motor shaft is free.)	<ol style="list-style-type: none"> <li>1. Check the display to see if the servo amplifier is ready to operate.</li> <li>2. Check the external I/O signal indication (section 4.5.7) to see if SON (Servo-on) is on.</li> </ol>	<ol style="list-style-type: none"> <li>1. SON (Servo-on) is not input. (wiring mistake)</li> <li>2. 24 V DC power is not supplied to DICOM.</li> </ol>	Section 4.5.7
3	Input command pulse (test operation).	Servo motor does not rotate.	Check the cumulative command pulse on the status display (section 4.5.3).	<ol style="list-style-type: none"> <li>1. Wiring mistake               <ol style="list-style-type: none"> <li>(a) For open collector pulse train input, 24 V DC power is not supplied to OPC.</li> <li>(b) LSP and LSN are not on.</li> </ol> </li> <li>2. Pulse is not input from the controller.</li> </ol>	Section 4.5.3
		Servo motor run in reverse direction.		Mistake in setting of [Pr. PA13]. <ol style="list-style-type: none"> <li>1. Mistake in wiring to controller.</li> <li>2. Mistake in setting of [Pr. PA14].</li> </ol>	Chapter 5
4	Gain adjustment	Rotation ripples (speed fluctuations) are large at low speed.	Make gain adjustment in the following procedure. <ol style="list-style-type: none"> <li>1. Increase the auto tuning response level.</li> <li>2. Repeat acceleration and deceleration three times to complete auto tuning.</li> </ol>	Gain adjustment fault	Chapter 6
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be driven with safety, repeat acceleration and deceleration three times to complete auto tuning.	Gain adjustment fault	Chapter 6
5	Cyclic operation	Position shift occurs	Confirm the cumulative command pulses, cumulative feedback pulses and actual servo motor position.	Pulse counting error, etc. due to noise.	(2) of this section

## 4. STARTUP

### (2) How to find the cause of position shift



When a position shift occurs, check (a) output pulse counter Q, (b) cumulative command pulse P, (c) cumulative feedback pulse C, and (d) machine stop position M in the above diagram.

Also, Causes A, B, and C indicate the causes of position mismatch. For example, Cause A indicates that noise entered the wiring between the controller and servo amplifier, causing command input pulses to be miscounted.

In a normal status without position shift, there are the following relationships.

1)  $Q = P$  (Output counter = Cumulative command pulses)

2) When [Pr. PA21] is "0 \_ \_ \_"

$$P \cdot \frac{\text{CMX [Pr. PA06]}}{\text{CDV [Pr. PA07]}} = C \text{ (Cumulative command pulses} \times \text{Electronic gear = Cumulative feedback pulses)}$$

3) When [Pr. PA21] is "1 \_ \_ \_"

$$P \cdot \frac{131072}{\text{FBP [Pr. PA05]}} = C$$

4)  $C \cdot \Delta l = M$  (Cumulative feedback pulses  $\times$  Travel distance per pulse = Machine position)

Check for a position mismatch in the following sequence.

1) When  $Q \neq P$

Noise entered the pulse train signal wiring between the controller and servo amplifier, causing command input pulses to be miscounted. (Cause A)

Make the following check or take the following measures.

- Check how the shielding is done.
- Change the open collector type to the differential line driver type.
- Run wiring away from the power circuit.
- Install a data line filter. (Refer to section 11.9 (2) (a).)
- Change the [Pr. PA13 Command pulse input form] setting.

## 4. STARTUP

---

- 2) When  $P \cdot \frac{CMX}{CDV} \neq C$

During operation, SON (Servo-on), LSP (Forward rotation stroke end), or LSN (Reverse rotation stroke end) was switched off; or CR (Clear) or RES (Reset) was switched on. (Cause C)

- 3) When  $C \cdot \Delta t \neq M$

Mechanical slip occurred between the servo motor and machine. (Cause B)

### 4.3 Startup in speed control mode

Make a startup in accordance with section 4.1. This section provides the methods specific to the speed control mode.

#### 4.3.1 Power on and off procedures

##### (1) Power-on

Switch power on in the following procedure. Always follow this procedure at power-on.

- 1) Switch off SON (Servo-on).
- 2) Make sure that ST1 (Forward rotation start) and ST2 (Reverse rotation start) are off.
- 3) Turn on the power.

The display shows "r (Servo motor speed)", and in 2 s later, shows data.



##### (2) Power-off

- 1) Switch off ST1 (Forward rotation start) and ST2 (Reverse rotation start).
- 2) Switch off SON (Servo-on).
- 3) Shut off the power.

#### 4.3.2 Stop

If any of the following situations occurs, the servo amplifier suspends the running of the servo motor and brings it to a stop.

Refer to section 3.10 for the servo motor with an electromagnetic brake.

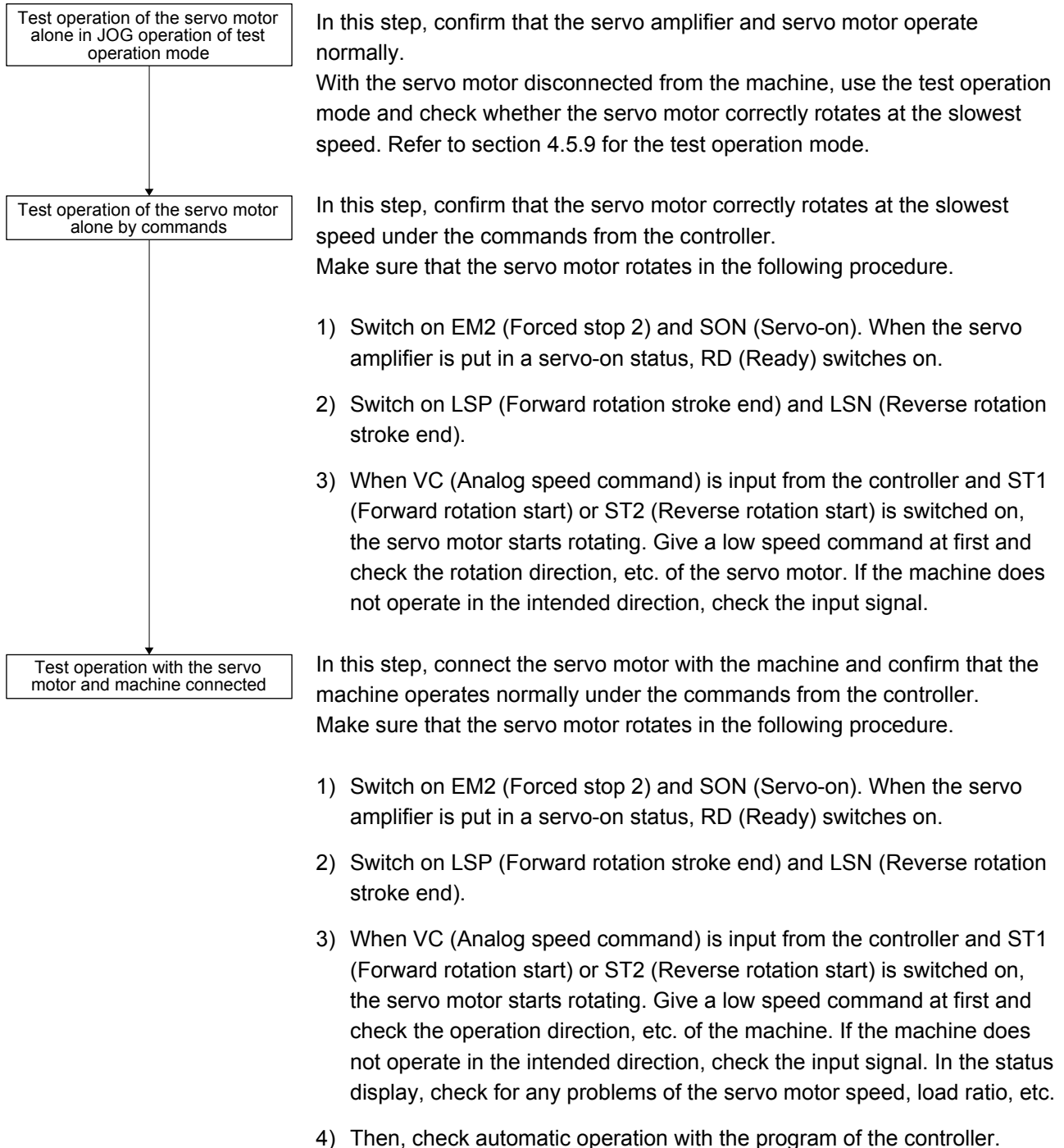
Operation/command	Stopping condition
Switch off SON (Servo-on).	The base circuit is shut off and the servo motor coasts.
Alarm occurrence	The servo motor decelerates to a stop with the command. With some alarms, however, the dynamic brake operates to bring the servo motor to a stop. (Refer to chapter 8.)
EM2 (Forced stop 2) off	The servo motor decelerates to a stop with the command. [AL. E6 Servo forced stop warning] occurs. EM2 has the same function as EM1 in the torque control mode. Refer to section 3.5 for EM1.
LSP (Forward rotation stroke end) off, LSN (Reverse rotation stroke end) off	It will bring the motor to a sudden stop and make it servo-locked. It can be run in the opposite direction.
Simultaneous on or off of ST1 (Forward rotation start) and ST2 (Reverse rotation start)	The servo motor is decelerated to a stop.

## 4. STARTUP

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### 4.3.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally. Refer to section 4.3.1 for how to power on and off the servo amplifier.



## 4. STARTUP

---

### 4.3.4 Parameter setting

POINT
●The following encoder cables are of four-wire type. When using any of these encoder cables, set [Pr. PC22] to "1 _ _ _" to select the four-wire type. Incorrect setting will result in [AL. 16 Encoder initial communication error 1]. MR-EKCBL30M-L MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H

When using this servo in the speed control mode, change [Pr. PA01] setting to select the speed control mode. In the speed control mode, the servo can be used by merely changing the basic setting parameters ([Pr. PA \_ \_ ]) and extension setting parameters ([Pr. PC \_ \_ ]) mainly. As necessary, set other parameters.



## 4. STARTUP

### 4.3.5 Actual operation

Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings.

### 4.3.6 Trouble at start-up



**CAUTION** ● Never make a drastic adjustment or change to the parameter values as doing so will make the operation unstable.

#### POINT

● Using the optional MR Configurator2, you can refer to reason for rotation failure, etc.

The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	<ul style="list-style-type: none"> <li>• 7-segment LED is not lit.</li> <li>• 7-segment LED flickers.</li> </ul>	Not improved even if CN1 and CN2 connectors are disconnected.	<ol style="list-style-type: none"> <li>1. Power supply voltage fault</li> <li>2. The servo amplifier is malfunctioning.</li> </ol>	/
			Improved when CN1 connector is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when CN2 connector is disconnected.	<ol style="list-style-type: none"> <li>1. Power supply of encoder cabling is shorted.</li> <li>2. Encoder is malfunctioning.</li> </ol>	
		Alarm occurs.	Refer to chapter 8 and remove cause.	Chapter 8	
2	Switch on SON (Servo-on).	Alarm occurs.	Refer to chapter 8 and remove cause.		Chapter 8
		Servo motor shaft is not servo-locked. (Servo motor shaft is free.)	<ol style="list-style-type: none"> <li>1. Check the display to see if the servo amplifier is ready to operate.</li> <li>2. Check the external I/O signal indication (section 4.5.7) to see if SON (Servo-on) is on.</li> </ol>	<ol style="list-style-type: none"> <li>1. SON (Servo-on) is not input. (wiring mistake)</li> <li>2. 24 V DC power is not supplied to DICOM.</li> </ol>	Section 4.5.7
3	Switch on ST1 (Forward rotation start) or ST2 (Reverse rotation start).	Servo motor does not rotate.	Call the status display (section 4.5.3) and check the input voltage of VC (Analog speed command).	Analog speed command is 0 V.	Section 4.5.3
			Call the external I/O signal display (section 4.5.7) and check the on/off status of the input signal.	LSP, LSN, ST1, and ST2 are off.	Section 4.5.7
			Check the internal speed commands 1 to 7 ([Pr. PC05] to [Pr. PC11]).	Set value is 0.	Section 5.2.3
			Check the forward rotation torque limit ([Pr. PA11]) and the reverse rotation torque limit ([Pr. PA12]).	Torque limit level is too low as compared to the load torque.	Section 5.2.1
			When TLA (Analog torque limit) is usable, check the input voltage on the status display.	Torque limit level is too low as compared to the load torque.	Section 4.5.3

## 4. STARTUP

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
4	Gain adjustment	Rotation ripples (speed fluctuations) are large at low speed.	Make gain adjustment in the following procedure. 1. Increase the auto tuning response level. 2. Repeat acceleration and deceleration three times to complete auto tuning.	Gain adjustment fault	Chapter 6
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be driven with safety, repeat acceleration and deceleration three times to complete auto tuning.	Gain adjustment fault	Chapter 6

### 4.4 Startup in torque control mode

Make a startup in accordance with section 4.1. This section provides the methods specific to the torque control mode.

#### 4.4.1 Power on and off procedures

##### (1) Power-on

Switch power on in the following procedure. Always follow this procedure at power-on.

- 1) Switch off SON (Servo-on).
- 2) Make sure that RS1 (Forward rotation selection) and RS2 (Reverse rotation selection) are off.
- 3) Turn on the power.  
Data is displayed in 2 s after "U" (Analog torque command) is displayed.



##### (2) Power-off

- 1) Switch off RS1 (Forward rotation selection) or RS2 (Reverse rotation selection).
- 2) Switch off SON (Servo-on).
- 3) Shut off the power.

#### 4.4.2 Stop

If any of the following situations occurs, the servo amplifier suspends the running of the servo motor and brings it to a stop. Refer to section 3.10 for the servo motor with an electromagnetic brake.

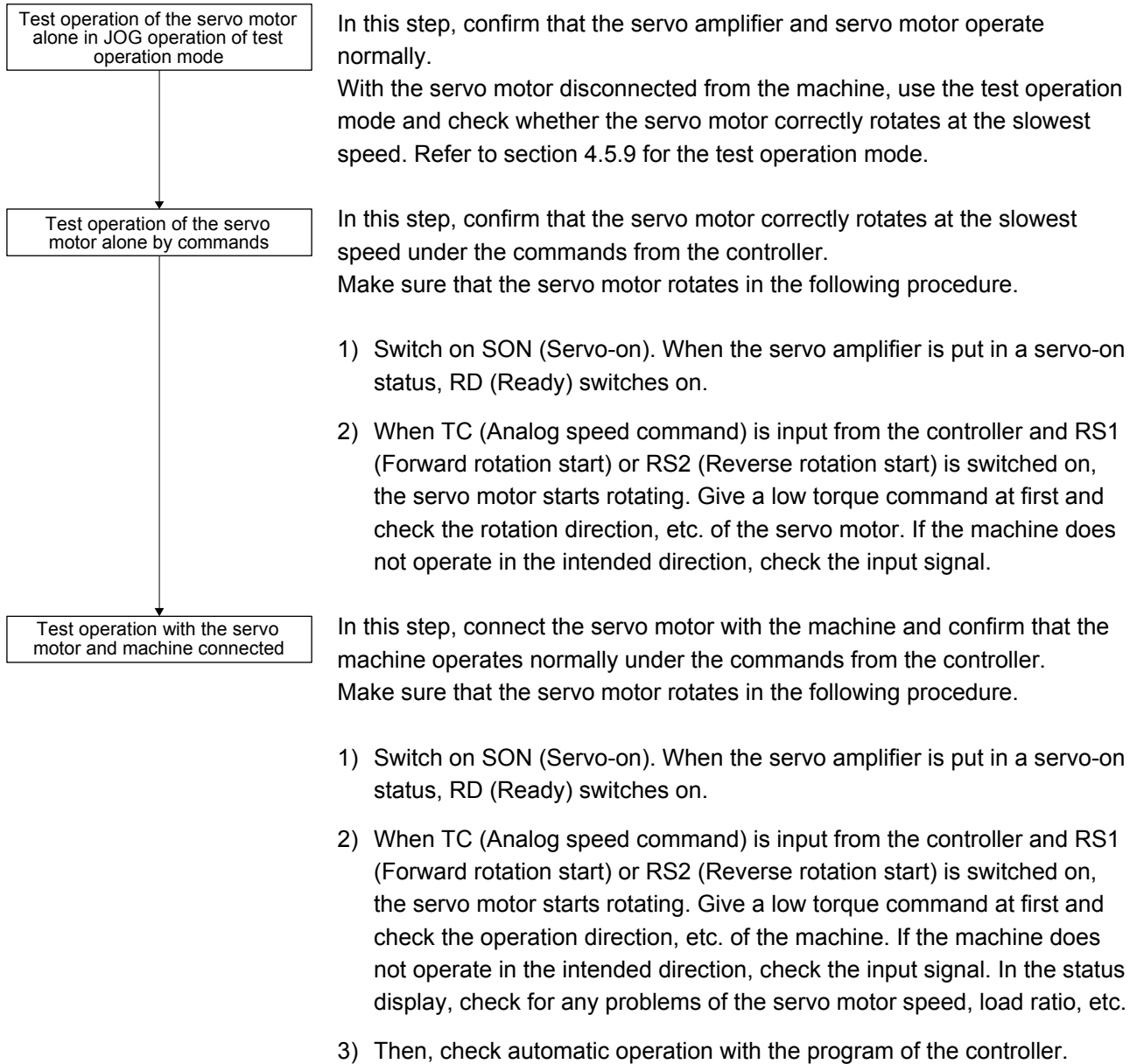
Operation/command	Stopping condition
Switch off SON (Servo-on).	The base circuit is shut off and the servo motor coasts.
Alarm occurrence	The servo motor decelerates to a stop with the command. With some alarms, however, the dynamic brake operates to bring the servo motor to a stop. (Refer to chapter 8.)
EM2 (Forced stop 2) off	This stops the servo motor with the dynamic brake. [AL. E6 Servo forced stop warning] occurs. EM2 has the same function as EM1 in the torque control mode. Refer to section 3.5 for EM1.
Simultaneous on or off of RS1 (Forward rotation selection) and RS2 (Reverse rotation selection)	The servo motor coasts.

## 4. STARTUP

---

### 4.4.3 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally. Refer to section 4.4.1 for how to power on and off the servo amplifier.



## 4. STARTUP

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### 4.4.4 Parameter setting

POINT
●The following encoder cables are of four-wire type. When using any of these encoder cables, set [Pr. PC22] to "1 _ _ _" to select the four-wire type. Incorrect setting will result in [AL. 16 Encoder initial communication error 1]. MR-EKCBL30M-L MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H

When using this servo in the torque control mode, change [Pr. PA01] setting to select the torque control mode. In the torque control mode, the servo can be used by merely changing the basic setting parameters ([Pr. PA \_ \_ ]) and extension setting parameters ([Pr. PC \_ \_ ]) mainly. As necessary, set other parameters.

### 4.4.5 Actual operation

Start actual operation after confirmation of normal operation by test operation and completion of the corresponding parameter settings.

## 4. STARTUP

### 4.4.6 Trouble at start-up



#### CAUTION

● Never make a drastic adjustment or change to the parameter values as doing so will make the motion unstable.

#### POINT

● Using the optional MR Configurator2, you can refer to reason for rotation failure, etc.

The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	<ul style="list-style-type: none"> <li>• 7-segment LED is not lit.</li> <li>• 7-segment LED flickers.</li> </ul>	Not improved even if CN1 and CN2 connectors are disconnected.	1. Power supply voltage fault 2. The servo amplifier is malfunctioning.	/
			Improved when CN1 connector is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when CN2 connector is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is malfunctioning.	
		Alarm occurs.	Refer to chapter 8 and remove cause.	Chapter 8	
2	Switch on SON (Servo-on).	Alarm occurs.	Refer to chapter 8 and remove cause.		Chapter 8
		Servo motor shaft is free.	Call the external I/O signal display (section 4.5.7) and check the on/off status of the input signal.	1. SON (Servo-on) is not input. (wiring mistake) 2. 24 V DC power is not supplied to DICOM.	Section 4.5.7
3	Switch on RS1 (Forward rotation start) or RS2 (Reverse rotation start).	Servo motor does not rotate.	Call the status display (section 4.5.3) and check the input voltage of TC (Analog torque command).	Analog torque command is 0 V.	Section 4.5.3
			Call the external I/O signal display (section 4.5.7) and check the on/off status of the input signal.	RS1 and RS2 are off.	Section 4.5.7
			Check the internal speed limit 1 to 7 ([Pr. PC05] to [Pr. PC11]).	Set value is 0.	Section 5.2.3
			Check the analog torque command maximum output ([Pr. PC13]) value.	Torque command level is too low as compared to the load torque.	Section 5.2.3
			Check the forward rotation torque limit ([Pr. PA11]) and the reverse rotation torque limit ([Pr. PA12]).	Set value is 0.	Section 5.2.1

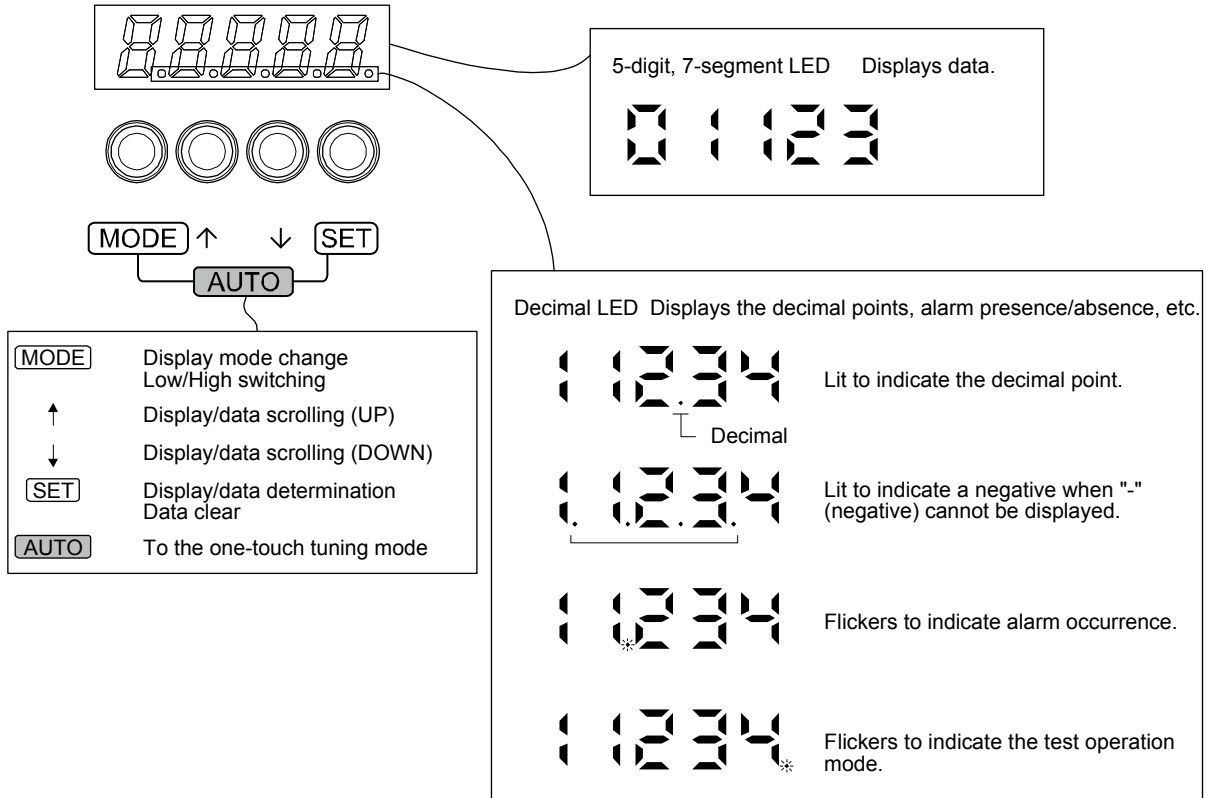
# 4. STARTUP

## 4.5 Display and operation sections

### 4.5.1 Summary

The MR-JE-A servo amplifier has the display section (5-digit, 7-segment LED) and operation section (4 pushbuttons) for servo amplifier status display, alarm display, parameter setting, etc. Push the "MODE" and "SET" buttons at the same time for 3 s or more to switch to the one-touch tuning mode.

The operation section and display data are described below.



## 4. STARTUP

### 4.5.2 Display flowchart

Press the "MODE" button once to shift to the next display mode. Refer to section 4.5.3 and later for the description of the corresponding display mode.

To refer to and set the gain/filter parameters, extension setting parameters and I/O setting parameters, enable them with [Pr. PA19 Parameter writing inhibit].

Display mode transition	Initial screen	Function	Reference
		Servo status display. "C" appears at power-on. (Note)	Section 4.5.3
		One-touch tuning Select this when performing the one-touch tuning.	Section 6.2
		Sequence display, external signal display, output signal (DO) forced output, test operation, software version display, VC automatic offset, servo motor series ID display, servo motor type ID display, servo motor encoder ID display, drive recorder enabled/disabled display.	Section 4.5.4
		Current alarm display, alarm history display, parameter error number display.	Section 4.5.5
		Display and setting of basic setting parameters.	Section 4.5.6
		Display and setting of gain/filter parameters.	
		Display and setting of extension setting parameters.	
		Display and setting of I/O setting parameters.	
		Display and setting of extension setting 2 parameters.	
		Display and setting of extension setting 3 parameters.	

Note. When the axis name is set to the servo amplifier using MR Configurator2, the axis name is displayed and the servo status is then displayed.

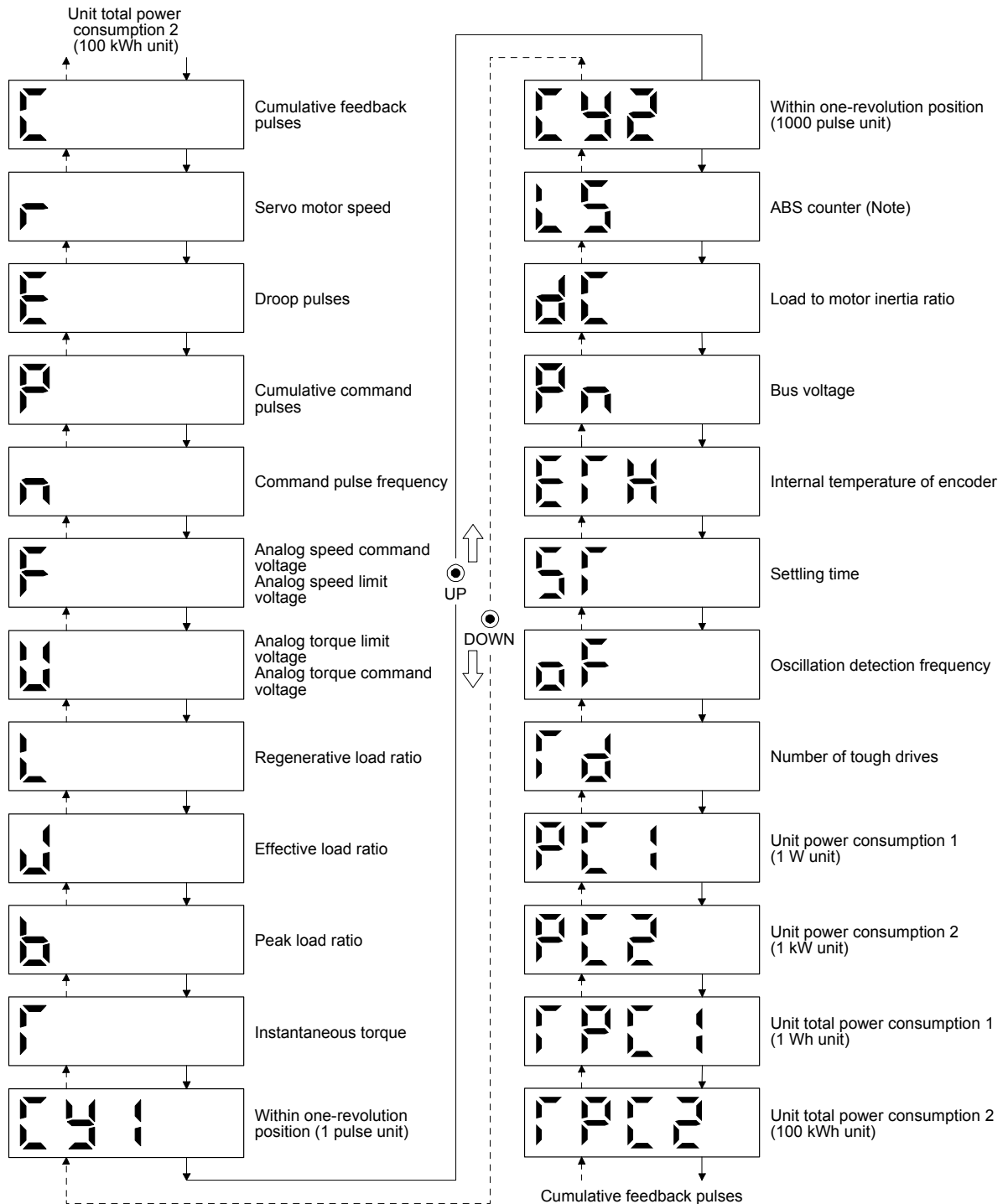
# 4. STARTUP

## 4.5.3 Status display mode

The servo status during operation is shown on the 5-digit, 7-segment LED display. Press the "UP" or "DOWN" button to change display data as desired. When the required data is selected, the corresponding symbol is displayed. Press the "SET" button to display that data. At only power-on, however, data appears after the symbol of the status display selected in [Pr. PC36] has been shown for 2 s.

### (1) Display transition

After selecting the status display mode with the "MODE" button, pressing the "UP" or "DOWN" button changes the display as shown below.



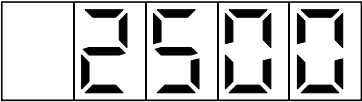
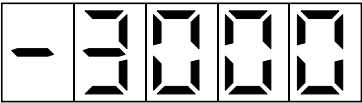
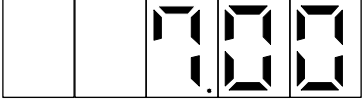
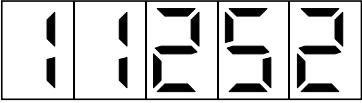
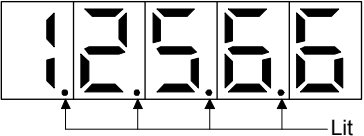
Note. Travel distance from power on is displayed by counter value.



## 4. STARTUP

### (2) Display examples

The following table shows the display examples.

Item	Status	Displayed data
		Servo amplifier display
Servo motor speed	Forward rotation at 2500 r/min	
	Reverse rotation at 3000 r/min	 Reverse rotation is indicated by "-".
Load to motor inertia ratio	7.00 times	
Cumulative feedback pulses	11252 pulses	
	-12566 pulses	 Lit Negative value is indicated by the lit decimal points in the upper four digits.

## 4. STARTUP

### (3) Status display list

The following table lists the servo statuses that may be shown. Refer to app. 5 for the measurement point.

Status display	Symbol	Unit	Description
Cumulative feedback pulses	C	pulse	Feedback pulses from the servo motor encoder are counted and displayed. The values in excess of $\pm 99999$ can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. Press the "SET" button to reset the display value to zero. The value of minus is indicated by the lit decimal points in the upper four digits.
Servo motor speed	r	r/min	The servo motor speed is displayed. It is displayed rounding off 0.1 r/min unit.
Droop pulses	E	pulse	The number of droop pulses in the deviation counter are displayed. The decimal points in the upper four digits are lit for reverse rotation pulses. The values in excess of $\pm 99999$ can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. The number of pulses displayed is in the encoder pulse unit.
Cumulative command pulses	P	pulse	Position command input pulses are counted and displayed. As the value displayed is not yet multiplied by the electronic gear (CMX/CDV), it may not match the indication of the cumulative feedback pulses. The values in excess of $\pm 99999$ can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. Press the "SET" button to reset the display value to zero. When the servo motor is rotating in the reverse direction, the decimal points in the upper four digits are lit.
Command pulse frequency	n	kpulse/s	The frequency of position command input pulses is counted and displayed. The value displayed is not multiplied by the electronic gear (CMX/CDV).
Analog speed command voltage	F	V	1) Torque control mode Input voltage of VLA (Analog speed limit) voltage is displayed.
Analog speed limit voltage			2) Speed control mode Input voltage of VC (Analog speed command) voltage is displayed
Analog torque command voltage	U	V	1) Position control mode and speed control mode Voltage of TLA (Analog torque limit) voltage is displayed.
Analog torque limit voltage			2) Torque control mode Voltage of TC (Analog torque command) voltage is displayed.
Regenerative load ratio	L	%	The ratio of regenerative power to permissible regenerative power is displayed in %.
Effective load ratio	J	%	The continuous effective load current is displayed. The effective value in the past 15 s is displayed relative to the rated current of 100 %.
Peak load ratio	b	%	The maximum occurrence torque is displayed. The highest value in the past 15 s is displayed relative to the rated current of 100 %.
Instantaneous torque	T	%	The instantaneous occurrence torque is displayed. The value of torque being occurred is displayed in real time considering a rated torque as 100%.
Within one-revolution position (1 pulse unit)	Cy1	pulse	Position within one revolution is displayed in encoder pulses. The values in excess of $\pm 99999$ can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits. When the servo motor rotates in the CCW direction, the value is added.
Within one-revolution position (1000 pulses unit)	Cy2	1000 pulses	The within one-revolution position is displayed in 1000 pulse increments of the encoder. When the servo motor rotates in the CCW direction, the value is added.
ABS counter	LS	rev	Travel distance from power on is displayed by counter value.
Load to motor inertia ratio	dC	Multiplier	The estimated ratio of the load inertia moment to the servo motor shaft inertia moment is displayed.

## 4. STARTUP

Status display	Symbol	Unit	Description
Bus voltage	Pn	V	The voltage of main circuit converter is displayed.
Internal temperature of encoder	ETh	°C	Inside temperature of encoder detected by the encoder is displayed.
Settling time	ST	ms	Settling time is displayed. When it exceeds 1000 ms, "1000" will be displayed.
Oscillation detection frequency	oF	Hz	Frequency at the time of oscillation detection is displayed.
Number of tough drive operations	Td	times	The number of tough drive functions activated is displayed.
Unit power consumption 1 (1 W unit)	PC1	W	Unit power consumption is displayed by increment of 1 W. Positive value indicate power running, and negative value indicate regeneration. The values in excess of ±99999 can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits.
Unit power consumption 2 (1 kW unit)	PC2	kW	Unit power consumption is displayed by increment of 1 kW. Positive value indicate power running, and negative value indicate regeneration.
Unit total power consumption 1 (1 Wh unit)	TPC1	Wh	Unit total power consumption is displayed by increment of 1 Wh. Positive value is cumulated during power running and negative value during regeneration. The values in excess of ±99999 can be counted. However, the counter shows only the lower five digits of the actual value since the servo amplifier display is five digits.
Unit total power consumption 2 (100 kWh unit)	TPC2	100 kWh	Unit total power consumption is displayed by increment of 100 kWh. Positive value is cumulated during power running and negative value during regeneration.

### (4) Changing the status display screen

The status display item of the servo amplifier display shown at power-on can be changed by changing [Pr. PC36] settings. The item displayed in the initial status changes with the control mode as follows.









Control mode	Status display
Position	Cumulative feedback pulses
Position/speed	Cumulative feedback pulses/servo motor speed
Speed	Servo motor speed
Speed/torque	Servo motor speed/analog torque command voltage
Torque	Analog torque command voltage
Torque/position	Analog torque command voltage/cumulative feedback pulses

## 4. STARTUP

### 4.5.4 Diagnostic mode

Name		Display	Description
Sequence			Not ready Indicates that the servo amplifier is being initialized or an alarm has occurred.
			Ready Indicates that the servo was switched on after completion of initialization and the servo amplifier is ready to operate.
Drive recorder enabled/disabled display			Drive recorder enabled When an alarm occurs in the status, the drive recorder will operate and write the status of occurrence.
			Drive recorder disabled The drive recorder will not operate on the following conditions. 1. You are using the graph function of MR Configurator2. 2. You are using the machine analyzer function. 3. [Pr. PF21] is set to "-1".
External I/O signal display		Refer to section 4.5.7.	This Indicates the on/off status of external I/O signal. The upper segments correspond to the input signals and the lower segments to the output signals.
Output signal (DO) forced output			This allows digital output signal to be switched on/off forcibly. For details, refer to section 4.5.8.
Test operation mode	JOG operation		JOG operation can be performed when there is no command from an external controller. For details, refer to section 4.5.9 (2).
	Positioning operation		Positioning operation can be performed when there is no command from an external controller. MR Configurator2 is required to perform positioning operation. For details, refer to section 4.5.9 (3).
	Motor-less operation		Without connecting the servo motor, this test operation mode enables to output signals and check the status display in response to the input device as if the servo motor is actually running. For details, refer to section 4.5.9 (4).
	Machine analyzer operation		Merely connecting the servo amplifier allows the resonance point of the mechanical system to be measured. MR Configurator2 is required to perform machine analyzer operation. Refer to section 11.4 for details.
	For manufacturer adjustment		This is for manufacturer adjustment.
	For manufacturer adjustment.		This is for manufacturer adjustment.

## 4. STARTUP


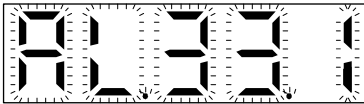

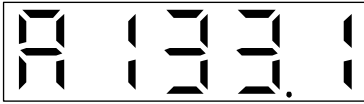
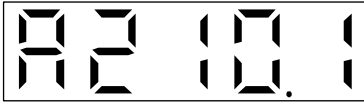


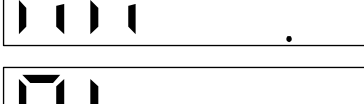

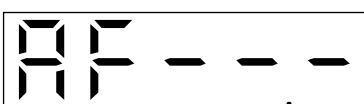

Name	Display	Description
Software version - Lower		Indicates the version of the software.
Software version - Upper		Indicates the system number of the software.
Automatic VC offset		<p>If offset voltages in the analog circuits inside and outside the servo amplifier cause the servo motor to rotate slowly at VC (Analog speed command) or VLA (Analog speed limit) of 0 V, this function automatically makes zero-adjustment of offset voltages.</p> <p>When using this function, enable the function in the following procedure. When it is enabled, [Pr. PC37] value changes to the automatically adjusted offset voltage.</p> <ol style="list-style-type: none"> <li>1) Push "SET" once.</li> <li>2) Set the number in the first digit to 1 with "UP".</li> <li>3) Push "SET".</li> </ol> <p>This function cannot be used if the input voltage of VC or VLA is -0.4 V or less, or +0.4 V or more. (Note)</p>
Servo motor series ID		<p>Push the "SET" button to show the series ID of the servo motor currently connected.</p> <p>For indication details, refer to app. 1 of "HG-KN/HG-SN servo Motor Instruction Manual".</p>
Servo motor type ID		<p>Push the "SET" button to show the type ID of the servo motor currently connected.</p> <p>For indication details, refer to app. 1 of "HG-KN/HG-SN servo Motor Instruction Manual".</p>
Servo motor encoder ID		<p>Push the "SET" button to show the encoder ID of the servo motor currently connected.</p> <p>For indication details, refer to app. 1 of "HG-KN/HG-SN servo Motor Instruction Manual".</p>
For manufacturer adjustment		This is for manufacturer adjustment.
For manufacturer adjustment		This is for manufacturer adjustment.

Note. Even if Automatic VC offset is performed and 0 V is input, the servo motor may not completely stop due to an internal error. To completely stop the servo motor, switch off ST1 or ST2.

## 4. STARTUP

### 4.5.5 Alarm mode

The current alarm, past alarm history and parameter error are displayed. The lower 3 digits on the display indicate the alarm number that has occurred or the parameter number in error.

Name	Display	Description
Current alarm		Indicates no occurrence of an alarm.
		Indicates the occurrence of [AL. 33.1 Main circuit voltage error]. Flickers at alarm occurrence.
Alarm history		Indicates that the last alarm is [AL. 50.1 Thermal overload error 1 during operation].
		Indicates the second last alarm is [AL. 33.1 Main circuit voltage error].
		Indicates the third last alarm is [AL. 10.1 Voltage drop in the power].
		Indicates that there is no tenth alarm in the past.
		Indicates that there is no eleventh alarm in the past.
		Indicates that there is no twelfth alarm in the past.
		Indicates that there is no sixteenth alarm in the past.
Parameter error No.		This indicates no occurrence of [AL. 37 Parameter error].
		The data content error of [Pr. PA12 Reverse rotation torque limit].

## 4. STARTUP

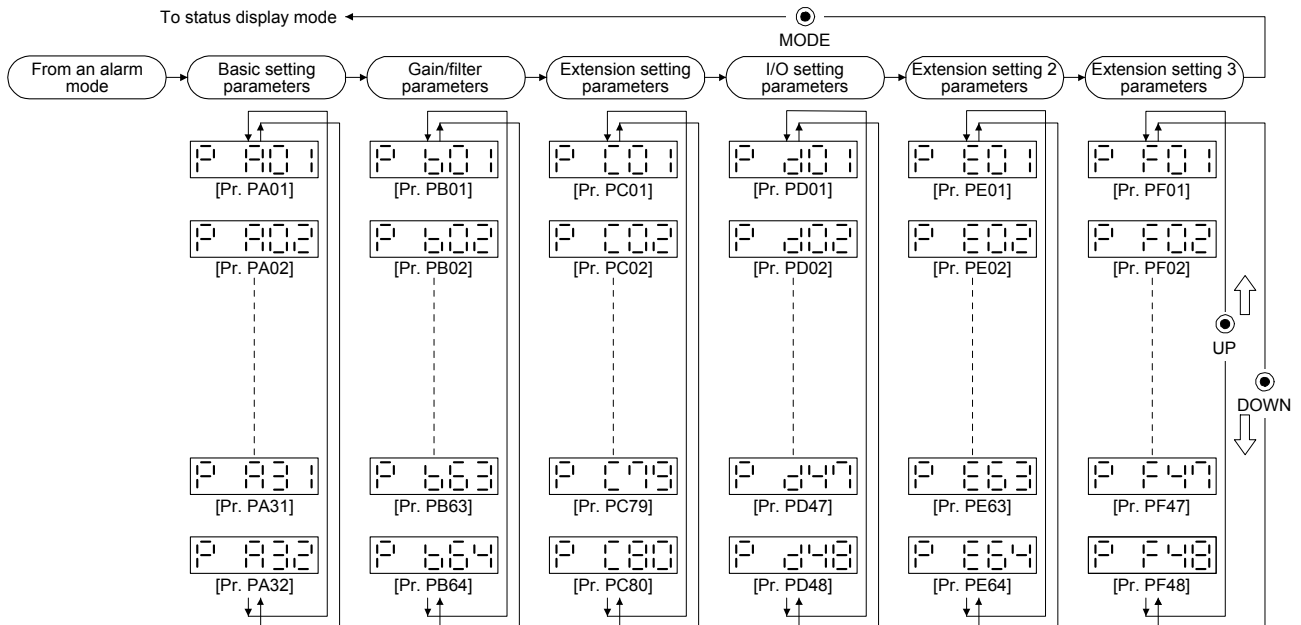
Functions at occurrence of an alarm

- (1) Any mode screen displays the current alarm.
- (2) Even during alarm occurrence, the other screen can be viewed by pressing the button in the operation area. At this time, the decimal point in the fourth digit remains flickering.
- (3) For any alarm, remove its cause and clear it in any of the following methods. (Refer to chapter 8 for the alarms that can be cleared.)
  - (a) Switch power off, then on.
  - (b) Push the "SET" button on the current alarm screen.
  - (c) Turn on RES (Reset).
- (4) Use [Pr. PC18] to clear the alarm history.
- (5) Push "UP" or "DOWN" to move to the next history.

### 4.5.6 Parameter mode

#### (1) Parameter mode transition

After selecting the corresponding parameter mode with the "MODE" button, pushing the "UP" or "DOWN" button changes the display as shown below.

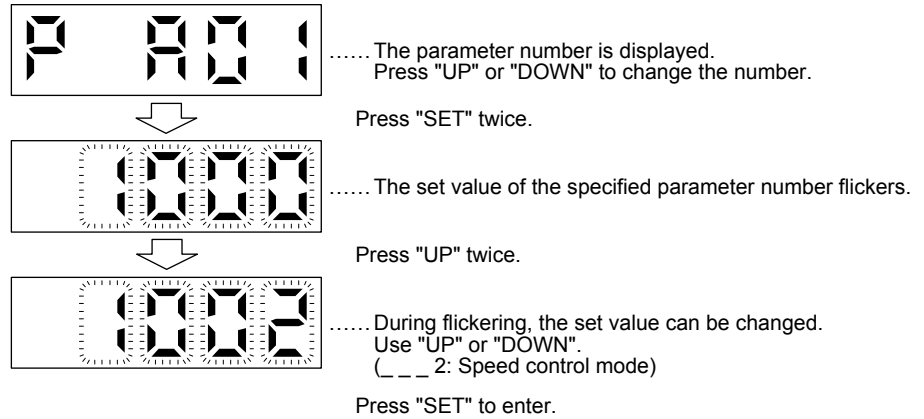


## 4. STARTUP

### (2) Operation example

#### (a) Parameters of 5 or less digits

The following example shows the operation procedure performed after power-on to change the control mode to the speed control mode with [Pr. PA01 Operation mode]. Press "MODE" to switch to the basic setting parameter screen.

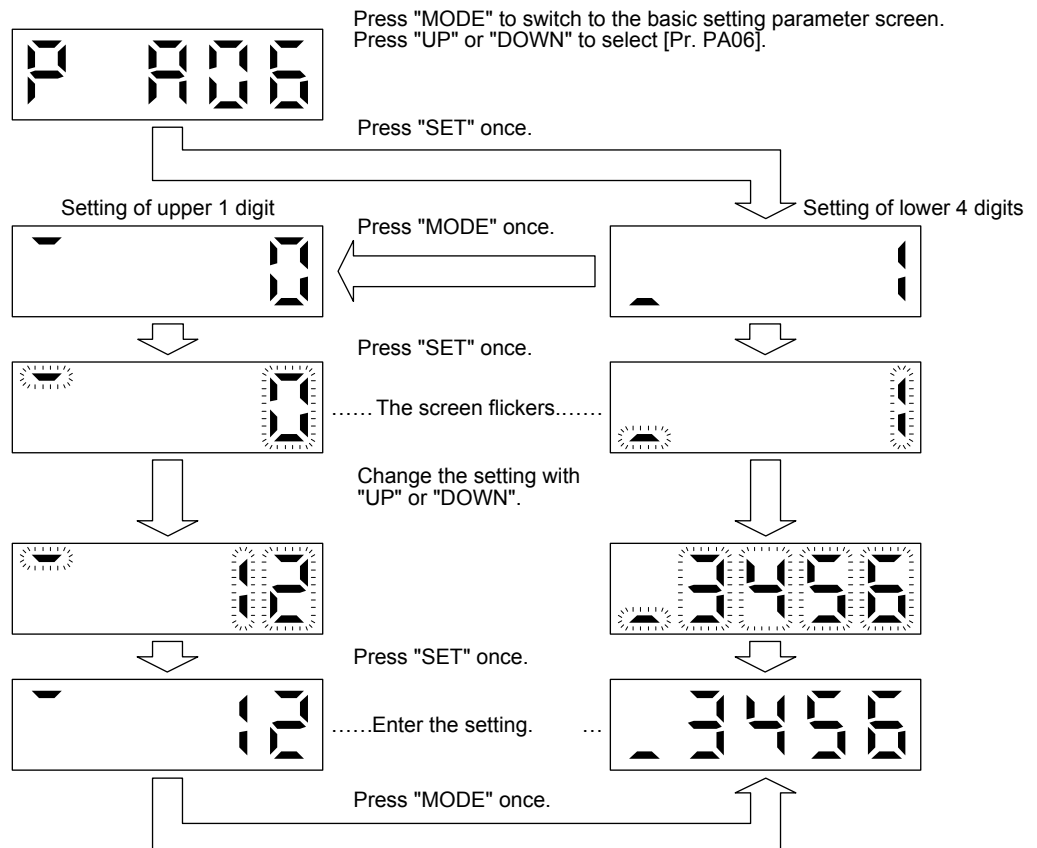


To shift to the next parameter, press the "UP" or "DOWN" button.

When changing the [Pr. PA01] setting, change its set value, then switch power off once and switch it on again to enable the new value.

#### (b) Parameters of 6 or more digits

The following example gives the operation procedure to change the electronic gear numerator to "123456" with [Pr. PA06 Electronic gear numerator].





## 4. STARTUP

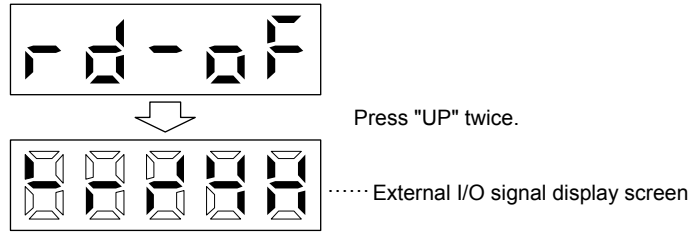
### 4.5.7 External I/O signal display

POINT
<p>● The I/O signal settings can be changed using the I/O setting parameters [Pr. PD03] to [Pr. PD28].</p>

The on/off states of the digital I/O signals connected to the servo amplifier can be confirmed.

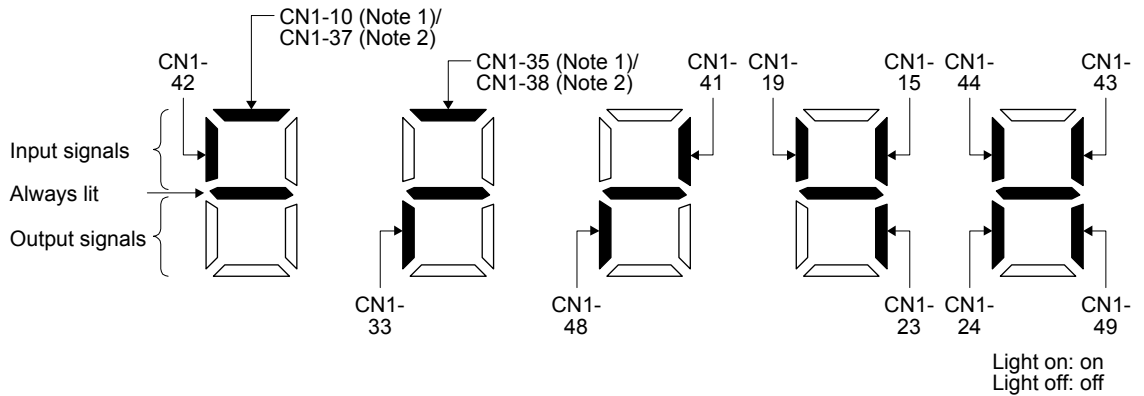
#### (1) Operation

The display screen at power-on. Using the "MODE" button, display the diagnostic screen.



#### (2) Display definition

The 7-segment LED segments and CN1 connector pins correspond as shown below.



Note 1. This is available with servo amplifiers with software version B7 or later.

Note 2. This is available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later.

The LED segment corresponding to the pin is lit to indicate on, and is extinguished to indicate off.

The signals corresponding to the pins in the respective control modes are indicated below.

## 4. STARTUP

### (a) Control modes and I/O signals

Connector	Pin No.	Signal input/output (Note 1) I/O	(Note 2) Symbols of I/O signals in control modes						Related parameter
			P	P/S	S	S/T	T	T/P	
CN1	10	I	PP	PP/-	(Note 4)	(Note 4)	(Note 4)	-/PP	PD43/PD44 (Note 3)
	15	I	SON	SON	SON	SON	SON	SON	PD03/PD04
	16								
	17								
	18								
	19	I	RES	RES/ST1	ST1	ST1/RS2	RS2	RS2/RES	PD11/PD12
	22								
	23	O	ZSP	ZSP	ZSP	ZSP	ZSP	ZSP	PD24
	24	O	INP	INP/SA	SA	SA/-		-/INP	PD25
	25								
	33	O	OP	OP	OP	OP	OP	OP	
	35	I	NP	NP/-	(Note 4)	(Note 4)	(Note 4)	-/NP	PD45/PD46 (Note 3)
	37 (Note 6)	I	PP2	PP2/-	(Note 5)	(Note 5)	(Note 5)	-/PP2	PD43/PD44 (Note 3)
	38 (Note 6)	I	NP2	NP2/-	(Note 5)	(Note 5)	(Note 5)	-/NP2	PD45/PD46 (Note 3)
	41	I	CR	CR/ST2	ST2	ST2/RS1	RS1	RS1/CR	PD13/PD14
	42	I	EM2	EM2	EM2	EM2	EM2	EM2	
	43	I	LSP	LSP	LSP	LSP/-		-/LSP	PD17/PD18
44	I	LSN	LSN	LSN	LSN/-		-/LSN	PD19/PD20	
45									
48	O	ALM	ALM	ALM	ALM	ALM	ALM		
49	O	RD	RD	RD	RD	RD	RD	PD28	

Note 1. I: input signal, O: output signal

2. P: position control mode, S: speed control mode, T: torque control mode

P/S: position/speed control switching mode, S/T: speed/torque control switching mode, T/P: torque/position switching mode

3. This is available with servo amplifiers with software version B7 or later.

4. This is available as an input device of sink interface. Input devices are not assigned by default. Assign the input devices with [Pr. PD43] to [Pr. PD46] as necessary. In addition, supply + of 24 DC V to the CN1-12 pin. This is available with servo amplifiers with software version B7 or later.

5. This is available as an input device of source interface. Input devices are not assigned by default. Assign the input devices with [Pr. PD43] to [Pr. PD46] as necessary.

6. These pins are available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later.

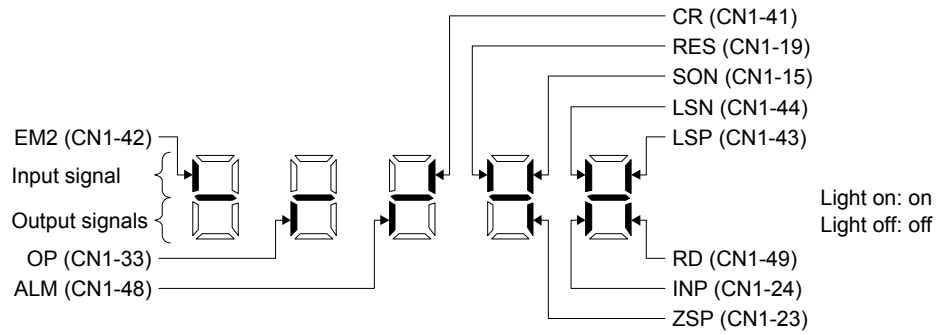
### (b) Symbol and signal names

Symbol	Signal name	Symbol	Signal name
SON	Servo-on	RES	Reset
LSP	Forward rotation stroke end	EM2	Forced stop 2
LSN	Reverse rotation stroke end	LOP	Control switching
CR	Clear	TLC	Limiting torque
SP1	Speed selection 1	VLC	Limiting speed
SP2	Speed selection 2	RD	Ready
PC	Proportion control	ZSP	Zero speed detection
ST1	Forward rotation start	INP	In-position
ST2	Reverse rotation start	SA	Speed reached
RS1	Forward rotation selection	ALM	Malfunction
RS2	Reverse rotation selection	OP	Encoder Z-phase pulse (open collector)
TL	External torque limit selection		

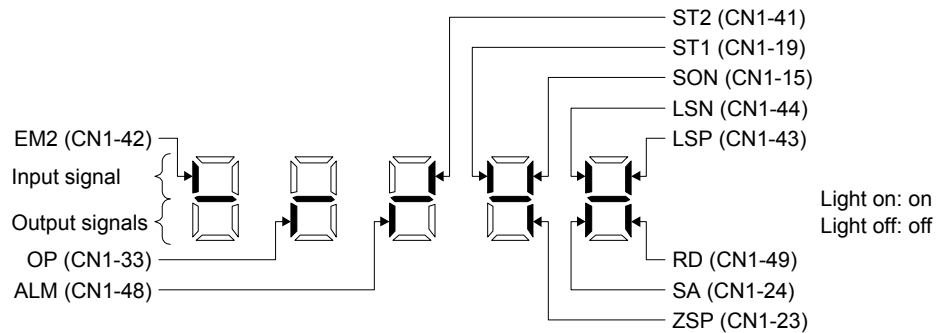
## 4. STARTUP

### (3) Display data at initial values

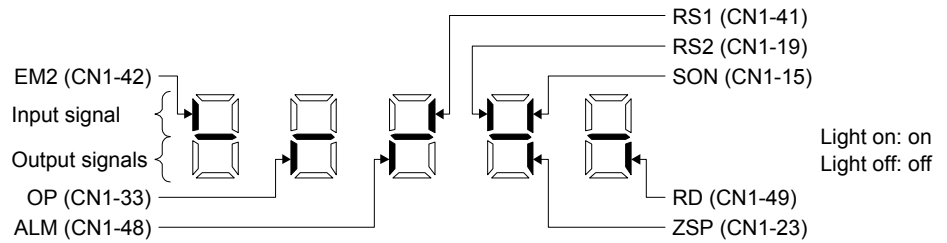
#### (a) Position control mode



#### (b) Speed control mode



#### (c) Torque control mode



## 4. STARTUP

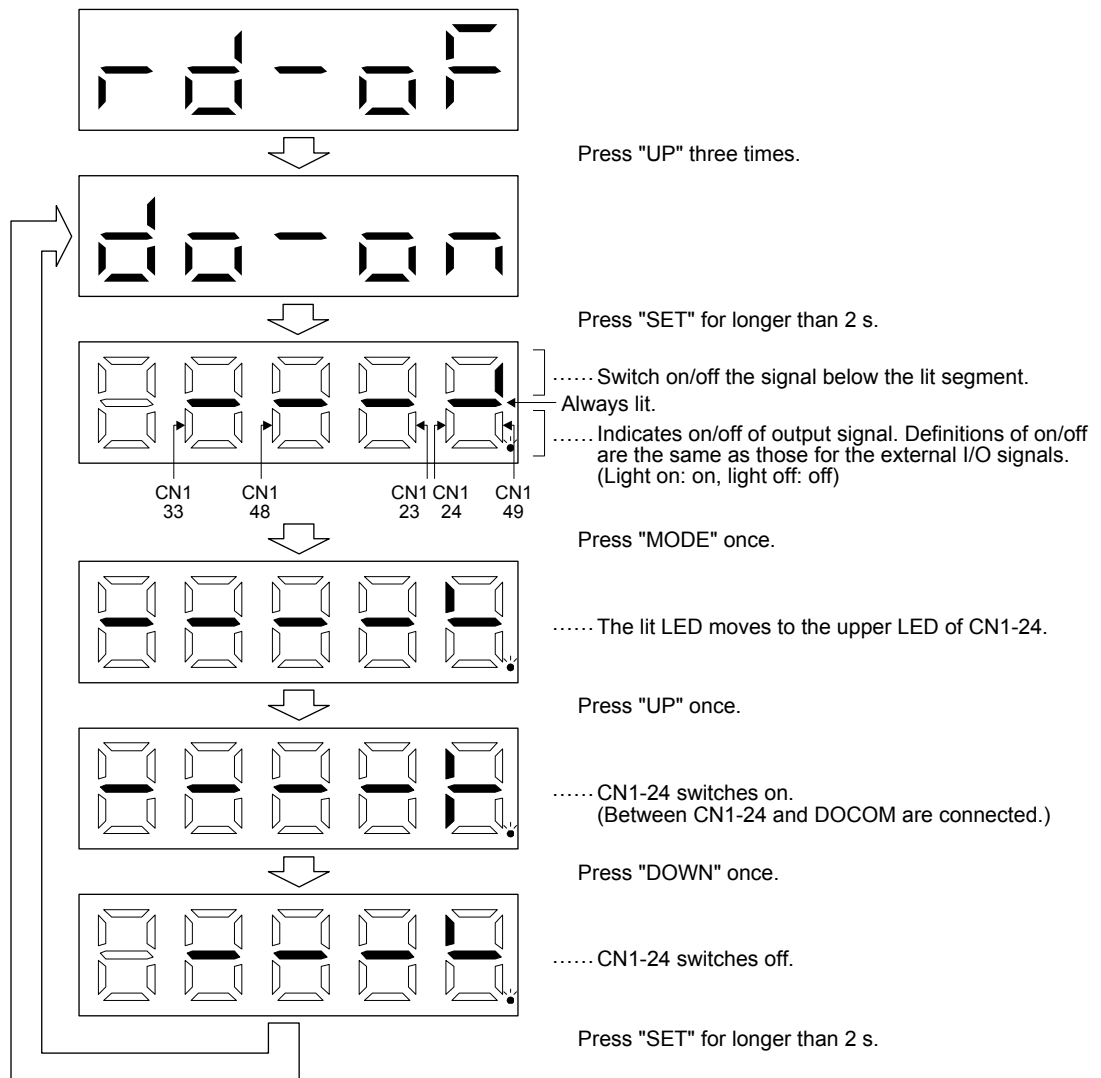
### 4.5.8 Output signal (DO) forced output

POINT
<p>● When the servo system is used in a vertical lift application, turning on MBR (Electromagnetic brake interlock) by the DO forced output after assigning it to connector CN1 will release the electromagnetic brake, causing a drop. Take drop preventive measures on the machine side.</p>

Output signals can be switched on/off forcibly independently of the servo status. Use this function for output signal wiring check, etc. This operation must be performed in the servo off state by turning off SON (Servo-on).

#### Operation

The display screen at power-on. Using the "MODE" button, display the diagnostic screen.



## 4. STARTUP

### 4.5.9 Test operation mode



#### CAUTION

- The test operation mode is designed for checking servo operation. Do not use it for actual operation.
- If the servo motor operates unexpectedly, use EM2 (Forced stop 2) to stop it.

#### POINT

- MR Configurator2 is required to perform positioning operation.
- Test operation cannot be performed if SON (Servo-on) is not turned off.

#### (1) Mode switching

The display screen at power-on. Select JOG operation or motor-less operation in the following procedure. Using the "MODE" button, display the diagnostic screen.



Press "UP" four times.



Press "SET" for longer than 2 s.

..... When this screen appears,  
JOG operation can be performed.

↑ Flickers in the test operation mode.

## 4. STARTUP

### (2) JOG operation

POINT	<p>● When performing JOG operation, turn on EM2, LSP and LSN. LSP and LSN can be set to automatic on by setting [Pr. PD01] to "_ C _ _".</p>
-------	--

JOG operation can be performed when there is no command from the controller.

#### (a) Operation

The servo motor rotates while holding down the "UP" or the "DOWN" button. The servo motor stops rotating by releasing the button. The operation condition can be changed using MR Configurator2. The initial operation condition and setting range for operation are listed below.

Item	Initial setting	Setting range
Speed [r/min]	200	0 to permissible instantaneous speed
Acceleration/deceleration time constant [ms]	1000	0 to 50000

The following table shows how to use the buttons.

Button	Description
"UP"	Press to start CCW rotation. Release to stop.
"DOWN"	Press to start CW rotation. Release to stop.

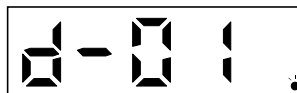
If the USB cable is disconnected during JOG operation using the MR Configurator2, the servo motor decelerates to a stop.

#### (b) Status display

Press the "MODE" button in the JOG operation-ready status to call the status display screen. When the JOG operation is performed using the "UP" or "DOWN" button, the servo status is displayed during the JOG operation. Every time the "MODE" button is pressed, the next status display screen appears. When one cycle of the screen display is complete, it returns to the JOG operation-ready status screen. Refer to section 4.5.3 for details of status display. Note that the status display screen cannot be changed by the "UP" or "DOWN" button during the JOG operation.

#### (c) Termination of JOG operation

To end the JOG operation, shut the power off once, or press the "MODE" button to switch to the next screen, and then hold down the "SET" button for 2 s or longer.



## 4. STARTUP

### (3) Positioning operation

POINT
<ul style="list-style-type: none"> <li>● MR Configurator2 is required to perform positioning operation.</li> <li>● Turn on EM2 (forced stop 2) when performing positioning operation.</li> </ul>

Positioning operation can be performed when there is no command from the controller.

#### (a) Operation

The screenshot shows the 'Positioning Mode' window with various parameters and controls. Labels a) through m) point to specific elements: a) Motor speed, b) Accel./decel. time constant, c) Move distance, d) LSP, LSN auto ON checkbox, e) Z-phase signal movement checkbox, f) Move distance unit radio buttons, g) Make the repeated operation valid checkbox, h) Forward CCW(F) and Reverse CW(R) buttons, i) Pause button, j) Stop button, k) Forced Stop button, l) Operating status and Operation count fields, m) Axis 1 dropdown menu.

#### a) Motor speed [r/min]

Enter the servo motor speed into the "Motor speed" input field.

#### b) Acceleration/deceleration time constant [ms]

Enter the acceleration/deceleration time constant into the "Accel/decel time" input field.

#### c) Travel distance [pulse]

Enter the travel distance into the "Travel distance" input field.

#### d) LSP/LSN are automatically turned on

When setting the external stroke signal to automatic on, click the check box to enable it. When it is not selected, turn on LSP and LSN externally.

#### e) Move till Z-phase signal

Travel is made until the travel distance is reached and the first Z-phase signal in the travelling direction turns on.

## 4. STARTUP

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f) Travel distance unit selection

Select with the option buttons whether the travel distance set in c) is in the command pulse unit or in the encoder pulse unit.

When the command input pulse unit is selected, the value, which is the set travel distance multiplied by the electronic gear, will be the command value. When the encoder pulse unit is selected, the travel distance is not multiplied by the electronic gear.

g) Enable repeat operation

To perform repeat operation, click the check. The initial setting and setting range for the repeat operation are listed below.

Item	Initial setting	Setting range
Repeat pattern	Fwd. rot. (CCW) to rev. rot. (CW)	Fwd. rot. (CCW) to rev. rot. (CW) Fwd. rot. (CCW) to fwd. rot. (CCW) Rev. rot. (CW) to fwd. rot. (CCW) Rev. rot. (CW) to rev. rot. (CW)
Dwell time [s]	2.0	0.1 to 50.0
Number of operations [times]	1	1 to 9999

To perform continuous operation with the repeat pattern and dwell time settings, which are set by referring to the above table, click the check box of "Make the aging function enabled".

h) Forward/reverse the servo motor

Click "Forward CCW" to rotate the servo motor in the forward rotation direction.

Click "Reverse CW" to rotate the servo motor in the reverse rotation direction.

i) Pause the servo motor

Click "Pause" during servo motor rotation to temporarily stop the servo motor.

"Pause" is enabled during servo motor rotation.

j) Stop the servo motor

Click "Stop" during servo motor rotation to stop the servo motor.

k) Forced stop

Click "Forced stop" during servo motor rotation to make a sudden stop.

"Forced stop" is enabled during servo motor rotation.

l) Operation status

The operation status during the repeat operation, and the number of operations are displayed

m) Axis No.

Axis No. in operation is displayed.

n) Termination of positioning operation window

Click "X" to cancel the positioning operation mode and close the window.

(b) Status display

The status display can be checked during positioning operation.



## 4. STARTUP

---

### (4) Motor-less operation

Without connecting the servo motor, output signals or status display can be provided in response to the input device as if the servo motor is actually running. This operation can be used to check the sequence of a controller or the like.

#### (a) Start of motor-less operation

After setting "\_\_\_ 1" in [Pr. PC60], cycle the power. After that, perform external operation as in ordinary operation.

#### (b) Termination of motor-less operation

To terminate the motor-less operation, set [Pr. PC60] to "\_\_\_ 0" and then turn the power off.

### (5) Program operation

Positioning operation can be performed in two or more operation patterns combined, without using a controller. Use this operation with the forced stop reset. This operation may be used independently of whether servo-on or servo-off and whether a controller is connected or not.

Exercise control on the program operation screen of MR Configurator2. For full information, refer to the MR Configurator2 Installation Guide.

Operation	Screen control
Start	Click "Operation start".
Stop	Click "Stop".
Forced stop	Click "Forced Stop".

### (6) Output signal (DO) forced output

Output signals can be switched on/off forcibly independently of the servo status. This function is used for output signal wiring check, etc. Exercise control on the DO forced output screen of MR Configurator2.

## 5. PARAMETERS

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### 5. PARAMETERS

#### CAUTION

- Never make a drastic adjustment or change to the parameter values as doing so will make the operation unstable.
- Do not change the parameter settings as described below. Doing so may cause an unexpected condition, such as failing to start up the servo amplifier.
  - Changing the values of the parameters for manufacturer setting
  - Setting a value out of the range
  - Changing the fixed values in the digits of a parameter

#### 5.1 Parameter list

POINT
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- To enable a parameter whose symbol is preceded by \*, turn off the power for 1 s or more after setting and turn it on again. However, the time will be longer depending on a setting value of [Pr. PF25 instantaneous power failure tough drive - detection time] when "Instantaneous power failure tough drive selection" is enabled in [Pr. PA20].
- The symbols in the control mode column mean as follows.
  - P: Position control mode
  - S: Speed control mode
  - T: Torque control mode

## 5. PARAMETERS

### 5.1.1 Basic setting parameters ([Pr. PA\_ \_])

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PA01	*STY	Operation mode	1000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA02	*REG	Regenerative option	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA03		For manufacturer setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA04	*AOP1	Function selection A-1	2000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA05	*FBP	Number of command input pulses per revolution	10000		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA06	CMX	Electronic gear numerator (command pulse multiplication numerator)	1		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA07	CDV	Electronic gear denominator (command pulse multiplication denominator)	1		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA08	ATU	Auto tuning mode	0001h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA09	RSP	Auto tuning response	16		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA10	INP	In-position range	100	[pulse]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA11	TLP	Forward rotation torque limit	100.0	[%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA12	TLN	Reverse rotation torque limit	100.0	[%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA13	*PLSS	Command pulse input form	0100h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA14	*POL	Rotation direction selection	0		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA15	*ENR	Encoder output pulses	4000	[pulse/rev]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA16	*ENR2	Encoder output pulses 2	1		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA17		For manufacturer setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA18			0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA19	*BLK	Parameter writing inhibit	00AAh		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA20	*TDS	Tough drive setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA21	*AOP3	Function selection A-3	0001h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA22		For manufacturer setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA23	DRAT	Drive recorder arbitrary alarm trigger setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA24	AOP4	Function selection A-4	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA25	OTHOV	One-touch tuning - Overshoot permissible level	0	[%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA26	*AOP5	Function selection A-5	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA27		For manufacturer setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA28	*AOP6	Function selection A-6	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA29		For manufacturer setting	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA30			0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA31			0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA32			0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

### 5.1.2 Gain/filter setting parameters ([Pr. PB\_ \_])

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PB01	FILT	Adaptive tuning mode (adaptive filter II)	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB02	VRFT	Vibration suppression control tuning mode (advanced vibration suppression control II)	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB03	PST	Position command acceleration/deceleration time constant (position smoothing)	0	[ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB04	FFC	Feed forward gain	0	[%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB05		For manufacturer setting	500		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB06	GD2	Load to motor inertia ratio	7.00	[Multiplier]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB07	PG1	Model loop gain	15.0	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB08	PG2	Position loop gain	37.0	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB09	VG2	Speed loop gain	823	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB10	VIC	Speed integral compensation	33.7	[ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB11	VDC	Speed differential compensation	980		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB12	OVA	Overshoot amount compensation	0	[%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB13	NH1	Machine resonance suppression filter 1	4500	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB14	NHQ1	Notch shape selection 1	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB15	NH2	Machine resonance suppression filter 2	4500	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

## 5. PARAMETERS

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PB16	NHQ2	Notch shape selection 2	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB17	NHF	Shaft resonance suppression filter	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB18	LPF	Low-pass filter setting	3141	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB19	VRF11	Vibration suppression control 1 - Vibration frequency	100.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB20	VRF12	Vibration suppression control 1 - Resonance frequency	100.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB21	VRF13	Vibration suppression control 1 - Vibration frequency damping	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB22	VRF14	Vibration suppression control 1 - Resonance frequency damping	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB23	VFBF	Low-pass filter selection	0100h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB24	*MVS	Slight vibration suppression control	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB25	*BOP1	Function selection B-1	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB26	*CDP	Gain switching function	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB27	CDL	Gain switching condition	10	[kpulse/s]/ [pulse]/ [r/min]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB28	CDT	Gain switching time constant	1	[ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB29	GD2B	Load to motor inertia ratio after gain switching	7.00	[Multiplier]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB30	PG2B	Position loop gain after gain switching	0.0	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB31	VG2B	Speed loop gain after gain switching	0	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB32	VICB	Speed integral compensation after gain switching	0.0	[ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB33	VRF1B	Vibration suppression control 1 - Vibration frequency after gain switching	0.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB34	VRF2B	Vibration suppression control 1 - Resonance frequency after gain switching	0.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB35	VRF3B	Vibration suppression control 1 - Vibration frequency damping after gain switching	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB36	VRF4B	Vibration suppression control 1 - Resonance frequency damping after gain switching	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB37		For manufacturer setting	1600				
PB38			0.00				
PB39			0.00				
PB40			0.00				
PB41			0000h				
PB42			0000h				
PB43			0000h				
PB44			0.00				
PB45	CNHF	Command notch filter	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB46	NH3	Machine resonance suppression filter 3	4500	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB47	NHQ3	Notch shape selection 3	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB48	NH4	Machine resonance suppression filter 4	4500	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB49	NHQ4	Notch shape selection 4	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB50	NH5	Machine resonance suppression filter 5	4500	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB51	NHQ5	Notch shape selection 5	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB52	VRF21	Vibration suppression control 2 - Vibration frequency	100.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB53	VRF22	Vibration suppression control 2 - Resonance frequency	100.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB54	VRF23	Vibration suppression control 2 - Vibration frequency damping	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB55	VRF24	Vibration suppression control 2 - Resonance frequency damping	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB56	VRF21B	Vibration suppression control 2 - Vibration frequency after gain switching	0.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB57	VRF22B	Vibration suppression control 2 - Resonance frequency after gain switching	0.0	[Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB58	VRF23B	Vibration suppression control 2 - Vibration frequency damping after gain switching	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB59	VRF24B	Vibration suppression control 2 - Resonance frequency damping after gain switching	0.00		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB60	PG1B	Model loop gain after gain switching	0.0	[rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB61		For manufacturer setting	0.0				
PB62			0000h				
PB63			0000h				
PB64			0000h				

## 5. PARAMETERS

### 5.1.3 Extension setting parameters ([Pr. PC\_ \_ ])

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PC01	STA	Acceleration time constant	0	[ms]	/	○	○
PC02	STB	Deceleration time constant	0	[ms]	/	○	○
PC03	STC	S-pattern acceleration/deceleration time constant	0	[ms]	/	○	○
PC04	TQC	Torque command time constant	0	[ms]	/	/	○
PC05	SC1	Internal speed command 1	100	[r/min]	/	○	/
		Internal speed limit 1			/	/	○
PC06	SC2	Internal speed command 2	500	[r/min]	/	○	/
		Internal speed limit 2			/	/	○
PC07	SC3	Internal speed command 3	1000	[r/min]	/	○	/
		Internal speed limit 3			/	/	○
PC08	SC4	Internal speed command 4	200	[r/min]	/	○	/
		Internal speed limit 4			/	/	○
PC09	SC5	Internal speed command 5	300	[r/min]	/	○	/
		Internal speed limit 5			/	/	○
PC10	SC6	Internal speed command 6	500	[r/min]	/	○	/
		Internal speed limit 6			/	/	○
PC11	SC7	Internal speed command 7	800	[r/min]	/	○	/
		Internal speed limit 7			/	/	○
PC12	VCM	Analog speed command - Maximum speed	0	[r/min]	/	○	/
		Analog speed limit - Maximum speed			/	/	○
PC13	TLC	Analog torque command maximum output	100.0	[%]	/	/	○
PC14	MOD1	Analog monitor 1 output	0000h	/	○	○	○
PC15	MOD2	Analog monitor 2 output	0001h	/	○	○	○
PC16	MBR	Electromagnetic brake sequence output	0	[ms]	○	○	○
PC17	ZSP	Zero speed	50	[r/min]	○	○	○
PC18	*BPS	Alarm history clear	0000h	/	○	○	○
PC19	*ENRS	Encoder output pulse selection	0000h	/	○	○	○
PC20	*SNO	Station number setting (Note)	0	[Station]	○	○	○
PC21	*SOP	RS-422 communication function selection (Note)	0000h	/	○	○	○
PC22	*COP1	Function selection C-1	0020h	/	○	○	○
PC23	*COP2	Function selection C-2	0000h	/	/	○	○
PC24	*COP3	Function selection C-3	0000h	/	○	/	/
PC25	/	For manufacturer setting	0000h	/	/	/	/
PC26	*COP5	Function selection C-5	0000h	/	○	○	/
PC27	*COP6	Function selection C-6	0000h	/	○	○	○
PC28	/	For manufacturer setting	0000h	/	/	/	/
PC29	/		0000h	/	/	/	/
PC30	STA2	Acceleration time constant 2	0	[ms]	/	○	○
PC31	STB2	Deceleration time constant 2	0	[ms]	/	○	○
PC32	CMX2	Command input pulse multiplication numerator 2	1	/	○	/	/
PC33	CMX3	Command input pulse multiplication numerator 3	1	/	○	/	/
PC34	CMX4	Command input pulse multiplication numerator 4	1	/	○	/	/
PC35	TL2	Internal torque limit 2	100.0	[%]	○	○	○
PC36	*DMD	Status display selection	0000h	/	○	○	○
PC37	VCO	Analog speed command offset	0	[mV]	/	○	/
		Analog speed limit offset			/	/	○
PC38	TPO	Analog torque command offset	0	[mV]	/	/	○
		Analog torque limit offset			/	/	○
PC39	MO1	Analog monitor 1 offset	0	[mV]	○	○	○
PC40	MO2	Analog monitor 2 offset	0	[mV]	○	○	○
PC41	/	For manufacturer setting	0	/	/	/	/
PC42	/		0	/	/	/	/
PC43	ERZ	Error excessive alarm level	0	[rev]	○	/	/

Note. This parameter is supported by servo amplifier manufactured in December 2013 or later.

## 5. PARAMETERS

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PC44		For manufacturer setting	0000h				
PC45			0000h				
PC46			0				
PC47			0				
PC48			0				
PC49			0				
PC50			0000h				
PC51	RSBR	Forced stop deceleration time constant	100	[ms]	<input type="radio"/>	<input type="radio"/>	<input type="checkbox"/>
PC52		For manufacturer setting	0				
PC53			0				
PC54	RSUP1	Vertical axis freefall prevention compensation amount	0	[0.0001rev]	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
PC55		For manufacturer setting	0				
PC56			100				
PC57			0000h				
PC58			0				
PC59			0000h				
PC60	*COPD	Function selection C-D	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC61		For manufacturer setting	0000h				
PC62			0000h				
PC63			0000h				
PC64			0000h				
PC65			0000h				
PC66			0				
PC67			0				
PC68			0				
PC69			0				
PC70			0				
PC71			0040h				
PC72			0000h				
PC73	ERW	Error excessive warning level	0	[rev]	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
PC74		For manufacturer setting	0000h				
PC75			0000h				
PC76			0000h				
PC77			0000h				
PC78			0000h				
PC79			0000h				
PC80			0000h				

### 5.1.4 I/O setting parameters ([Pr. PD\_ \_])

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PD01	*DIA1	Input signal automatic on selection 1	0000h		<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PD02		For manufacturer setting	0000h				
PD03			*DI1L				
PD04	*DI1H	Input device selection 1H	0202h		<input type="checkbox"/>	<input type="checkbox"/>	<input type="radio"/>
PD05		For manufacturer setting	0000h				
PD06			0000h				
PD07			0000h				
PD08			0000h				
PD09			0000h				
PD10			0000h				
PD11	*DI5L	Input device selection 5L	0703h		<input type="radio"/>	<input type="radio"/>	<input type="checkbox"/>
PD12	*DI5H	Input device selection 5H	3807h		<input type="checkbox"/>	<input type="checkbox"/>	<input type="radio"/>
PD13	*DI6L	Input device selection 6L	0806h		<input type="radio"/>	<input type="radio"/>	<input type="checkbox"/>
PD14	*DI6H	Input device selection 6H	3908h		<input type="checkbox"/>	<input type="checkbox"/>	<input type="radio"/>

## 5. PARAMETERS

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PD15		For manufacturer setting	0000h				
PD16			0000h				
PD17	*DI8L	Input device selection 8L	0A0Ah		○	○	
PD18	*DI8H	Input device selection 8H	0700h				○
PD19	*DI9L	Input device selection 9L	0B0Bh		○	○	
PD20	*DI9H	Input device selection 9H	0800h				○
PD21		For manufacturer setting	0000h				
PD22			0000h				
PD23			0000h				
PD24	*DO2	Output device selection 2	000Ch		○	○	○
PD25	*DO3	Output device selection 3	0004h		○	○	○
PD26		For manufacturer setting	0000h				
PD27			0003h				
PD28	*DO6	Output device selection 6	0002h		○	○	○
PD29	*DIF	Input filter setting	0004h		○	○	○
PD30	*DOP1	Function selection D-1	0000h		○	○	○
PD31		For manufacturer setting	0000h				
PD32			*DOP3				
PD33		For manufacturer setting	0000h				
PD34			DOP5				
PD35		For manufacturer setting	0000h				
PD36			0000h				
PD37			0000h				
PD38			0				
PD39			0				
PD40			0				
PD41			0000h				
PD42			0000h				
PD43	*DI11L	Input device selection 11L	0000h			○	
PD44	*DI11H	Input device selection 11H	2000h				○
PD45	*DI12L	Input device selection 12L	0000h			○	
PD46	*DI12H	Input device selection 12H	2B00h				○
PD47		For manufacturer setting	0000h				
PD48			0000h				

### 5.1.5 Extension setting 2 parameters ([Pr. PE\_\_])

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PE01		For manufacturer setting	0000h				
PE02			0000h				
PE03			0000h				
PE04			0				
PE05			0				
PE06			0				
PE07			0				
PE08			0				
PE09			0000h				
PE10			0000h				
PE11			0000h				
PE12			0000h				
PE13			0000h				
PE14			0111h				
PE15			20				
PE16			0000h				
PE17			0000h				

## 5. PARAMETERS

No.	Symbol	Name	Initial value	Unit	Control mode		
					P	S	T
PE18		For manufacturer setting	0000h				
PE19			0000h				
PE20			0000h				
PE21			0000h				
PE22			0000h				
PE23			0000h				
PE24			0000h				
PE25			0000h				
PE26			0000h				
PE27			0000h				
PE28			0000h				
PE29			0000h				
PE30			0000h				
PE31			0000h				
PE32			0000h				
PE33			0000h				
PE34			0				
PE35			0				
PE36			0.0				
PE37			0.00				
PE38			0.00				
PE39			0				
PE40			0000h				
PE41	EOP3	Function selection E-3	0000h				○ ○ ○
PE42		For manufacturer setting	0				
PE43			0.0				
PE44	LMCP	Lost motion compensation positive-side compensation value selection	0	[0.01%]	○		
PE45	LMCN	Lost motion compensation negative-side compensation value selection	0	[0.01%]	○		
PE46	LMFLT	Lost motion filter setting	0	[0.1 ms]	○		
PE47	TOF	Torque offset	0	[0.01%]	○	○	○
PE48	*LMOP	Lost motion compensation function selection	0000h		○		
PE49	LMCD	Lost motion compensation timing	0	[0.1 ms]	○		
PE50	LMCT	Lost motion compensation non-sensitive band	0	[pulse]/ [kpulse]	○		
PE51		For manufacturer setting	0000h				
PE52			0000h				
PE53			0000h				
PE54			0000h				
PE55			0000h				
PE56			0000h				
PE57			0000h				
PE58			0000h				
PE59			0000h				
PE60			0000h				
PE61			0.00				
PE62			0.00				
PE63			0.00				
PE64			0.00				



## 5. PARAMETERS

### 5.1.6 Extension setting 3 parameters ([Pr. PF\_\_])

No.	Symbol	Name	Initial value	Unit	Control mode					
					P	S	T			
PF01		For manufacturer setting	0000h							
PF02			0000h							
PF03			0000h							
PF04			0							
PF05			0							
PF06			0000h							
PF07			1							
PF08			1							
PF09	*FOP5	Function selection F-5	0000h				<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	
PF10			0000h							
PF11			0000h							
PF12			10000							
PF13			100							
PF14			100							
PF15			2000							
PF16			0000h							
PF17			10							
PF18			0000h							
PF19			0000h							
PF20			0000h							
PF21	DRT	Drive recorder switching time setting	0	[s]				<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PF22		For manufacturer setting	200							
PF23	OSCL1	Vibration tough drive - Oscillation detection level	50	[%]				<input type="radio"/>	<input type="radio"/>	
PF24	*OSCL2	Vibration tough drive function selection	0000h					<input type="radio"/>	<input type="radio"/>	
PF25	CVAT	Instantaneous power failure tough drive - detection time	200	[ms]				<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PF26		For manufacturer setting	0							
PF27			0							
PF28			0							
PF29			0000h							
PF30			0							
PF31	FRIC	Machine diagnosis function - Friction judgement speed	0	[r/min]				<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PF32		For manufacturer setting	50							
PF33			0000h							
PF34			0000h							
PF35			0000h							
PF36			0000h							
PF37			0000h							
PF38			0000h							
PF39			0000h							
PF40			0							
PF41			0							
PF42			0							
PF43			0							
PF44			0							
PF45			0000h							
PF46			0							
PF47			0000h							
PF48			0000h							

## 5. PARAMETERS

### 5.2 Detailed list of parameters

POINT
● Set a value to each "x" in the "Setting digit" columns.

#### 5.2.1 Basic setting parameters ([Pr. PA\_ \_ ])

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PA01 *STY Operation mode	___x	Control mode selection Select a control mode. 0: Position control mode 1: Position control mode and speed control mode 2: Speed control mode 3: Speed control mode and torque control mode 4: Torque control mode 5: Torque control mode and position control mode	0h	○	○	○
	__x_	For manufacturer setting	0h	/	/	/
	_x__		0h	/	/	/
	x___		1h	/	/	/
PA02 *REG Regenerative option	__xx	Regenerative option Select a regenerative option. Incorrect setting may cause the regenerative option to burn. If a selected regenerative option is not for use with the servo amplifier, [AL. 37 Parameter error] occurs.  00: Regenerative option is not used. • For servo amplifier of 200 W or less, regenerative resistor is not used. • For servo amplifier of 0.4 kW to 3 kW, built-in regenerative resistor is used. 02: MR-RB032 03: MR-RB12 04: MR-RB32 05: MR-RB30 06: MR-RB50 (Cooling fan is required.)	00h	○	○	○
	_x__	For manufacturer setting	0h	/	/	/
	x___		0h	/	/	/
PA04 *AOP1 Function selection A-1	___x	For manufacturer setting	0h	/	/	/
	__x_		0h	/	/	/
	_x__		0h	/	/	/
	x___		2h	○	○	/
		Forced stop deceleration function selection 0: Forced stop deceleration function disabled (EM1) 2: Forced stop deceleration function enabled (EM2) Refer to table 5.1 for details.				

Table 5.1 Deceleration method

Setting value	EM2/EM1	Deceleration method	
		EM2 or EM1 is off	Alarm occurred
0 ___	EM1	MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.	MBR (Electromagnetic brake interlock) turns off without the forced stop deceleration.
2 ___	EM2	MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.	MBR (Electromagnetic brake interlock) turns off after the forced stop deceleration.

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PA05 *FBP Number of command input pulses per revolution		<p>The servo motor rotates based on set command input pulses. To enable the parameter value, select "Number of command input pulses per revolution (1 ___)" of "Electronic gear selection" in [Pr. PA21].</p> <p>Setting range: 1000 to 1000000</p>	10000	○		
PA06 CMX Electronic gear numerator (command pulse multiplication numerator)		<p>Set the numerator of the electronic gear. To enable the parameter, select "Electronic gear (0 ___)" of "Electronic gear selection" in [Pr. PA21]. The following shows a standard of the setting range of the electronic gear.</p> $\frac{1}{10} < \frac{CMX}{CDV} < 4000$ <p>If the set value is outside this range, noise may be generated during acceleration/deceleration or operation may not be performed at the preset speed and/or acceleration/deceleration time constants.</p> <p>Number of command input pulses per revolution ([Pr. PA05] "1000" to "1000000")</p> <p>Electronic gear selection (x ___) ([Pr. PA21])</p> <p>Electronic gear ([Pr. PA06] • [Pr. PA07])</p> <p>CMX CDV</p> <p>Pt FBP</p> <p>Deviation counter</p> <p>Servo motor (M)</p> <p>Encoder</p> <p>Pt (servo motor resolution): 131072 pulses/rev</p> <p>Always set the electronic gear with servo-off state to prevent unexpected operation due to improper setting.</p> <p>Setting range: 1 to 16777215</p>	1	○		
PA07 CDV Electronic gear denominator (command pulse multiplication denominator)		<p>Set the denominator of the electronic gear. To enable the parameter, select "Electronic gear (0 ___)" of "Electronic gear selection" in [Pr. PA21].</p> <p>Setting range: 1 to 16777215</p>	1	○		

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																				
				P	S	T																		
PA08 ATU Auto tuning mode	___x	Gain adjustment mode selection Select the gain adjustment mode. 0: 2 gain adjustment mode 1 (interpolation mode) 1: Auto tuning mode 1 2: Auto tuning mode 2 3: Manual mode 4: 2 gain adjustment mode 2 Refer to table 5.2 for details.	1h	○	○																			
	__x_	For manufacturer setting	0h																					
	_x__		0h																					
	x___		0h																					
<b>Table 5.2 Gain adjustment mode selection</b>																								
<table border="1" style="width: 100%; border-collapse: collapse;"> <thead> <tr> <th style="width: 10%;">Setting value</th> <th style="width: 20%;">Gain adjustment mode</th> <th style="width: 70%;">Automatically adjusted parameter</th> </tr> </thead> <tbody> <tr> <td>___0</td> <td>2 gain adjustment mode 1 (interpolation mode)</td> <td>[Pr. PB06 Load to motor inertia ratio] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]</td> </tr> <tr> <td>___1</td> <td>Auto tuning mode 1</td> <td>[Pr. PB06 Load to motor inertia ratio] [Pr. PB07 Model loop gain] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]</td> </tr> <tr> <td>___2</td> <td>Auto tuning mode 2</td> <td>[Pr. PB07 Model loop gain] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]</td> </tr> <tr> <td>___3</td> <td>Manual mode</td> <td></td> </tr> <tr> <td>___4</td> <td>2 gain adjustment mode 2</td> <td>[Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]</td> </tr> </tbody> </table>							Setting value	Gain adjustment mode	Automatically adjusted parameter	___0	2 gain adjustment mode 1 (interpolation mode)	[Pr. PB06 Load to motor inertia ratio] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]	___1	Auto tuning mode 1	[Pr. PB06 Load to motor inertia ratio] [Pr. PB07 Model loop gain] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]	___2	Auto tuning mode 2	[Pr. PB07 Model loop gain] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]	___3	Manual mode		___4	2 gain adjustment mode 2	[Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]
Setting value	Gain adjustment mode	Automatically adjusted parameter																						
___0	2 gain adjustment mode 1 (interpolation mode)	[Pr. PB06 Load to motor inertia ratio] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]																						
___1	Auto tuning mode 1	[Pr. PB06 Load to motor inertia ratio] [Pr. PB07 Model loop gain] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]																						
___2	Auto tuning mode 2	[Pr. PB07 Model loop gain] [Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]																						
___3	Manual mode																							
___4	2 gain adjustment mode 2	[Pr. PB08 Position loop gain] [Pr. PB09 Speed loop gain] [Pr. PB10 Speed integral compensation]																						

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																																																																								
				P	S	T																																																																																						
PA09 RSP Auto tuning response		Set a response of the auto tuning.	16	○	○																																																																																							
		<table border="1"> <thead> <tr> <th rowspan="2">Setting value</th> <th colspan="2">Machine characteristic</th> <th rowspan="2">Setting value</th> <th colspan="2">Machine characteristic</th> </tr> <tr> <th>Response</th> <th>Guideline for machine resonance frequency [Hz]</th> <th>Response</th> <th>Guideline for machine resonance frequency [Hz]</th> </tr> </thead> <tbody> <tr> <td>1</td> <td rowspan="19">Low respon se  ↑  ↓  Middle respon se</td> <td>2.7</td> <td>21</td> <td rowspan="19">Middle respon se  ↑  ↓  High respon se</td> <td>67.1</td> </tr> <tr><td>2</td><td>3.6</td><td>22</td><td>75.6</td></tr> <tr><td>3</td><td>4.9</td><td>23</td><td>85.2</td></tr> <tr><td>4</td><td>6.6</td><td>24</td><td>95.9</td></tr> <tr><td>5</td><td>10.0</td><td>25</td><td>108.0</td></tr> <tr><td>6</td><td>11.3</td><td>26</td><td>121.7</td></tr> <tr><td>7</td><td>12.7</td><td>27</td><td>137.1</td></tr> <tr><td>8</td><td>14.3</td><td>28</td><td>154.4</td></tr> <tr><td>9</td><td>16.1</td><td>29</td><td>173.9</td></tr> <tr><td>10</td><td>18.1</td><td>30</td><td>195.9</td></tr> <tr><td>11</td><td>20.4</td><td>31</td><td>220.6</td></tr> <tr><td>12</td><td>23.0</td><td>32</td><td>248.5</td></tr> <tr><td>13</td><td>25.9</td><td>33</td><td>279.9</td></tr> <tr><td>14</td><td>29.2</td><td>34</td><td>315.3</td></tr> <tr><td>15</td><td>32.9</td><td>35</td><td>355.1</td></tr> <tr><td>16</td><td>37.0</td><td>36</td><td>400.0</td></tr> <tr><td>17</td><td>41.7</td><td>37</td><td>446.6</td></tr> <tr><td>18</td><td>47.0</td><td>38</td><td>501.2</td></tr> <tr><td>19</td><td>52.9</td><td>39</td><td>571.5</td></tr> <tr><td>20</td><td>59.6</td><td>40</td><td>642.7</td></tr> </tbody> </table>					Setting value	Machine characteristic		Setting value	Machine characteristic		Response	Guideline for machine resonance frequency [Hz]	Response	Guideline for machine resonance frequency [Hz]	1	Low respon se  ↑  ↓  Middle respon se	2.7	21	Middle respon se  ↑  ↓  High respon se	67.1	2	3.6	22	75.6	3	4.9	23	85.2	4	6.6	24	95.9	5	10.0	25	108.0	6	11.3	26	121.7	7	12.7	27	137.1	8	14.3	28	154.4	9	16.1	29	173.9	10	18.1	30	195.9	11	20.4	31	220.6	12	23.0	32	248.5	13	25.9	33	279.9	14	29.2	34	315.3	15	32.9	35	355.1	16	37.0	36	400.0	17	41.7	37	446.6	18	47.0	38	501.2	19	52.9
Setting value	Machine characteristic		Setting value	Machine characteristic																																																																																								
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1	Low respon se  ↑  ↓  Middle respon se	2.7	21	Middle respon se  ↑  ↓  High respon se	67.1																																																																																							
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19		52.9	39		571.5																																																																																							
20	59.6	40	642.7																																																																																									
		Setting range: 1 to 40																																																																																										
PA10 INP In-position range		Set an in-position range per command pulse. To change it to the servo motor encoder pulse unit, set [Pr. PC24].  Setting range: 0 to 65535	100 [pulse]	○																																																																																								
PA11 TLP Forward rotation torque limit		You can limit the torque generated by the servo motor. Set the parameter referring to section 3.6.1 (5). The larger value of [Pr. PA11 Forward rotation torque limit] or [Pr. PA12 Reverse rotation torque limit] will be the maximum output voltage (8 V). Set the parameter on the assumption that the maximum torque is 100 [%]. The parameter is for limiting the torque of the servo motor in the CCW power running or CW regeneration. Set this parameter to "0.0" to generate no torque.  Setting range: 0.0 to 100.0	100.0 [%]	○	○	○																																																																																						
PA12 TLN Reverse rotation torque limit		You can limit the torque generated by the servo motor. Set the parameter referring to section 3.6.1 (5). The larger value of [Pr. PA11 Forward rotation torque limit] or [Pr. PA12 Reverse rotation torque limit] will be the maximum output voltage (8 V). Set the parameter on the assumption that the maximum torque is 100 [%]. The parameter is for limiting the torque of the servo motor in the CW power running or CCW regeneration. Set this parameter to "0.0" to generate no torque.  Setting range: 0.0 to 100.0	100.0 [%]	○	○	○																																																																																						

## 5. PARAMETERS

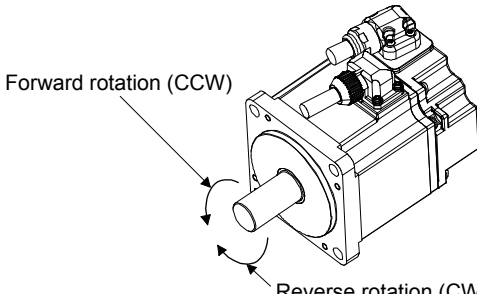
No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PA13 *PLSS Command pulse input form	___x	Command input pulse train form selection 0: Forward/reverse rotation pulse train 1: Signed pulse train 2: A-phase/B-phase pulse train (The servo amplifier imports input pulses after multiplying by four.) Refer to table 5.3 for settings.	0h	○		
	__x_	Pulse train logic selection 0: Positive logic 1: Negative logic Select the same one as a logic of command pulse train from controller to connect. Refer to POINT of section 3.6.1 for logic of MELSEC iQ-R series/MELSEC-Q series/MELSEC-L series/MELSEC-F series. Refer to table 5.3 for settings.	0h	○		
	_x__	Command input pulse train filter selection Selecting proper filter enables to enhance noise tolerance. 0: Command input pulse train is 4 Mpulses/s or less. 1: Command input pulse train is 1 Mpulse/s or less. 2: Command input pulse train is 500 kpulses/s or less. 3: Command input pulse train is 200 kpulses/s or less. 1 Mpulse/s or lower commands are supported by "1". When inputting commands over 1 Mpulse/s and 4 Mpulses/s or lower, set "0". Setting a value not according to the command pulse frequency may cause the following malfunctions. <ul style="list-style-type: none"> <li>Setting a value higher than actual command will lower noise tolerance.</li> <li>Setting a value lower than actual command will cause a position mismatch.</li> </ul>	1h	○		
	x___	For manufacturer setting	0h			

Table 5.3 Command input pulse train form selection

Setting value		Pulse train form	Forward rotation command	Reverse rotation command
__10 __11 __12	Negative logic	Forward rotation pulse train Reverse rotation pulse train	PP	NP
		Signed pulse train	PP	NP
		A-phase pulse train B-phase pulse train	PP	NP
__00 __01 __02	Positive logic	Forward rotation pulse train Reverse rotation pulse train	PP	NP
		Signed pulse train	PP	NP
		A-phase pulse train B-phase pulse train	PP	NP

Arrows in the table indicate the timing of importing pulse trains. A-phase pulse train and B-phase pulse train are imported after they have been multiplied by 4.

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode													
				P	S	T											
PA14 *POL Rotation direction selection		<p>Select servo motor rotation direction relative to the input pulse train.</p> <table border="1"> <thead> <tr> <th rowspan="2">Setting value</th> <th colspan="2">Servo motor rotation direction</th> </tr> <tr> <th>When forward rotation pulse is input</th> <th>When reverse rotation pulse is input</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>CCW</td> <td>CW</td> </tr> <tr> <td>1</td> <td>CW</td> <td>CCW</td> </tr> </tbody> </table> <p>The following shows the servo motor rotation directions.</p>  <p>Setting range: 0, 1</p>	Setting value	Servo motor rotation direction		When forward rotation pulse is input	When reverse rotation pulse is input	0	CCW	CW	1	CW	CCW	0	<input type="radio"/>		
Setting value	Servo motor rotation direction																
	When forward rotation pulse is input	When reverse rotation pulse is input															
0	CCW	CW															
1	CW	CCW															
PA15 *ENR Encoder output pulses		<p>Set the encoder output pulses from the servo amplifier by using the number of output pulses per revolution, dividing ratio, or electronic gear ratio. (after multiplication by 4)</p> <p>Set a numerator of the electronic gear when "A-phase/B-phase pulse electronic gear setting ( _ _ 3 _ )" is selected in [Pr. PC19 Encoder output pulser setting selection].</p> <p>The maximum output frequency is 4.6 Mpulses/s. Set the parameter within this range.</p> <p>Select "Output pulse setting" or "Dividing ratio setting" in [Pr. PC19].</p> <p>Setting range: 1 to 4194304</p>	4000 [pulse/ rev]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>											
PA16 *ENR2 Encoder output pulses 2		<p>Set a denominator of the electronic gear for the A/B-phase pulse output.</p> <p>To set a denominator of the electronic gear, select "A-phase/B-phase pulse electronic gear setting ( _ _ 3 _ )" of "Encoder output pulse setting selection" in [Pr. PC19].</p> <p>When "Encoder output pulse setting selection" is set to "Disabled ( _ _ 1 _ )" in [Pr. PC19], the setting value of this parameter will be disabled.</p> <p>Setting range: 1 to 4194304</p>	1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>											

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																																																																																																																	
				P	S	T																																																																																																																															
PA19 *BLK Parameter writing inhibit		Select a reference range and writing range of the parameter. Refer to table 5.4 for settings.	00AAh	○	○	○																																																																																																																															
	<p style="text-align: center;"><b>Table 5.4 [Pr. PA19] setting value and reading/writing range</b></p> <table border="1" style="width: 100%; border-collapse: collapse; text-align: center;"> <thead> <tr> <th>PA19</th> <th>Setting operation</th> <th>PA</th> <th>PB</th> <th>PC</th> <th>PD</th> <th>PE</th> <th>PF</th> </tr> </thead> <tbody> <tr> <td rowspan="2">Other than below</td> <td>Reading</td> <td>○</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td>Writing</td> <td>○</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td rowspan="2">000Ah</td> <td>Reading</td> <td>Only 19</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td>Writing</td> <td>Only 19</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td rowspan="2">000Bh</td> <td>Reading</td> <td>○</td> <td>○</td> <td>○</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td>Writing</td> <td>○</td> <td>○</td> <td>○</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td rowspan="2">000Ch</td> <td>Reading</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>△</td> <td>△</td> </tr> <tr> <td>Writing</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>△</td> <td>△</td> </tr> <tr> <td rowspan="2">00AAh (initial value)</td> <td>Reading</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> </tr> <tr> <td>Writing</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> </tr> <tr> <td rowspan="2">100Bh</td> <td>Reading</td> <td>○</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td>Writing</td> <td>Only 19</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td rowspan="2">100Ch</td> <td>Reading</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>△</td> <td>△</td> </tr> <tr> <td>Writing</td> <td>Only 19</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> <tr> <td rowspan="2">10AAh</td> <td>Reading</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> <td>○</td> </tr> <tr> <td>Writing</td> <td>Only 19</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> <td>△</td> </tr> </tbody> </table>						PA19	Setting operation	PA	PB	PC	PD	PE	PF	Other than below	Reading	○	△	△	△	△	△	Writing	○	△	△	△	△	△	000Ah	Reading	Only 19	△	△	△	△	△	Writing	Only 19	△	△	△	△	△	000Bh	Reading	○	○	○	△	△	△	Writing	○	○	○	△	△	△	000Ch	Reading	○	○	○	○	△	△	Writing	○	○	○	○	△	△	00AAh (initial value)	Reading	○	○	○	○	○	○	Writing	○	○	○	○	○	○	100Bh	Reading	○	△	△	△	△	△	Writing	Only 19	△	△	△	△	△	100Ch	Reading	○	○	○	○	△	△	Writing	Only 19	△	△	△	△	△	10AAh	Reading	○	○	○	○	○	○	Writing	Only 19	△	△	△	△
PA19	Setting operation	PA	PB	PC	PD	PE	PF																																																																																																																														
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	Writing	Only 19	△	△	△	△	△																																																																																																																														
PA20 *TDS Tough drive setting	Alarms may not be avoided with the tough drive function depending on the situations of the power supply and load fluctuation. You can assign MTTR (During tough drive) to pins CN1-23, CN1-24, and CN1-49 with [Pr. PD24], [Pr. PD25], and [Pr. PD28].																																																																																																																																				
	__ _ x	For manufacturer setting	0h	△	△	△																																																																																																																															
	__ x _	Vibration tough drive selection 0: Disabled 1: Enabled  Selecting "1" enables to suppress vibrations by automatically changing setting values of [Pr. PB13 Machine resonance suppression filter 1] and [Pr. PB15 Machine resonance suppression filter 2] in case that the vibration exceed the value of the oscillation level set in [Pr. PF23]. To output the oscillation detection alarm as a warning, set [Pr. PF24 Vibration tough drive function selection]. Refer to section 7.3 for details.	0h	○	○	△																																																																																																																															
	_ x _ _	Instantaneous power failure tough drive selection 0: Disabled 1: Enabled  Selecting "1" enables to avoid occurring [AL. 10 Undervoltage] using the electrical energy charged in the capacitor in the servo amplifier in case that an instantaneous power failure occurs during operation. In [Pr. PF25 Instantaneous power failure tough drive - Detection time], set the time until the occurrence of [AL. 10.1 Voltage drop in the power]. When the digit is enabled, the power should be off for the setting value of [Pr. PF25] + 1 s or more before cycling the power to enable a parameter whose symbol is preceded by "*".	0h	○	○	○																																																																																																																															
x _ _ _	For manufacturer setting	0h	△	△	△																																																																																																																																



## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PA21 *AOP3 Function selection A-3	___x	One-touch tuning function selection 0: Disabled 1: Enabled  When the digit is "0", the one-touch tuning is not available.	1h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___	Electronic gear selection 0: Electronic gear ([Pr. PA06] and [Pr. PA07]) 1: Number of command input pulses per revolution ([Pr. PA05])	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA23 DRAT Drive recorder arbitrary alarm trigger setting	__xx	Alarm detail No. setting Set the digits when you execute the trigger with arbitrary alarm detail No. for the drive recorder function. When these digits are "0 0", only the arbitrary alarm No. setting will be enabled.	00h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	xx__	Alarm No. setting Set the digits when you execute the trigger with arbitrary alarm No. for the drive recorder function. When "0 0" are set, arbitrary alarm trigger of the drive recorder will be disabled.	00h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	Setting example: To activate the drive recorder when [AL. 50 Overload 1] occurs, set "5 0 0 0". To activate the drive recorder when [AL. 50.3 Thermal overload error 4 during operation] occurs, set "5 0 0 3".					
PA24 AOP4 Function selection A-4	___x	Vibration suppression mode selection 0: Standard mode 1: 3 inertia mode 2: Low response mode  When you select the standard mode or low response mode, "Vibration suppression control 2" is not available. When you select the 3 inertia mode, the feed forward gain is not available. Before changing the control mode during the 3 inertia mode or low response mode, stop the motor.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
PA25 OTHOV One-touch tuning - Overshoot permissible level		Set a permissible value of overshoot amount for one-touch tuning as a percentage of the in-position range. However, setting "0" will be 50%.  Setting range: 0 to 100	0 [%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PA26 *AOP5 Function selection A-5	___x	Torque limit function selection at instantaneous power failure 0: Disabled 1: Enabled Selecting "1" for this digit will limit torques to save electric energy when an instantaneous power failure occurs during operation and will make [AL. 10 Undervoltage] less likely to occur. The torque limit function at instantaneous power failure is enabled when "Instantaneous power failure tough drive selection" in [Pr. PA20] is "Enabled (_ 1 _)".	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>

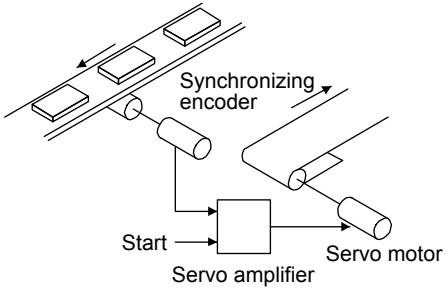
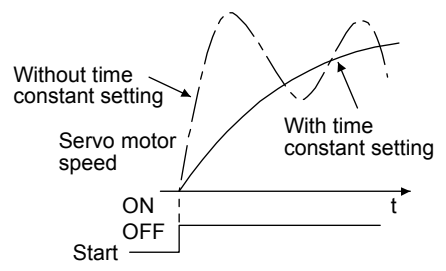
## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PA28 *AOP6 Function selection A-6	___x	Selection of the HG-KN series servo motor maximum speed Select the maximum speed of the HG-KN series servo motor. 0: A maximum speed of 5000 r/min 1: A maximum speed of 6000 r/min This digit is disabled when a servo motor other than HG-KN series is connected. This digit is available with servo amplifier with software version C5 or later.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>

### 5.2.2 Gain/filter setting parameters ([Pr. PB\_ \_])

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB01 FILT Adaptive tuning mode (adaptive filter II)	___x	Filter tuning mode selection Set the adaptive tuning. Select the adjustment mode of the machine resonance suppression filter 1. Refer to section 7.1.2 for details. 0: Disabled 1: Automatic setting (Do not use this in the torque control mode.) 2: Manual setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___	Tuning accuracy selection 0: Standard 1: High accuracy The frequency is estimated more accurately in the high accuracy mode compared to the standard mode. However, the tuning sound may be larger in the high accuracy mode. This digit is available with servo amplifier with software version C5 or later.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB02 VRFT Vibration suppression control tuning mode (advanced vibration suppression control II)	___x	Vibration suppression control 1 tuning mode selection Select the tuning mode of the vibration suppression control 1. Refer to section 7.1.5 for details. 0: Disabled 1: Automatic setting 2: Manual setting	0h	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
	__x_	Vibration suppression control 2 tuning mode selection Select the tuning mode of the vibration suppression control 2. To enable the digit, select "3 inertia mode (___ 1)" of "Vibration suppression mode selection" in [Pr. PA24]. Refer to section 7.1.5 for details. 0: Disabled 1: Automatic setting 2: Manual setting	0h	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>

# 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode											
				P	S	T									
PB03 PST Position command acceleration/ deceleration time constant (position smoothing)		<p>Set the constant of a primary delay to the position command.</p> <p>You can select a control method from "Primary delay" or "Linear acceleration/deceleration" in [Pr. PB25 Function selection B-1]. The setting range of "Linear acceleration/deceleration" is 0 ms to 10 ms. Setting of longer than 10 ms will be recognized as 10 ms.</p> <p>When the linear acceleration/deceleration is selected, do not set the "Control mode selection" ([Pr. PA01]) to the setting other than "___0". Doing so will cause the servo motor to make a sudden stop at the time of position control mode switching.</p> <p>(Example) When a command is given from a synchronizing encoder, synchronous operation will start smoothly even if it start during line operation.</p>   <p>Setting range: 0 to 65535</p>	0 [ms]	<input type="radio"/>											
PB04 FFC Feed forward gain		<p>Set the feed forward gain.</p> <p>When the setting is 100%, the droop pulses during operation at constant speed are nearly zero. However, sudden acceleration/deceleration will increase the overshoot. As a guideline, when the feed forward gain setting is 100%, set 1 s or more as the acceleration time constant up to the rated speed.</p> <p>Setting range: 0 to 100</p>	0 [%]	<input type="radio"/>											
PB06 GD2 Load to motor inertia ratio		<p>Set the load to motor inertia ratio.</p> <p>Setting a value considerably different from the actual load moment of inertia may cause an unexpected operation such as an overshoot.</p> <p>The setting of the parameter will be the automatic setting or manual setting depending on the [Pr. PA08] setting. Refer to the following table for details. When the parameter is automatic setting, the value will vary between 0.00 and 100.00.</p> <p>Setting range: 0.00 to 300.00</p> <table border="1" data-bbox="391 1713 1077 1937"> <thead> <tr> <th>Pr. PA08</th> <th>This parameter</th> </tr> </thead> <tbody> <tr> <td>___0 (2 gain adjustment mode 1 (interpolation mode))</td> <td>Automatic setting</td> </tr> <tr> <td>___1: (Auto tuning mode 1)</td> <td rowspan="4">Manual setting</td> </tr> <tr> <td>___2: (Auto tuning mode 2)</td> </tr> <tr> <td>___3: (Manual mode)</td> </tr> <tr> <td>___4: (2 gain adjustment mode 2)</td> </tr> </tbody> </table>	Pr. PA08	This parameter	___0 (2 gain adjustment mode 1 (interpolation mode))	Automatic setting	___1: (Auto tuning mode 1)	Manual setting	___2: (Auto tuning mode 2)	___3: (Manual mode)	___4: (2 gain adjustment mode 2)	7.00 [Multiplier]	<input type="radio"/>	<input type="radio"/>	
Pr. PA08	This parameter														
___0 (2 gain adjustment mode 1 (interpolation mode))	Automatic setting														
___1: (Auto tuning mode 1)	Manual setting														
___2: (Auto tuning mode 2)															
___3: (Manual mode)															
___4: (2 gain adjustment mode 2)															

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode										
				P	S	T								
PB07 PG1 Model loop gain		Set the response gain up to the target position. Increasing the setting value will also increase the response level to the position command but will be liable to generate vibration and noise. The setting of the parameter will be the automatic setting or manual setting depending on the [Pr. PA08] setting. Refer to the following table for details.  Setting range: 1.0 to 2000.0	15.0 [rad/s]	<input type="radio"/>	<input type="radio"/>									
		<table border="1"> <thead> <tr> <th>Pr. PA08</th> <th>This parameter</th> </tr> </thead> <tbody> <tr> <td>___ 0 (2 gain adjustment mode 1 (interpolation mode))</td> <td>Manual setting</td> </tr> <tr> <td>___ 1: (Auto tuning mode 1)</td> <td rowspan="2">Automatic setting</td> </tr> <tr> <td>___ 2: (Auto tuning mode 2)</td> </tr> <tr> <td>___ 3: (Manual mode)</td> <td>Manual setting</td> </tr> <tr> <td>___ 4: (2 gain adjustment mode 2)</td> <td></td> </tr> </tbody> </table>	Pr. PA08	This parameter	___ 0 (2 gain adjustment mode 1 (interpolation mode))	Manual setting	___ 1: (Auto tuning mode 1)	Automatic setting	___ 2: (Auto tuning mode 2)	___ 3: (Manual mode)	Manual setting	___ 4: (2 gain adjustment mode 2)		
Pr. PA08	This parameter													
___ 0 (2 gain adjustment mode 1 (interpolation mode))	Manual setting													
___ 1: (Auto tuning mode 1)	Automatic setting													
___ 2: (Auto tuning mode 2)														
___ 3: (Manual mode)	Manual setting													
___ 4: (2 gain adjustment mode 2)														
PB08 PG2 Position loop gain		Set the gain of the position loop. Set this parameter to increase the position response to level load disturbance. Increasing the setting value will also increase the response level to the load disturbance but will be liable to generate vibration and noise. The setting of the parameter will be the automatic setting or manual setting depending on the [Pr. PA08] setting. Refer to the following table for details.  Setting range: 1.0 to 2000.0	37.0 [rad/s]	<input type="radio"/>										
		<table border="1"> <thead> <tr> <th>Pr. PA08</th> <th>This parameter</th> </tr> </thead> <tbody> <tr> <td>___ 0 (2 gain adjustment mode 1 (interpolation mode))</td> <td rowspan="3">Automatic setting</td> </tr> <tr> <td>___ 1: (Auto tuning mode 1)</td> </tr> <tr> <td>___ 2: (Auto tuning mode 2)</td> </tr> <tr> <td>___ 3: (Manual mode)</td> <td>Manual setting</td> </tr> <tr> <td>___ 4: (2 gain adjustment mode 2)</td> <td>Automatic setting</td> </tr> </tbody> </table>	Pr. PA08	This parameter	___ 0 (2 gain adjustment mode 1 (interpolation mode))	Automatic setting	___ 1: (Auto tuning mode 1)	___ 2: (Auto tuning mode 2)	___ 3: (Manual mode)	Manual setting	___ 4: (2 gain adjustment mode 2)	Automatic setting		
Pr. PA08	This parameter													
___ 0 (2 gain adjustment mode 1 (interpolation mode))	Automatic setting													
___ 1: (Auto tuning mode 1)														
___ 2: (Auto tuning mode 2)														
___ 3: (Manual mode)	Manual setting													
___ 4: (2 gain adjustment mode 2)	Automatic setting													
PB09 VG2 Speed loop gain		Set the gain of the speed loop. Set this parameter when vibration occurs on machines of low rigidity or large backlash. Increasing the setting value will also increase the response level but will be liable to generate vibration and noise. The setting of the parameter will be the automatic setting or manual setting depending on the [Pr. PA08] setting. Refer to the table of [Pr. PB08] for details.  Setting range: 20 to 65535	823 [rad/s]	<input type="radio"/>	<input type="radio"/>									
PB10 VIC Speed integral compensation		Set the integral time constant of the speed loop. Decreasing the setting value will increase the response level but will be liable to generate vibration and noise. The setting of the parameter will be the automatic setting or manual setting depending on the [Pr. PA08] setting. Refer to the table of [Pr. PB08] for details.  Setting range: 0.1 to 1000.0	33.7 [ms]	<input type="radio"/>	<input type="radio"/>									
PB11 VDC Speed differential compensation		Set the differential compensation. To enable the setting value, turn on PC (proportional control).  Setting range: 0 to 1000	980	<input type="radio"/>	<input type="radio"/>									
PB12 OVA Overshoot amount compensation		Set a viscous friction torque per percent to the servo motor rated speed. When the response level is low, or when the torque is limited, the efficiency of the parameter can be lower.  Setting range: 0 to 100	0 [%]	<input type="radio"/>										

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB13 NH1 Machine resonance suppression filter 1		Machine resonance suppression filter 1 Set the notch frequency of the machine resonance suppression filter 1. When "Filter tuning mode selection" is set to "Automatic setting (___ 1)" in [Pr. PB01], this parameter will be adjusted automatically by adaptive tuning. When "Filter tuning mode selection" is set to "Manual setting (___ 2)" in [Pr. PB01], the setting value will be enabled.  Setting range: 10 to 4500	4500 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB14 NHQ1 Notch shape selection 1		Set the shape of the machine resonance suppression filter 1. When "Filter tuning mode selection" is set to "Automatic setting (___ 1)" in [Pr. PB01], this parameter will be adjusted automatically by adaptive tuning. To enable the setting value, select the manual setting.				
	___ x	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	__ x _	Notch depth selection 0: -40 dB 1: -14 dB 2: -8 dB 3: -4 dB	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ x __	Notch width selection 0: $\alpha = 2$ 1: $\alpha = 3$ 2: $\alpha = 4$ 3: $\alpha = 5$	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x ___	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
PB15 NH2 Machine resonance suppression filter 2		Set the notch frequency of the machine resonance suppression filter 2. To enable the setting value, select "Enabled (___ 1)" of "Machine resonance suppression filter 2 selection" in [Pr. PB16].  Setting range: 10 to 4500	4500 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB16 NHQ2 Notch shape selection 2		Set the shape of the machine resonance suppression filter 2.				
	___ x	Machine resonance suppression filter 2 selection 0: Disabled 1: Enabled	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__ x _	Notch depth selection 0: -40 dB 1: -14 dB 2: -8 dB 3: -4 dB	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ x __	Notch width selection 0: $\alpha = 2$ 1: $\alpha = 3$ 2: $\alpha = 4$ 3: $\alpha = 5$	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x ___	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																																																						
				P	S	T																																																																				
PB17 NHF Shaft resonance suppression filter		Set the shaft resonance suppression filter. Use this filter to suppress a low-frequency machine vibration. When you select "Automatic setting (___ 0)" of "Shaft resonance suppression filter selection" in [Pr. PB23], the value will be calculated automatically from the servo motor you use and load to motor inertia ratio. When "Manual setting (___ 1)" is selected, the setting written to the parameter is used. When "Shaft resonance suppression filter selection" is "Disabled (___ 2)" in [Pr. PB23], the setting value of this parameter will be disabled. When you select "Enabled (___ 1)" of "Machine resonance suppression filter 4 selection" in [Pr. PB49], the shaft resonance suppression filter is not available.																																																																								
	__ x x	Shaft resonance suppression filter setting frequency selection Refer to table 5.5 for settings. Set the value closest to the frequency you need.	00h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>																																																																				
	_ x _ _	Notch depth selection 0: -40 dB 1: -14 dB 2: -8 dB 3: -4 dB	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>																																																																				
	x _ _ _	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>																																																																				
<p>Table 5.5 Shaft resonance suppression filter setting frequency selection</p> <table border="1"> <thead> <tr> <th>Setting value</th> <th>Frequency [Hz]</th> <th>Setting value</th> <th>Frequency [Hz]</th> </tr> </thead> <tbody> <tr><td>__ 0 0</td><td>Disabled</td><td>__ 1 0</td><td>562</td></tr> <tr><td>__ 0 1</td><td>Disabled</td><td>__ 1 1</td><td>529</td></tr> <tr><td>__ 0 2</td><td>4500</td><td>__ 1 2</td><td>500</td></tr> <tr><td>__ 0 3</td><td>3000</td><td>__ 1 3</td><td>473</td></tr> <tr><td>__ 0 4</td><td>2250</td><td>__ 1 4</td><td>450</td></tr> <tr><td>__ 0 5</td><td>1800</td><td>__ 1 5</td><td>428</td></tr> <tr><td>__ 0 6</td><td>1500</td><td>__ 1 6</td><td>409</td></tr> <tr><td>__ 0 7</td><td>1285</td><td>__ 1 7</td><td>391</td></tr> <tr><td>__ 0 8</td><td>1125</td><td>__ 1 8</td><td>375</td></tr> <tr><td>__ 0 9</td><td>1000</td><td>__ 1 9</td><td>360</td></tr> <tr><td>__ 0 A</td><td>900</td><td>__ 1 A</td><td>346</td></tr> <tr><td>__ 0 B</td><td>818</td><td>__ 1 B</td><td>333</td></tr> <tr><td>__ 0 C</td><td>750</td><td>__ 1 C</td><td>321</td></tr> <tr><td>__ 0 D</td><td>692</td><td>__ 1 D</td><td>310</td></tr> <tr><td>__ 0 E</td><td>642</td><td>__ 1 E</td><td>300</td></tr> <tr><td>__ 0 F</td><td>600</td><td>__ 1 F</td><td>290</td></tr> </tbody> </table>							Setting value	Frequency [Hz]	Setting value	Frequency [Hz]	__ 0 0	Disabled	__ 1 0	562	__ 0 1	Disabled	__ 1 1	529	__ 0 2	4500	__ 1 2	500	__ 0 3	3000	__ 1 3	473	__ 0 4	2250	__ 1 4	450	__ 0 5	1800	__ 1 5	428	__ 0 6	1500	__ 1 6	409	__ 0 7	1285	__ 1 7	391	__ 0 8	1125	__ 1 8	375	__ 0 9	1000	__ 1 9	360	__ 0 A	900	__ 1 A	346	__ 0 B	818	__ 1 B	333	__ 0 C	750	__ 1 C	321	__ 0 D	692	__ 1 D	310	__ 0 E	642	__ 1 E	300	__ 0 F	600	__ 1 F	290
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PB18 LPF Low-pass filter setting		Set the low-pass filter. The following shows a relation of a required parameter to this parameter.  Setting range: 100 to 18000	3141 [rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="checkbox"/>																																																																				
		<table border="1"> <thead> <tr> <th>[Pr. PB23]</th> <th>[Pr. PB18]</th> </tr> </thead> <tbody> <tr> <td>__ 0 _ (Initial value)</td> <td>Automatic setting</td> </tr> <tr> <td>__ 1 _</td> <td>Setting value enabled</td> </tr> <tr> <td>__ 2 _</td> <td>Setting value disabled</td> </tr> </tbody> </table>	[Pr. PB23]	[Pr. PB18]	__ 0 _ (Initial value)	Automatic setting	__ 1 _	Setting value enabled	__ 2 _	Setting value disabled																																																																
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## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB19 VRF11 Vibration suppression control 1 - Vibration frequency		Set the vibration frequency for vibration suppression control 1 to suppress low-frequency machine vibration. When "Vibration suppression control 1 tuning mode selection" is set to "Automatic setting ( _ _ _ 1)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting ( _ _ _ 2)" is selected, the setting written to the parameter is used.  Setting range: 0.1 to 300.0	100.0 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB20 VRF12 Vibration suppression control 1 - Resonance frequency		Set the resonance frequency for vibration suppression control 1 to suppress low-frequency machine vibration. When "Vibration suppression control 1 tuning mode selection" is set to "Automatic setting ( _ _ _ 1)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting ( _ _ _ 2)" is selected, the setting written to the parameter is used.  Setting range: 0.1 to 300.0	100.0 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB21 VRF13 Vibration suppression control 1 - Vibration frequency damping		Set a damping of the vibration frequency for vibration suppression control 1 to suppress low-frequency machine vibration. When "Vibration suppression control 1 tuning mode selection" is set to "Automatic setting ( _ _ _ 1)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting ( _ _ _ 2)" is selected, the setting written to the parameter is used.  Setting range: 0.00 to 0.30	0.00	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB22 VRF14 Vibration suppression control 1 - Resonance frequency damping		Set a damping of the resonance frequency for vibration suppression control 1 to suppress low-frequency machine vibration. When "Vibration suppression control 1 tuning mode selection" is set to "Automatic setting ( _ _ _ 1)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting ( _ _ _ 2)" is selected, the setting written to the parameter is used.  Setting range: 0.00 to 0.30	0.00	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB23 VFBF Low-pass filter selection	_ _ _ x	Shaft resonance suppression filter selection Select the shaft resonance suppression filter. 0: Automatic setting 1: Manual setting 2: Disabled  When "Machine resonance suppression filter 4 selection" is set to "Enabled ( _ _ _ 1)" in [Pr. PB49], the shaft resonance suppression filter is not available.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ _ x _	Low-pass filter selection Select the low-pass filter. 0: Automatic setting 1: Manual setting 2: Disabled	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ x _ _	For manufacturer setting	1h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x _ _ _		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB24 *MVS Slight vibration suppression control	_ _ _ x	Slight vibration suppression control selection Select the slight vibration suppression control. 0: Disabled 1: Enabled  To enable the slight vibration suppression control, select "Manual mode ( _ _ _ 3)" of "Gain adjustment mode selection" in [Pr. PA08]. Slight vibration suppression control cannot be used in the speed control mode.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ _ x _	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ x _ _		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x _ _ _		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB25 *BOP1 Function selection B-1	___x	Model adaptive control selection 0: Enabled (model adaptive control) 2: Disabled (PID control) This parameter setting is available with servo amplifiers with software version B4 or later.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	Position acceleration/deceleration filter type selection Select the position acceleration/deceleration filter type. 0: Primary delay 1: Linear acceleration/deceleration When you select "Linear acceleration/deceleration", do not switch the control mode. Doing so will cause the servo motor to make a sudden stop at the time of control mode switching.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_x__	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x___		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB26 *CDP Gain switching function	Select the gain switching condition. Set conditions to enable the gain switching values set in [Pr. PB29] to [Pr. PB36] and [Pr. PB56] to [Pr. PB60].					
	___x	Gain switching selection 0: Disabled 1: Input device (gain switching (CDP)) 2: Command frequency 3: Droop pulses 4: Servo motor speed	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	Gain switching condition selection 0: Gain after switching is enabled with gain switching condition or more 1: Gain after switching is enabled with gain switching condition or less	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_x__	Gain switching time constant disabling condition selection 0: Switching time constant enabled 1: Switching time constant disabled 2: Return time constant disabled Refer to section 7.2.4 for details. This parameter setting is available with servo amplifiers with software version B4 or later.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x___	For manufacturing setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB27 CDL Gain switching condition		Set the value of gain switching (command frequency, droop pulses, and servo motor speed) selected in [Pr. PB26]. The set value unit differs depending on the switching condition item. (Refer to section 7.2.3.)  Setting range: 0 to 9999	10 [kpulse/ s] /[pulse] /[r/min]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB28 CDT Gain switching time constant		Set the time constant at which the gains will change in response to the conditions set in [Pr. PB26] and [Pr. PB27].  Setting range: 0 to 100	1 [ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB29 GD2B Load to motor inertia ratio after gain switching		Set the load to motor inertia ratio when gain switching is enabled. This parameter is enabled only when you select "Manual mode (_ _ _ 3)" of "Gain adjustment mode selection" in [Pr. PA08].  Setting range: 0.00 to 300.00	7.00 [Multipli er]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB30 PG2B Position loop gain after gain switching		Set the position loop gain when the gain switching is enabled. When you set a value less than 1.0 rad/s, the value will be the same as [Pr. PB08]. This parameter is enabled only when you select "Manual mode (_ _ _ 3)" of "Gain adjustment mode selection" in [Pr. PA08].  Setting range: 0.0 to 2000.0	0.0 [rad/s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>



## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB31 VG2B Speed loop gain after gain switching		Set the speed loop gain when the gain switching is enabled. When you set a value less than 20 rad/s, the value will be the same as [Pr. PB09]. This parameter is enabled only when you select "Manual mode ( _ _ _ 3)" of "Gain adjustment mode selection" in [Pr. PA08].  Setting range: 0 to 65535	0 [rad/s]	<input type="radio"/>	<input type="radio"/>	
PB32 VICB Speed integral compensation after gain switching		Set the speed integral compensation when the gain changing is enabled. When you set a value less than 0.1 ms, the value will be the same as [Pr. PB10]. This parameter is enabled only when you select "Manual mode ( _ _ _ 3)" of "Gain adjustment mode selection" in [Pr. PA08].  Setting range: 0.0 to 5000.0	0.0 [ms]	<input type="radio"/>	<input type="radio"/>	
PB33 VRF1B Vibration suppression control 1 - Vibration frequency after gain switching		Set the vibration frequency for vibration suppression control 1 when the gain switching is enabled. When you set a value less than 0.1 Hz, the value will be the same as [Pr. PB19]. This parameter will be enabled only when the following conditions are fulfilled. <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression control 1 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ _ 2)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.  Setting range: 0.0 to 300.0	0.0 [Hz]	<input type="radio"/>		
PB34 VRF2B Vibration suppression control 1 - Resonance frequency after gain switching		Set the resonance frequency for vibration suppression control 1 when the gain switching is enabled. When you set a value less than 0.1 Hz, the value will be the same as [Pr. PB20]. This parameter will be enabled only when the following conditions are fulfilled. <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression control 1 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ _ 2)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.  Setting range: 0.0 to 300.0	0.0 [Hz]	<input type="radio"/>		
PB35 VRF3B Vibration suppression control 1 - Vibration frequency damping after gain switching		Set a damping of the vibration frequency for vibration suppression control 1 when the gain switching is enabled. This parameter will be enabled only when the following conditions are fulfilled. <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression control 1 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ _ 2)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.  Setting range: 0.00 to 0.30	0.00	<input type="radio"/>		
PB36 VRF4B Vibration suppression control 1 - Resonance frequency damping after gain switching		Set a damping of the resonance frequency for vibration suppression control 1 when the gain switching is enabled. This parameter will be enabled only when the following conditions are fulfilled. <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression control 1 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ _ 2)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.  Setting range: 0.00 to 0.30	0.00	<input type="radio"/>		

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																																																																																																																																																																																																																												
				P	S	T																																																																																																																																																																																																																																										
PB45 CNHF Command notch filter	Set the command notch filter.																																																																																																																																																																																																																																															
	-- x x	Command notch filter setting frequency selection Refer to table 5.6 for the relation of setting values to frequency.	00h	○	△	△																																																																																																																																																																																																																																										
	_ x _ _	Notch depth selection Refer to table 5.7 for details.	0h	○	△	△																																																																																																																																																																																																																																										
	x _ _ _	For manufacturer setting	0h	△	△	△																																																																																																																																																																																																																																										
<p>Table 5.6 Command notch filter setting frequency selection</p> <table border="1"> <thead> <tr> <th>Setting value</th> <th>Frequency [Hz]</th> <th>Setting value</th> <th>Frequency [Hz]</th> <th>Setting value</th> <th>Frequency [Hz]</th> </tr> </thead> <tbody> <tr><td>-- 0 0</td><td>Disabled</td><td>-- 2 0</td><td>70</td><td>-- 4 0</td><td>17.6</td></tr> <tr><td>-- 0 1</td><td>2250</td><td>-- 2 1</td><td>66</td><td>-- 4 1</td><td>16.5</td></tr> <tr><td>-- 0 2</td><td>1125</td><td>-- 2 2</td><td>62</td><td>-- 4 2</td><td>15.6</td></tr> <tr><td>-- 0 3</td><td>750</td><td>-- 2 3</td><td>59</td><td>-- 4 3</td><td>14.8</td></tr> <tr><td>-- 0 4</td><td>562</td><td>-- 2 4</td><td>56</td><td>-- 4 4</td><td>14.1</td></tr> <tr><td>-- 0 5</td><td>450</td><td>-- 2 5</td><td>53</td><td>-- 4 5</td><td>13.4</td></tr> <tr><td>-- 0 6</td><td>375</td><td>-- 2 6</td><td>51</td><td>-- 4 6</td><td>12.8</td></tr> <tr><td>-- 0 7</td><td>321</td><td>-- 2 7</td><td>48</td><td>-- 4 7</td><td>12.2</td></tr> <tr><td>-- 0 8</td><td>281</td><td>-- 2 8</td><td>46</td><td>-- 4 8</td><td>11.7</td></tr> <tr><td>-- 0 9</td><td>250</td><td>-- 2 9</td><td>45</td><td>-- 4 9</td><td>11.3</td></tr> <tr><td>-- 0 A</td><td>225</td><td>-- 2 A</td><td>43</td><td>-- 4 A</td><td>10.8</td></tr> <tr><td>-- 0 B</td><td>204</td><td>-- 2 B</td><td>41</td><td>-- 4 B</td><td>10.4</td></tr> <tr><td>-- 0 C</td><td>187</td><td>-- 2 C</td><td>40</td><td>-- 4 C</td><td>10</td></tr> <tr><td>-- 0 D</td><td>173</td><td>-- 2 D</td><td>38</td><td>-- 4 D</td><td>9.7</td></tr> <tr><td>-- 0 E</td><td>160</td><td>-- 2 E</td><td>37</td><td>-- 4 E</td><td>9.4</td></tr> <tr><td>-- 0 F</td><td>150</td><td>-- 2 F</td><td>36</td><td>-- 4 F</td><td>9.1</td></tr> <tr><td>-- 1 0</td><td>140</td><td>-- 3 0</td><td>35.2</td><td>-- 5 0</td><td>8.8</td></tr> <tr><td>-- 1 1</td><td>132</td><td>-- 3 1</td><td>33.1</td><td>-- 5 1</td><td>8.3</td></tr> <tr><td>-- 1 2</td><td>125</td><td>-- 3 2</td><td>31.3</td><td>-- 5 2</td><td>7.8</td></tr> <tr><td>-- 1 3</td><td>118</td><td>-- 3 3</td><td>29.6</td><td>-- 5 3</td><td>7.4</td></tr> <tr><td>-- 1 4</td><td>112</td><td>-- 3 4</td><td>28.1</td><td>-- 5 4</td><td>7.0</td></tr> <tr><td>-- 1 5</td><td>107</td><td>-- 3 5</td><td>26.8</td><td>-- 5 5</td><td>6.7</td></tr> <tr><td>-- 1 6</td><td>102</td><td>-- 3 6</td><td>25.6</td><td>-- 5 6</td><td>6.4</td></tr> <tr><td>-- 1 7</td><td>97</td><td>-- 3 7</td><td>24.5</td><td>-- 5 7</td><td>6.1</td></tr> <tr><td>-- 1 8</td><td>93</td><td>-- 3 8</td><td>23.4</td><td>-- 5 8</td><td>5.9</td></tr> <tr><td>-- 1 9</td><td>90</td><td>-- 3 9</td><td>22.5</td><td>-- 5 9</td><td>5.6</td></tr> <tr><td>-- 1 A</td><td>86</td><td>-- 3 A</td><td>21.6</td><td>-- 5 A</td><td>5.4</td></tr> <tr><td>-- 1 B</td><td>83</td><td>-- 3 B</td><td>20.8</td><td>-- 5 B</td><td>5.2</td></tr> <tr><td>-- 1 C</td><td>80</td><td>-- 3 C</td><td>20.1</td><td>-- 5 C</td><td>5.0</td></tr> <tr><td>-- 1 D</td><td>77</td><td>-- 3 D</td><td>19.4</td><td>-- 5 D</td><td>4.9</td></tr> <tr><td>-- 1 E</td><td>75</td><td>-- 3 E</td><td>18.8</td><td>-- 5 E</td><td>4.7</td></tr> <tr><td>-- 1 F</td><td>72</td><td>-- 3 F</td><td>18.2</td><td>-- 5 F</td><td>4.5</td></tr> </tbody> </table> <p>Table 5.7 Notch depth selection</p> <table border="1"> <thead> <tr> <th>Setting value</th> <th>Depth [dB]</th> <th>Setting value</th> <th>Depth [dB]</th> </tr> </thead> <tbody> <tr><td>_ 0 _ _</td><td>-40.0</td><td>_ 8 _ _</td><td>-6.0</td></tr> <tr><td>_ 1 _ _</td><td>-24.1</td><td>_ 9 _ _</td><td>-5.0</td></tr> <tr><td>_ 2 _ _</td><td>-18.1</td><td>_ A _ _</td><td>-4.1</td></tr> <tr><td>_ 3 _ _</td><td>-14.5</td><td>_ B _ _</td><td>-3.3</td></tr> <tr><td>_ 4 _ _</td><td>-12.0</td><td>_ C _ _</td><td>-2.5</td></tr> <tr><td>_ 5 _ _</td><td>-10.1</td><td>_ D _ _</td><td>-1.8</td></tr> <tr><td>_ 6 _ _</td><td>-8.5</td><td>_ E _ _</td><td>-1.2</td></tr> <tr><td>_ 7 _ _</td><td>-7.2</td><td>_ F _ _</td><td>-0.6</td></tr> </tbody> </table>							Setting value	Frequency [Hz]	Setting value	Frequency [Hz]	Setting value	Frequency [Hz]	-- 0 0	Disabled	-- 2 0	70	-- 4 0	17.6	-- 0 1	2250	-- 2 1	66	-- 4 1	16.5	-- 0 2	1125	-- 2 2	62	-- 4 2	15.6	-- 0 3	750	-- 2 3	59	-- 4 3	14.8	-- 0 4	562	-- 2 4	56	-- 4 4	14.1	-- 0 5	450	-- 2 5	53	-- 4 5	13.4	-- 0 6	375	-- 2 6	51	-- 4 6	12.8	-- 0 7	321	-- 2 7	48	-- 4 7	12.2	-- 0 8	281	-- 2 8	46	-- 4 8	11.7	-- 0 9	250	-- 2 9	45	-- 4 9	11.3	-- 0 A	225	-- 2 A	43	-- 4 A	10.8	-- 0 B	204	-- 2 B	41	-- 4 B	10.4	-- 0 C	187	-- 2 C	40	-- 4 C	10	-- 0 D	173	-- 2 D	38	-- 4 D	9.7	-- 0 E	160	-- 2 E	37	-- 4 E	9.4	-- 0 F	150	-- 2 F	36	-- 4 F	9.1	-- 1 0	140	-- 3 0	35.2	-- 5 0	8.8	-- 1 1	132	-- 3 1	33.1	-- 5 1	8.3	-- 1 2	125	-- 3 2	31.3	-- 5 2	7.8	-- 1 3	118	-- 3 3	29.6	-- 5 3	7.4	-- 1 4	112	-- 3 4	28.1	-- 5 4	7.0	-- 1 5	107	-- 3 5	26.8	-- 5 5	6.7	-- 1 6	102	-- 3 6	25.6	-- 5 6	6.4	-- 1 7	97	-- 3 7	24.5	-- 5 7	6.1	-- 1 8	93	-- 3 8	23.4	-- 5 8	5.9	-- 1 9	90	-- 3 9	22.5	-- 5 9	5.6	-- 1 A	86	-- 3 A	21.6	-- 5 A	5.4	-- 1 B	83	-- 3 B	20.8	-- 5 B	5.2	-- 1 C	80	-- 3 C	20.1	-- 5 C	5.0	-- 1 D	77	-- 3 D	19.4	-- 5 D	4.9	-- 1 E	75	-- 3 E	18.8	-- 5 E	4.7	-- 1 F	72	-- 3 F	18.2	-- 5 F	4.5	Setting value	Depth [dB]	Setting value	Depth [dB]	_ 0 _ _	-40.0	_ 8 _ _	-6.0	_ 1 _ _	-24.1	_ 9 _ _	-5.0	_ 2 _ _	-18.1	_ A _ _	-4.1	_ 3 _ _	-14.5	_ B _ _	-3.3	_ 4 _ _	-12.0	_ C _ _	-2.5	_ 5 _ _	-10.1	_ D _ _	-1.8	_ 6 _ _	-8.5	_ E _ _	-1.2	_ 7 _ _	-7.2	_ F _ _	-0.6
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## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB46 NH3 Machine resonance suppression filter 3		Set the notch frequency of the machine resonance suppression filter 3. To enable the setting value, select "Enabled ( _ _ _ 1)" of "Machine resonance suppression filter 3 selection" in [Pr. PB47].  Setting range: 10 to 4500	4500 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB47 NHQ3 Notch shape selection 3	Set the shape of the machine resonance suppression filter 3.					
	_ _ _ x	Machine resonance suppression filter 3 selection 0: Disabled 1: Enabled	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ _ x _	Notch depth selection 0: -40 dB 1: -14 dB 2: -8 dB 3: -4 dB	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ x _ _	Notch width selection 0: $\alpha = 2$ 1: $\alpha = 3$ 2: $\alpha = 4$ 3: $\alpha = 5$	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x _ _ _	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
PB48 NH4 Machine resonance suppression filter 4		Set the notch frequency of the machine resonance suppression filter 4. To enable the setting value, select "Enabled ( _ _ _ 1)" of "Machine resonance suppression filter 4 selection" in [Pr. PB49].  Setting range: 10 to 4500	4500 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB49 NHQ4 Notch shape selection 4	Set the shape of the machine resonance suppression filter 4.					
	_ _ _ x	Machine resonance suppression filter 4 selection 0: Disabled 1: Enabled When you select "Enabled" of this digit, [Pr. PB17 Shaft resonance suppression filter] is not available.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ _ x _	Notch depth selection 0: -40 dB 1: -14 dB 2: -8 dB 3: -4 dB	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_ x _ _	Notch width selection 0: $\alpha = 2$ 1: $\alpha = 3$ 2: $\alpha = 4$ 3: $\alpha = 5$	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x _ _ _	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
PB50 NH5 Machine resonance suppression filter 5		Set the notch frequency of the machine resonance suppression filter 5. To enable the setting value, select "Enabled ( _ _ _ 1)" of "Machine resonance suppression filter 5 selection" in [Pr. PB51].  Setting range: 10 to 4500	4500 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB51 NHQ5 Notch shape selection 5	___x	Machine resonance suppression filter 5 selection 0: Disabled 1: Enabled	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	--x_	Notch depth selection 0: -40 dB 1: -14 dB 2: -8 dB 3: -4 dB	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_x__	Notch width selection 0: $\alpha = 2$ 1: $\alpha = 3$ 2: $\alpha = 4$ 3: $\alpha = 5$	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x___	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB52 VRF21 Vibration suppression control 2 - Vibration frequency		Set the vibration frequency for vibration suppression control 2 to suppress low-frequency machine vibration. When "Vibration suppression control 2 tuning mode selection" is set to "Automatic setting (_ _ 1 _)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting (_ _ 2 _)" is selected, the setting written to the parameter is used. To enable the setting value, set "Vibration suppression mode selection" to "3 inertia mode (_ _ _ 1)" in [Pr. PA24].  Setting range: 0.1 to 300.0	100.0 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB53 VRF22 Vibration suppression control 2 - Resonance frequency		Set the resonance frequency for vibration suppression control 2 to suppress low-frequency machine vibration. When "Vibration suppression control 2 tuning mode selection" is set to "Automatic setting (_ _ 1 _)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting (_ _ 2 _)" is selected, the setting written to the parameter is used. To enable the setting value, set "Vibration suppression mode selection" to "3 inertia mode (_ _ _ 1)" in [Pr. PA24].  Setting range: 0.1 to 300.0	100.0 [Hz]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB54 VRF23 Vibration suppression control 2 - Vibration frequency damping		Set a damping of the vibration frequency for vibration suppression control 2 to suppress low-frequency machine vibration. When "Vibration suppression control 2 tuning mode selection" is set to "Automatic setting (_ _ 1 _)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting (_ _ 2 _)" is selected, the setting written to the parameter is used. To enable the setting value, set "Vibration suppression mode selection" to "3 inertia mode (_ _ _ 1)" in [Pr. PA24].  Setting range: 0.00 to 0.30	0.00	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PB55 VRF24 Vibration suppression control 2 - Resonance frequency damping		Set a damping of the resonance frequency for vibration suppression control 2 to suppress low-frequency machine vibration. When "Vibration suppression control 2 tuning mode selection" is set to "Automatic setting (_ _ 1 _)" in [Pr. PB02], this parameter will be set automatically. When "Manual setting (_ _ 2 _)" is selected, the setting written to the parameter is used. To enable the setting value, set "Vibration suppression mode selection" to "3 inertia mode (_ _ _ 1)" in [Pr. PA24].  Setting range: 0.00 to 0.30	0.00	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

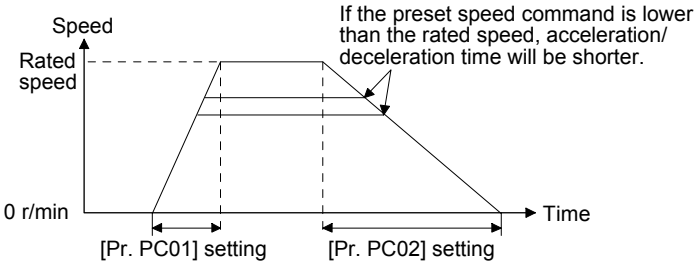
## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB56 VRF21B Vibration suppression control 2 - Vibration frequency after gain switching		<p>Set the vibration frequency for vibration suppression control 2 when the gain switching is enabled.</p> <p>When you set a value less than 0.1 Hz, the value will be the same as [Pr. PB52].</p> <p>This parameter will be enabled only when the following conditions are fulfilled.</p> <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression mode selection" in [Pr. PA24] is "3 inertia mode ( _ _ _ 1)".</li> <li>• "Vibration suppression control 2 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ 2 _)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> <p>Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.</p> <p>Setting range: 0.0 to 300.0</p>	0.0 [Hz]	<input type="radio"/>		
PB57 VRF22B Vibration suppression control 2 - Resonance frequency after gain switching		<p>Set the resonance frequency for vibration suppression control 2 when the gain switching is enabled.</p> <p>When you set a value less than 0.1 Hz, the value will be the same as [Pr. PB53].</p> <p>This parameter will be enabled only when the following conditions are fulfilled.</p> <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression mode selection" in [Pr. PA24] is "3 inertia mode ( _ _ _ 1)".</li> <li>• "Vibration suppression control 2 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ 2 _)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> <p>Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.</p> <p>Setting range: 0.0 to 300.0</p>	0.0 [Hz]	<input type="radio"/>		
PB58 VRF23B Vibration suppression control 2 - Vibration frequency damping after gain switching		<p>Set a damping of the vibration frequency for vibration suppression control 2 when the gain switching is enabled.</p> <p>This parameter will be enabled only when the following conditions are fulfilled.</p> <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression mode selection" in [Pr. PA24] is "3 inertia mode ( _ _ _ 1)".</li> <li>• "Vibration suppression control 2 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ 2 _)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> <p>Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.</p> <p>Setting range: 0.00 to 0.30</p>	0.00	<input type="radio"/>		
PB59 VRF24B Vibration suppression control 2 - Resonance frequency damping after gain switching		<p>Set a damping of the resonance frequency for vibration suppression control 2 when the gain switching is enabled.</p> <p>This parameter will be enabled only when the following conditions are fulfilled.</p> <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode ( _ _ _ 3)".</li> <li>• "Vibration suppression mode selection" in [Pr. PA24] is "3 inertia mode ( _ _ _ 1)".</li> <li>• "Vibration suppression control 2 tuning mode selection" in [Pr. PB02] is "Manual setting ( _ _ 2 _)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) ( _ _ _ 1)".</li> </ul> <p>Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.</p> <p>Setting range: 0.00 to 0.30</p>	0.00	<input type="radio"/>		

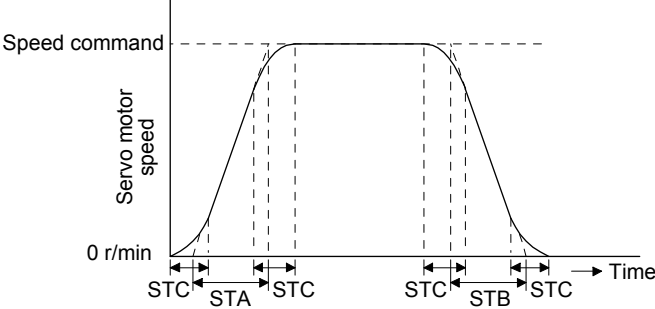
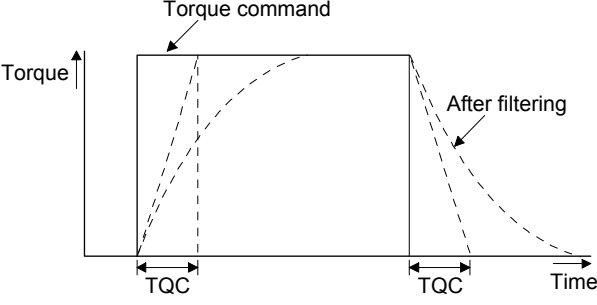
## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PB60 PG1B Model loop gain after gain switching		<p>Set the model loop gain when the gain switching is enabled.</p> <p>When you set a value less than 1.0 rad/s, the value will be the same as [Pr. PB07].</p> <p>This parameter will be enabled only when the following conditions are fulfilled.</p> <ul style="list-style-type: none"> <li>• "Gain adjustment mode selection" in [Pr. PA08] is "Manual mode (___ 3)".</li> <li>• "Gain switching selection" in [Pr. PB26] is "Input device (gain switching (CDP)) (___ 1)".</li> </ul> <p>Switching during driving may cause a shock. Be sure to switch them after the servo motor stops.</p> <p>Setting range: 0.0 to 2000.0</p>	0.0 [rad/s]	<input type="radio"/>	<input type="radio"/>	

### 5.2.3 Extension setting parameters ([Pr. PC\_\_])

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC01 STA Acceleration time constant		<p>Set the acceleration time required to reach the rated speed from 0 r/min in response to VC (Analog speed command) and [Pr. PC05 Internal speed command 1] to [Pr. PC11 Internal speed command 7].</p>  <p>For example for the servo motor of 3000 r/min rated speed, set 3000 (3 s) to increase speed from 0 r/min to 1000 r/min in 1 second.</p> <p>Setting range: 0 to 50000</p>	0 [ms]		<input type="radio"/>	<input type="radio"/>
PC02 STB Deceleration time constant		<p>Set the deceleration time required to reach 0 r/min from the rated speed in response to VC (Analog speed command) and [Pr. PC05 Internal speed command 1] to [Pr. PC11 Internal speed command 7].</p> <p>Setting range: 0 to 50000</p>	0 [ms]		<input type="radio"/>	<input type="radio"/>

# 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC03 STC S-pattern acceleration/ deceleration time constant		<p>Start/stop the servo motor smoothly. Set the time of the arc part for S-pattern acceleration/deceleration. Setting "0" will make it linear acceleration/deceleration.</p>  <p>STA: Acceleration time constant ([Pr. PC01]) STB: Deceleration time constant ([Pr. PC02]) STC: S-pattern acceleration/deceleration time constant ([Pr. PC03])</p> <p>Long setting of STA (acceleration time constant) or STB (deceleration time constant) may produce an error in the time of the arc part for the setting of the S-pattern acceleration/deceleration time constant. The upper limit value of the actual arc part time is limited by</p> $\frac{2000000}{STA} \text{ for acceleration or by } \frac{2000000}{STB} \text{ for deceleration.}$ <p>(Example) At the setting of STA 20000, STB 5000 and STC 200, the actual arc part times are as follows.</p> <p>Acceleration: 100 ms  <math>\frac{2000000}{20000} = 100 \text{ [ms]} &lt; 200 \text{ [ms]}</math>            Therefore, it will be limited to 100 ms.</p> <p>Deceleration: 200 ms  <math>\frac{2000000}{5000} = 400 \text{ [ms]} &gt; 200 \text{ [ms]}</math>            Therefore, it will be 200 ms as you set.</p> <p>Setting range: 0 to 5000</p>	0 [ms]		<input type="radio"/>	<input type="radio"/>
PC04 TQC Torque command time constant		<p>Set the constant of a primary delay to the torque command.</p>  <p>TQC: Torque command time constant</p> <p>Setting range: 0 to 50000</p>	0 [ms]			<input type="radio"/>

## 5. PARAMETERS

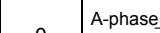
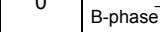
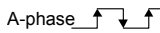
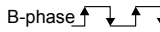
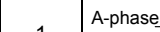
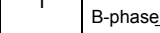
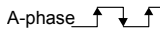
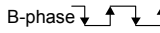
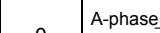
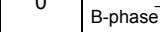
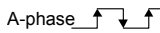
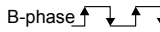
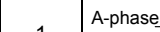
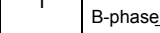
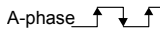
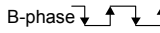
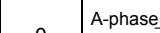
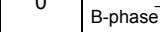
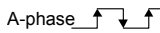
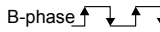
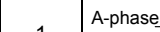
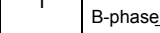
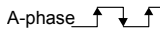
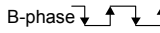
No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC05 SC1 Internal speed command 1/internal speed limit 1		Set speed 1 of internal speed commands. Setting range: 0 to permissible instantaneous speed	100 [r/min]		○	
		Set speed 1 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC06 SC2 Internal speed command 2 Internal speed limit 2		Set speed 2 of internal speed commands. Setting range: 0 to permissible instantaneous speed	500 [r/min]		○	
		Set speed 2 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC07 SC3 Internal speed command 3 Internal speed limit 3		Set speed 3 of internal speed commands. Setting range: 0 to permissible instantaneous speed	1000 [r/min]		○	
		Set speed 3 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC08 SC4 Internal speed command 4 Internal speed limit 4		Set speed 4 of internal speed commands. Setting range: 0 to permissible instantaneous speed	200 [r/min]		○	
		Set speed 4 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC09 SC5 Internal speed command 5 Internal speed limit 5		Set speed 5 of internal speed commands. Setting range: 0 to permissible instantaneous speed	300 [r/min]		○	
		Set speed 5 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC10 SC6 Internal speed command 6 Internal speed limit 6		Set speed 6 of internal speed commands. Setting range: 0 to permissible instantaneous speed	500 [r/min]		○	
		Set speed 6 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC11 SC7 Internal speed command 7 Internal speed limit 7		Set speed 7 of internal speed commands. Setting range: 0 to permissible instantaneous speed	800 [r/min]		○	
		Set speed 7 of internal speed limits. Setting range: 0 to permissible instantaneous speed				
PC12 VCM Analog speed command - Maximum speed Analog speed limit - Maximum speed		Set the speed at the maximum input voltage (10 V) of VC (Analog speed command). When "0" is set, the analog speed command maximum speed would be the rated speed of the servo motor connected. If a value equal to or larger than the permissible speed is inputted to VC, the value is clamped at the permissible speed. Setting range: 0 to 50000	0 [r/min]		○	
		Set the speed at the maximum input voltage (10 V) of VLA (Analog speed limit). When "0" is set, the analog speed command maximum speed would be the rated speed of the servo motor connected. If a limited value equal to or larger than the permissible speed is inputted to VLA, the value is clamped at the permissible speed. Setting range: 0 to 50000				



## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																														
				P	S	T																												
PC13 TLC Analog torque command maximum output		Set the output torque at the analog torque command voltage (TC = ±8 V) of +8 V on the assumption that the maximum torque is 100.0%. For example, set 50.0.  The maximum torque $\times \frac{50.0}{100.0}$ is outputted.  If a value equal to or larger than the maximum torque is inputted to TC, the value is clamped at the maximum torque. Setting range: 0.0 to 1000.0	100.0 [%]			○																												
PC14 MOD1 Analog monitor 1 output	__ x x	Analog monitor 1 output selection Select a signal to output to MO1 (Analog monitor 1). Refer to app. 3 (3) for detection point of output selection. Refer to table 5.8 for settings.	00h	○	○	○																												
	_ x _ _	For manufacturer setting	0h																															
	x _ _ _		0h																															
<p>Table 5.8 Analog monitor setting value</p> <table border="1"> <thead> <tr> <th>Setting value</th> <th>Item</th> </tr> </thead> <tbody> <tr><td>__ 0 0</td><td>Servo motor speed (±8 V/max. speed) (Note 3)</td></tr> <tr><td>__ 0 1</td><td>Torque (±8 V/max. torque) (Note 2)</td></tr> <tr><td>__ 0 2</td><td>Servo motor speed (+8 V/max. speed) (Note 3)</td></tr> <tr><td>__ 0 3</td><td>Torque (+8 V/max. torque) (Note 2)</td></tr> <tr><td>__ 0 4</td><td>Current command (±8 V/max. current command)</td></tr> <tr><td>__ 0 5</td><td>The command pulse frequency (±10 V/4 Mpulses/s)</td></tr> <tr><td>__ 0 6</td><td>Servo motor-side droop pulses (±10 V/100 pulses) (Note 1)</td></tr> <tr><td>__ 0 7</td><td>Servo motor-side droop pulses (±10 V/1000 pulses) (Note 1)</td></tr> <tr><td>__ 0 8</td><td>Servo motor-side droop pulses (±10 V/10000 pulses) (Note 1)</td></tr> <tr><td>__ 0 9</td><td>Servo motor-side droop pulses (±10 V/100000 pulses) (Note 1)</td></tr> <tr><td>__ 0 D</td><td>Bus voltage (+8 V/400 V)</td></tr> <tr><td>__ 0 E</td><td>Speed command 2 (±8 V/max. speed) (Note 3)</td></tr> <tr><td>__ 1 7</td><td>Internal temperature of encoder (±10 V/±128 °C)</td></tr> </tbody> </table> <p>Note 1. Encoder pulse unit 2. The value in [Pr. PA11] or [Pr. PA12] whichever higher is applied for the maximum torque. 3. The maximum speed of the HF-KN series servo motor is 4500 r/min and that of the HG-KN series is 5000 r/min. Please watch out when using an HG-KN series servo motor as a replacement for the HF-KN series servo motor because HG-KN series output 8 V at 5000 r/min. HG-KN series servo motors output 8 V at 6000 r/min when you set " _ _ _ 1" in [Pr. PA28] to change the maximum speed to 6000 r/min.</p>							Setting value	Item	__ 0 0	Servo motor speed (±8 V/max. speed) (Note 3)	__ 0 1	Torque (±8 V/max. torque) (Note 2)	__ 0 2	Servo motor speed (+8 V/max. speed) (Note 3)	__ 0 3	Torque (+8 V/max. torque) (Note 2)	__ 0 4	Current command (±8 V/max. current command)	__ 0 5	The command pulse frequency (±10 V/4 Mpulses/s)	__ 0 6	Servo motor-side droop pulses (±10 V/100 pulses) (Note 1)	__ 0 7	Servo motor-side droop pulses (±10 V/1000 pulses) (Note 1)	__ 0 8	Servo motor-side droop pulses (±10 V/10000 pulses) (Note 1)	__ 0 9	Servo motor-side droop pulses (±10 V/100000 pulses) (Note 1)	__ 0 D	Bus voltage (+8 V/400 V)	__ 0 E	Speed command 2 (±8 V/max. speed) (Note 3)	__ 1 7	Internal temperature of encoder (±10 V/±128 °C)
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PC15 MOD2 Analog monitor 2 output	__ x x	Analog monitor 2 output selection Select a signal to output to MO2 (Analog monitor 2). Refer to app. 3 (3) for detection point of output selection. Refer to [Pr. PC14] for settings.	01h	○	○	○																												
	_ x _ _	For manufacturer setting	0h																															
	x _ _ _		0h																															
PC16 MBR Electromagne tic brake sequence output		Set the delay time between MBR (Electromagnetic brake interlock) and the base drive circuit is shut-off.  Setting range: 0 to 1000	0 [ms]	○	○	○																												
PC17 ZSP Zero speed		Set the output range of ZSP (Zero speed detection). ZSP (Zero speed detection) has hysteresis of 20 r/min.  Setting range: 0 to 10000	50 [r/min]	○	○	○																												

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode													
				P	S	T											
PC18 *BPS Alarm history clear	___x	Alarm history clear selection Used to clear the alarm history. 0: Disabled 1: Enabled When "Enabled" is set, the alarm history will be cleared at the next power-on. After the alarm history is cleared, the setting is automatically disabled.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>											
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>											
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>											
	x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>											
PC19 *ENRS Encoder output pulse selection	___x	Encoder output pulse phase selection Select the encoder pulse direction. 0: Increasing A-phase 90° in CCW 1: Increasing A-phase 90° in CW  <table border="1" style="margin: 10px auto;"> <thead> <tr> <th rowspan="2">Setting value</th> <th colspan="2">Servo motor rotation direction</th> </tr> <tr> <th>CCW</th> <th>CW</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>A-phase  B-phase </td> <td>A-phase  B-phase </td> </tr> <tr> <td>1</td> <td>A-phase  B-phase </td> <td>A-phase  B-phase </td> </tr> </tbody> </table>	Setting value	Servo motor rotation direction		CCW	CW	0	A-phase  B-phase 	A-phase  B-phase 	1	A-phase  B-phase 	A-phase  B-phase 	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	Setting value	Servo motor rotation direction															
		CCW	CW														
	0	A-phase  B-phase 	A-phase  B-phase 														
1	A-phase  B-phase 	A-phase  B-phase 															
__x_	Encoder output pulse setting selection 0: Output pulse setting 1: Dividing ratio setting 2: The same output pulse setting as the command pulse 3: A-phase/B-phase pulse electronic gear setting When you select "1", the settings of [Pr. PA16 Encoder output pulses 2] will be disabled. When you select "2", the settings of [Pr. PA15 Encoder output pulses] and [Pr. PA16 Encoder output pulses 2] will be disabled. When you select the setting, do not change the settings in [Pr. PA06] and [Pr. PA07] after the power-on.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>												
_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>												
x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>												
PC20 *SNO Station No. setting		Set a station No. of the servo amplifier for RS-422 communication. Always set one station to one axis of the servo amplifier. Setting one station number to two or more stations will disable a normal communication.  Setting range: 0 to 31	0 [Station]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>											
PC21 *SOP RS-422 communi- cation function selection	Select the details of RS-422/RS-485 communication function.																
	___x	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>											
	__x_	RS-422 communication baud rate selection 0: 9600 [bps] 1: 19200 [bps] 2: 38400 [bps] 3: 57600 [bps] 4: 115200 [bps] 6: 4800 [bps]	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>											
	_x__	RS-422 communication response delay time selection 0: Disabled 1: Enabled (responding after 800 μs or longer delay time)	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>											
	x___	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>											

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode															
				P	S	T													
PC22 *COP1 Function selection C-1	___ x	For manufacturer setting	0h																
	__ x _		2h																
	_ x __		0h																
	x ___	Encoder cable communication method selection Select the encoder cable communication method. 0: Two-wire type 1: Four-wire type If the setting is incorrect, [AL. 16 Encoder initial communication error 1] or [AL. 20 Encoder normal communication error 1] occurs.	0h	○	○	○													
PC23 *COP2 Function selection C-2	___ x	Servo-lock selection at speed control stop Select the servo-lock selection at speed control stop. In the speed control mode, the servo motor shaft can be locked to prevent the shaft from being moved by an external force. 0: Enabled (servo-lock) The operation to maintain the stop position is performed. 1: Disabled (no servo-lock) The stop position is not maintained. The control to make the speed 0 r/min is performed.	0h		○														
	__ x _	For manufacturer setting	0h																
	_ x __	VC/VLA voltage averaging selection Select the VC/VLA voltage average. Set the filtering time when VC (Analog speed command) or VLA (Analog speed limit) is imported. Set 0 to vary the speed to voltage fluctuation in real time. Increase the set value to vary the speed slower to voltage fluctuation.	0h		○	○													
	<table border="1" style="margin-left: auto; margin-right: auto;"> <thead> <tr> <th>Setting value</th> <th>Filtering time [ms]</th> </tr> </thead> <tbody> <tr><td>0</td><td>0</td></tr> <tr><td>1</td><td>0.444</td></tr> <tr><td>2</td><td>0.888</td></tr> <tr><td>3</td><td>1.777</td></tr> <tr><td>4</td><td>3.555</td></tr> <tr><td>5</td><td>7.111</td></tr> </tbody> </table>		Setting value	Filtering time [ms]	0	0	1	0.444	2	0.888	3	1.777	4	3.555	5	7.111			
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0	0																		
1	0.444																		
2	0.888																		
3	1.777																		
4	3.555																		
5	7.111																		
	x ___	Speed limit selection at torque control Select the speed limit selection at torque control. 0: Enabled 1: Disabled Do not use this function except when configuring an external speed loop.	0h																
PC24 *COP3 Function selection C-3	___ x	In-position range unit selection Select a unit of in-position range. 0: Command input pulse unit 1: Servo motor encoder pulse unit	0h	○															
	__ x _	For manufacturer setting	0h																
	_ x __		0h																
	x ___	Error excessive alarm/error excessive warning level unit selection Select a setting unit for the error excessive alarm level set in [Pr. PC43] and for error excessive warning level setting with [Pr. PC73]. 0: 1 rev unit 1: 0.1 rev unit 2: 0.01 rev unit 3: 0.001 rev unit	0h	○															

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC26 *COP5 Function selection C-5	___x	[AL. 99 Stroke limit warning] selection Enable or disable [AL. 99 Stroke limit warning]. 0: Enabled 1: Disabled	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_x__		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x___		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC27 *COP6 Function selection C-6	___x	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_x__	Undervoltage alarm selection Select the alarm and warning that occurs when the bus voltage drops to the undervoltage alarm level. 0: [AL. 102] regardless of servo motor speed 1: [AL. E9.1] occurs when the servo motor speed is 50 r/min or less, and [AL. 10.2] occurs when the servo motor speed is over 50 r/min.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x___	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC30 STA2 Acceleration time constant 2		To enable the parameter, turn on STAB2 (Speed acceleration/deceleration selection). Set the acceleration time required to reach the rated speed from 0 r/min in response to VC (Analog speed command) and [Pr. PC05 Internal speed command 1] to [Pr. PC11 Internal speed command 7].  Setting range: 0 to 50000	0 [ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC31 STB2 Deceleration time constant 2		To enable the parameter, turn on STAB2 (Speed acceleration/deceleration selection). Set the deceleration time required to reach 0 r/min from the rated speed in response to VC (Analog speed command) and [Pr. PC05 Internal speed command 1] to [Pr. PC11 Internal speed command 7].  Setting range: 0 to 50000	0 [ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC32 CMX2 Commanded pulse multiplication numerator 2		To enable the parameter, select "Electronic gear (0 __ _)" of "Electronic gear selection" in [Pr. PA21].  Setting range: 1 to 16777215	1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC33 CMX3 Commanded pulse multiplication numerator 3		To enable the parameter, select "Electronic gear (0 __ _)" of "Electronic gear selection" in [Pr. PA21].  Setting range: 1 to 16777215	1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC34 CMX4 Commanded pulse multiplication numerator 4		To enable the parameter, select "Electronic gear (0 __ _)" of "Electronic gear selection" in [Pr. PA21].  Setting range: 1 to 16777215	1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC35 TL2 Internal torque limit 2		Set the parameter on the assumption that the maximum torque is 100 %. The parameter is for limiting the torque of the servo motor. No torque is generated when this parameter is set to "0.0". When TL1 (Internal torque limit selection) is turned on, Internal torque limits 1 and 2 are compared and the lower value will be enabled. Set the parameter referring to section 3.6.1 (5).  Setting range: 0.0 to 100.0	100.0 [%]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																
				P	S	T														
PC36 *DMD Status display selection	-- x x	Status display selection at power-on Select a status display shown at power-on. 00: Cumulative feedback pulses 01: Servo motor speed 02: Droop pulses 03: Cumulative command pulses 04: Command pulse frequency 05: Analog speed command voltage (Note 1) 06: Analog torque command voltage (Note 2) 07: Regenerative load ratio 08: Effective load ratio 09: Peak load ratio 0A: Instantaneous torque 0B: Within one-revolution position (1 pulse unit) 0C: Within one-revolution position (100 pulses unit) 0D: ABS counter (Note 3) 0E: Load to motor inertia ratio 0F: Bus voltage 10: Internal temperature of encoder 11: Settling time 12: Oscillation detection frequency 13: Number of tough operations 14: Unit power consumption (1 W unit) 15: Unit power consumption (1 kW unit) 16: Unit total power consumption (1 Wh unit) 17: Unit total power consumption (100 kWh unit)  Note 1. It is for the speed control mode. It will be the analog speed limit voltage in the torque control mode. 2. It is for the torque control mode. It will be the analog torque limit voltage in the speed control mode and position control mode. 3. Travel distance from power on is displayed by counter value.	00h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>														
	_ x _ _	Status display at power-on in corresponding control mode 0: Depends on the control mode  <table border="1" style="margin-left: auto; margin-right: auto;"> <thead> <tr> <th>Control mode</th> <th>Status display at power-on</th> </tr> </thead> <tbody> <tr> <td>Position</td> <td>Cumulative feedback pulses</td> </tr> <tr> <td>Position/speed</td> <td>Cumulative feedback pulses/servo motor speed</td> </tr> <tr> <td>Speed</td> <td>Servo motor speed</td> </tr> <tr> <td>Speed/torque</td> <td>Servo motor speed/analog torque command voltage</td> </tr> <tr> <td>Torque</td> <td>Analog torque command voltage</td> </tr> <tr> <td>Torque/position</td> <td>Analog torque command voltage/cumulative feedback pulses</td> </tr> </tbody> </table> 1: Depends on the last two digit setting of the parameter	Control mode	Status display at power-on	Position	Cumulative feedback pulses	Position/speed	Cumulative feedback pulses/servo motor speed	Speed	Servo motor speed	Speed/torque	Servo motor speed/analog torque command voltage	Torque	Analog torque command voltage	Torque/position	Analog torque command voltage/cumulative feedback pulses	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	Control mode	Status display at power-on																		
Position	Cumulative feedback pulses																			
Position/speed	Cumulative feedback pulses/servo motor speed																			
Speed	Servo motor speed																			
Speed/torque	Servo motor speed/analog torque command voltage																			
Torque	Analog torque command voltage																			
Torque/position	Analog torque command voltage/cumulative feedback pulses																			
x _ _ _	For manufacturer setting		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>														

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC37 VCO Analog speed command offset/Analog speed limit offset		<p>Set the offset voltage of VC (Analog speed command). For example, if CCW rotation is provided by switching on ST1 (Forward rotation start) with applying 0 V to VC, set a negative value. When automatic VC offset is used, the automatically offset value is set to this parameter. (Refer to section 4.5.4.) The initial value is provided before shipment by the automatic VC offset function on condition that the voltage between VC and LG is 0 V.</p> <p>Setting range: -9999 to 9999</p>	The value differs depending on the servo amplifiers. [mV]		<input type="radio"/>	
		<p>Set the offset voltage of VLA (Analog speed limit). For example, if CCW rotation is provided by switching on RS1 (Forward rotation selection) with applying 0 V to VLA, set a negative value. When automatic VC offset is used, the automatically offset value is set to this parameter. (Refer to section 4.5.4.) The initial value is provided before shipment by the automatic VC offset function on condition that the voltage between VLA and LG is 0 V.</p> <p>Setting range: -9999 to 9999</p>				<input type="radio"/>
PC38 TPO Analog torque command offset/Analog torque limit offset		<p>Set the offset voltage of TC (Analog torque command).</p> <p>Setting range: -9999 to 9999</p>	0 [mV]			<input type="radio"/>
		<p>Set the offset voltage of TLA (Analog torque limit).</p> <p>Setting range: -9999 to 9999</p>			<input type="radio"/>	
PC39 MO1 Analog monitor 1 offset		<p>Set the offset voltage of MO1 (Analog monitor 1).</p> <p>Setting range: -9999 to 9999</p>	0 [mV]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC40 MO2 Analog monitor 2 offset		<p>Set the offset voltage of MO2 (Analog monitor 2).</p> <p>Setting range: -9999 to 9999</p>	0 [mV]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PC43 ERZ Error excessive alarm level		<p>Set an error excessive alarm level. You can change the setting unit with "Error excessive alarm/error excessive warning level unit selection" in [Pr. PC24]. However, setting "0" will be 3 rev. Setting over 200 rev will be clamped with 200 rev.</p> <p>Setting range: 0 to 1000</p>	0 [rev]	<input type="radio"/>		

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC51 RSBR Forced stop deceleration time constant		<p>Set deceleration time constant when you use the forced stop deceleration function. Set the time per ms from the rated speed to 0 r/min. Setting "0" will be 100 ms.</p> <p>[Precautions]</p> <ul style="list-style-type: none"> <li>• If the servo motor torque is saturated at the maximum torque during forced stop deceleration because the set time is too short, the time to stop will be longer than the set time constant.</li> <li>• [AL. 50 Overload alarm 1] or [AL. 51 Overload alarm 2] may occur during forced stop deceleration, depending on the set value.</li> <li>• After an alarm that leads to a forced stop deceleration, if an alarm that does not lead to a forced stop deceleration occurs or if the power supply is cut, dynamic braking will start regardless of the deceleration time constant setting.</li> </ul> <p>Setting range: 0 to 20000</p>	100 [ms]	<input type="radio"/>	<input type="radio"/>	
PC54 RSUP1 Vertical axis freefall prevention compensation amount		<p>Set the compensation amount of the vertical axis freefall prevention function. Set it per servo motor rotation amount. The function will pull up an shaft per rotation amount to the servo motor rotation direction at the time of inputting forward rotation pulse for a positive value, and at the time of inputting reverse rotation pulse for a negative value. For example, if a positive compensation amount is set when the [Pr. PA14 Rotation direction selection] setting is "1", compensation will be performed to the CW direction. The vertical axis freefall prevention function is performed when all of the following conditions are met.</p> <ol style="list-style-type: none"> <li>1) Position control mode</li> <li>2) The value of the parameter is other than "0".</li> <li>3) The forced stop deceleration function is enabled.</li> <li>4) Alarm occurs or EM2 turns off when the servo motor speed is zero speed or less.</li> <li>5) MBR (Electromagnetic brake interlock) was enabled in [Pr. PD24], [Pr. PD25], and [Pr. PD28], and the base circuit shut-off delay time was set in [Pr. PC16].</li> </ol> <p>Setting range: -25000 to 25000</p>	0 [0.0001 rev]	<input type="radio"/>		
PC60 *COPD Function selection C-D	___x	<p>Motor-less operation selection Select the motor-less operation. 0: Disabled 1: Enabled</p>	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___	<p>[AL. 9B Error excessive warning] selection 0: [AL. 9B Error excessive warning] is disabled. 1: [AL. 9B Error excessive warning] is enabled. This parameter is available with servo amplifiers with software version B4 or later.</p>	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PC73 ERW Error excessive warning level		<p>Set an error excessive warning level.</p> <p>To enable the parameter, select "Enabled (1 _ _ _)" of "[AL. 9B Error excessive warning] selection" in [Pr. PC60].</p> <p>You can change the setting unit with "Error excessive alarm/error excessive warning level unit selection" in [Pr. PC24].</p> <p>Set the level in rev unit. When "0" is set, 1 rev will be applied. Setting over 200 rev will be clamped with 200 rev.</p> <p>When an error reaches the set value, [AL. 9B Error excessive warning] will occur. When the error decreases lower than the set value, the warning will be canceled automatically. The minimum pulse width of the warning signal is 100 [ms].</p> <p>Set as follows: [Pr. PC73 Error excessive warning level] &lt; [Pr. PC43 Error excessive alarm level] When you set as [Pr. PC73 Error excessive warning level] ≥ [Pr. PC43 Error excessive alarm level], [AL. 52 Error excessive] will occur earlier than the warning.</p> <p>This parameter setting is available with servo amplifiers with software version B4 or later.</p> <p>Setting range: 0 to 1000</p>	0 [rev]	○		



# 5. PARAMETERS

## 5.2.4 I/O setting parameters ([Pr. PD\_ \_])

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																															
				P	S	T																																													
PD01		Select input devices to turn on them automatically.																																																	
*DIA1																																																			
Input signal automatic on selection 1	_ _ _ x (HEX)	_ _ _ x (BIN): For manufacturer setting	0h																																																
		_ _ x _ (BIN): For manufacturer setting																																																	
		_ x _ _ (BIN): SON (Servo-on)		○	○	○																																													
		0: Disabled (Use for an external input signal.) 1: Enabled (automatic on)																																																	
		x _ _ _ (BIN): For manufacturer setting																																																	
	_ _ x _ (HEX)	_ _ _ x (BIN): PC (Proportional control)	0h	○	○																																														
		0: Disabled (Use for an external input signal.) 1: Enabled (automatic on)																																																	
		_ _ x _ (BIN): TL (External torque limit selection)		○	○																																														
		0: Disabled (Use for an external input signal.) 1: Enabled (automatic on)																																																	
		_ x _ _ (BIN): For manufacturer setting																																																	
		x _ _ _ (BIN): For manufacturer setting																																																	
	_ x _ _ (HEX)	_ _ _ x (BIN): For manufacturer setting	0h																																																
_ _ x _ (BIN): For manufacturer setting																																																			
_ x _ _ (BIN): LSP (Forward rotation stroke end)		○		○																																															
0: Disabled (Use for an external input signal.) 1: Enabled (automatic on)																																																			
	x _ _ _ (BIN): LSN (Reverse rotation stroke end)																																																		
	0: Disabled (Use for an external input signal.) 1: Enabled (automatic on)																																																		
x _ _ _	For manufacturer setting		0h																																																
Convert the setting value into hexadecimal as follows.																																																			
<table border="1" style="margin-left: 20px;"> <thead> <tr> <th>Signal name</th> <th colspan="2">Initial value</th> </tr> <tr> <td></td> <th>BIN</th> <th>HEX</th> </tr> </thead> <tbody> <tr> <td></td> <td>0</td> <td rowspan="4">0</td> </tr> <tr> <td></td> <td>0</td> </tr> <tr> <td>SON (Servo-on)</td> <td>0</td> </tr> <tr> <td></td> <td>0</td> </tr> </tbody> </table> <table border="1" style="margin-left: 20px;"> <thead> <tr> <th>Signal name</th> <th colspan="2">Initial value</th> </tr> <tr> <td></td> <th>BIN</th> <th>HEX</th> </tr> </thead> <tbody> <tr> <td>PC (Proportional control)</td> <td>0</td> <td rowspan="4">0</td> </tr> <tr> <td>TL (External torque limit selection)</td> <td>0</td> </tr> <tr> <td></td> <td>0</td> </tr> <tr> <td></td> <td>0</td> </tr> </tbody> </table> <table border="1" style="margin-left: 20px;"> <thead> <tr> <th>Signal name</th> <th colspan="2">Initial value</th> </tr> <tr> <td></td> <th>BIN</th> <th>HEX</th> </tr> </thead> <tbody> <tr> <td></td> <td>0</td> <td rowspan="4">0</td> </tr> <tr> <td></td> <td>0</td> </tr> <tr> <td>LSP (Forward rotation stroke end)</td> <td>0</td> </tr> <tr> <td>LSN (Reverse rotation stroke end)</td> <td>0</td> </tr> </tbody> </table> <p style="margin-left: 20px;">BIN 0: Use for an external input signal. BIN 1: Automatic on</p>							Signal name	Initial value			BIN	HEX		0	0		0	SON (Servo-on)	0		0	Signal name	Initial value			BIN	HEX	PC (Proportional control)	0	0	TL (External torque limit selection)	0		0		0	Signal name	Initial value			BIN	HEX		0	0		0	LSP (Forward rotation stroke end)	0	LSN (Reverse rotation stroke end)	0
Signal name	Initial value																																																		
	BIN	HEX																																																	
	0	0																																																	
	0																																																		
SON (Servo-on)	0																																																		
	0																																																		
Signal name	Initial value																																																		
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PC (Proportional control)	0	0																																																	
TL (External torque limit selection)	0																																																		
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Signal name	Initial value																																																		
	BIN	HEX																																																	
	0	0																																																	
	0																																																		
LSP (Forward rotation stroke end)	0																																																		
LSN (Reverse rotation stroke end)	0																																																		

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																																																																	
				P	S	T																																																																															
PD03 *DI1L Input device selection 1L	Any input device can be assigned to the CN1-15 pin.																																																																																				
	-- x x	Position control mode - Device selection Refer to table 5.9 for settings.	02h	○	/	/																																																																															
	x x --	Speed control mode - Device selection Refer to table 5.9 for settings.	02h	/	○	/																																																																															
<b>Table 5.9 Selectable input devices</b> <table border="1" style="margin: auto;"> <thead> <tr> <th rowspan="2">Setting value</th> <th colspan="3">Input device (Note 1)</th> </tr> <tr> <th>P</th> <th>S</th> <th>T</th> </tr> </thead> <tbody> <tr><td>-- 0 2</td><td>SON</td><td>SON</td><td>SON</td></tr> <tr><td>-- 0 3</td><td>RES</td><td>RES</td><td>RES</td></tr> <tr><td>-- 0 4</td><td>PC</td><td>PC</td><td>/</td></tr> <tr><td>-- 0 5</td><td>TL</td><td>TL</td><td>/</td></tr> <tr><td>-- 0 6</td><td>CR</td><td>/</td><td>/</td></tr> <tr><td>-- 0 7</td><td>/</td><td>ST1</td><td>RS2</td></tr> <tr><td>-- 0 8</td><td>/</td><td>ST2</td><td>RS1</td></tr> <tr><td>-- 0 9</td><td>TL1</td><td>TL1</td><td>/</td></tr> <tr><td>-- 0 A</td><td>LSP</td><td>LSP</td><td>/</td></tr> <tr><td>-- 0 B</td><td>LSN</td><td>LSN</td><td>/</td></tr> <tr><td>-- 0 D</td><td>CDP</td><td>CDP</td><td>/</td></tr> <tr><td>-- 2 0</td><td>/</td><td>SP1</td><td>SP1</td></tr> <tr><td>-- 2 1</td><td>/</td><td>SP2</td><td>SP2</td></tr> <tr><td>-- 2 2</td><td>/</td><td>SP3</td><td>SP3</td></tr> <tr><td>-- 2 3</td><td>LOP (Note 2)</td><td>LOP (Note 2)</td><td>LOP (Note 2)</td></tr> <tr><td>-- 2 4</td><td>CM1</td><td>/</td><td>/</td></tr> <tr><td>-- 2 5</td><td>CM2</td><td>/</td><td>/</td></tr> <tr><td>-- 2 6</td><td>/</td><td>STAB2</td><td>STAB2</td></tr> </tbody> </table> <p style="text-align: center;">           Note 1. P: position control mode, S: speed control mode, T: torque control mode            The diagonal lines indicate manufacturer settings. Never change the setting.            Note 2. When assigning LOP (Control switching), assign it to the same pin in all control modes.         </p>							Setting value	Input device (Note 1)			P	S	T	-- 0 2	SON	SON	SON	-- 0 3	RES	RES	RES	-- 0 4	PC	PC	/	-- 0 5	TL	TL	/	-- 0 6	CR	/	/	-- 0 7	/	ST1	RS2	-- 0 8	/	ST2	RS1	-- 0 9	TL1	TL1	/	-- 0 A	LSP	LSP	/	-- 0 B	LSN	LSN	/	-- 0 D	CDP	CDP	/	-- 2 0	/	SP1	SP1	-- 2 1	/	SP2	SP2	-- 2 2	/	SP3	SP3	-- 2 3	LOP (Note 2)	LOP (Note 2)	LOP (Note 2)	-- 2 4	CM1	/	/	-- 2 5	CM2	/	/	-- 2 6	/	STAB2	STAB2
Setting value	Input device (Note 1)																																																																																				
	P	S	T																																																																																		
-- 0 2	SON	SON	SON																																																																																		
-- 0 3	RES	RES	RES																																																																																		
-- 0 4	PC	PC	/																																																																																		
-- 0 5	TL	TL	/																																																																																		
-- 0 6	CR	/	/																																																																																		
-- 0 7	/	ST1	RS2																																																																																		
-- 0 8	/	ST2	RS1																																																																																		
-- 0 9	TL1	TL1	/																																																																																		
-- 0 A	LSP	LSP	/																																																																																		
-- 0 B	LSN	LSN	/																																																																																		
-- 0 D	CDP	CDP	/																																																																																		
-- 2 0	/	SP1	SP1																																																																																		
-- 2 1	/	SP2	SP2																																																																																		
-- 2 2	/	SP3	SP3																																																																																		
-- 2 3	LOP (Note 2)	LOP (Note 2)	LOP (Note 2)																																																																																		
-- 2 4	CM1	/	/																																																																																		
-- 2 5	CM2	/	/																																																																																		
-- 2 6	/	STAB2	STAB2																																																																																		
PD04 *DI1H Input device selection 1H	Any input device can be assigned to the CN1-15 pin.																																																																																				
	-- x x	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	02h	/	/	○																																																																															
	-- x -- x -- --	For manufacturer setting	2h 0h	/	/	/																																																																															
PD11 *DI5L Input device selection 5L	Any input device can be assigned to the CN1-19 pin.																																																																																				
	-- x x	Position control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	03h	○	/	/																																																																															
PD12 *DI5H Input device selection 5H	Any input device can be assigned to the CN1-19 pin.																																																																																				
	-- x x	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	07h	/	/	○																																																																															
	-- x -- x -- --	For manufacturer setting	8h 3h	/	/	/																																																																															
PD13 *DI6L Input device selection 6L	Any input device can be assigned to the CN1-41 pin.																																																																																				
	-- x x	Position control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	06h	○	/	/																																																																															
PD13 *DI6L Input device selection 6L	Any input device can be assigned to the CN1-41 pin.																																																																																				
	x x --	Speed control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	08h	/	○	/																																																																															

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode																																																								
				P	S	T																																																						
PD14 *DI6H Input device selection 6H	Any input device can be assigned to the CN1-41 pin.																																																											
	__ x x	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	08h			○																																																						
	__ x __ x __ __	For manufacturer setting	9h 3h																																																									
PD17 *DI8L Input device selection 8L	Any input device can be assigned to the CN1-43 pin.																																																											
	__ x x x x __	Position control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings. Speed control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	0Ah 0Ah	○																																																								
PD18 *DI8H Input device selection 8H	Any input device can be assigned to the CN1-43 pin.																																																											
	__ x x __ x __	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings. For manufacturer setting	00h 7h			○																																																						
	x __ __		0h																																																									
PD19 *DI9L Input device selection 9L	Any input device can be assigned to the CN1-44 pin.																																																											
	__ x x x x __	Position control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings. Speed control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	0Bh 0Bh	○																																																								
PD20 *DI9H Input device selection 9H	Any input device can be assigned to the CN1-44 pin.																																																											
	__ x x __ x __	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings. For manufacturer setting	00h 8h			○																																																						
	x __ __		0h																																																									
PD24 *DO2 Output device selection 2	Any output device can be assigned to the CN1-23 pin. Refer to table 5.10 for settings.		0Ch	○	○	○																																																						
	__ x __ x __ __	For manufacturer setting	0h 0h																																																									
	<p style="text-align: center;"><b>Table 5.10 Selectable output devices</b></p> <table border="1" style="margin-left: auto; margin-right: auto;"> <thead> <tr> <th rowspan="2">Setting value</th> <th colspan="3">Output device (Note)</th> </tr> <tr> <th>P</th> <th>S</th> <th>T</th> </tr> </thead> <tbody> <tr><td>__ 0 0</td><td>Always off</td><td>Always off</td><td>Always off</td></tr> <tr><td>__ 0 2</td><td>RD</td><td>RD</td><td>RD</td></tr> <tr><td>__ 0 3</td><td>ALM</td><td>ALM</td><td>ALM</td></tr> <tr><td>__ 0 4</td><td>INP</td><td>SA</td><td>Always off</td></tr> <tr><td>__ 0 5</td><td>MBR</td><td>MBR</td><td>MBR</td></tr> <tr><td>__ 0 7</td><td>TLC</td><td>TLC</td><td>VLC</td></tr> <tr><td>__ 0 8</td><td>WNG</td><td>WNG</td><td>WNG</td></tr> <tr><td>__ 0 A</td><td>Always off</td><td>SA</td><td>Always off</td></tr> <tr><td>__ 0 B</td><td>Always off</td><td>Always off</td><td>VLC</td></tr> <tr><td>__ 0 C</td><td>ZSP</td><td>ZSP</td><td>ZSP</td></tr> <tr><td>__ 0 D</td><td>MTTR</td><td>MTTR</td><td>MTTR</td></tr> <tr><td>__ 0 F</td><td>CDPS</td><td>Always off</td><td>Always off</td></tr> </tbody> </table> <p style="text-align: center;">Note. P: position control mode, S: speed control mode, T: torque control mode</p>						Setting value	Output device (Note)			P	S	T	__ 0 0	Always off	Always off	Always off	__ 0 2	RD	RD	RD	__ 0 3	ALM	ALM	ALM	__ 0 4	INP	SA	Always off	__ 0 5	MBR	MBR	MBR	__ 0 7	TLC	TLC	VLC	__ 0 8	WNG	WNG	WNG	__ 0 A	Always off	SA	Always off	__ 0 B	Always off	Always off	VLC	__ 0 C	ZSP	ZSP	ZSP	__ 0 D	MTTR	MTTR	MTTR	__ 0 F	CDPS	Always off
Setting value	Output device (Note)																																																											
	P	S	T																																																									
__ 0 0	Always off	Always off	Always off																																																									
__ 0 2	RD	RD	RD																																																									
__ 0 3	ALM	ALM	ALM																																																									
__ 0 4	INP	SA	Always off																																																									
__ 0 5	MBR	MBR	MBR																																																									
__ 0 7	TLC	TLC	VLC																																																									
__ 0 8	WNG	WNG	WNG																																																									
__ 0 A	Always off	SA	Always off																																																									
__ 0 B	Always off	Always off	VLC																																																									
__ 0 C	ZSP	ZSP	ZSP																																																									
__ 0 D	MTTR	MTTR	MTTR																																																									
__ 0 F	CDPS	Always off	Always off																																																									

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PD25 *DO3 Output device selection 3	__ x x	Device selection Any output device can be assigned to the CN1-24 pin. Refer to table 5.10 in [Pr. PD24] for settings.	04h	○	○	○
	_ x _ _	For manufacturer setting	0h			
	x _ _ _		0h			
PD28 *DO6 Output device selection 6	__ x x	Device selection Any output device can be assigned to the CN1-49 pin. Refer to table 5.10 in [Pr. PD24] for settings.	02h	○	○	○
	_ x _ _	For manufacturer setting	0h			
	x _ _ _		0h			
PD29 *DIF Input filter setting	Select a filter for the input signal.					
	___ x	Input signal filter selection If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0: None 1: 0.888 [ms] 2: 1.777 [ms] 3: 2.666 [ms] 4: 3.555 [ms]	4h	○	○	○
	__ x _	RES (Reset) dedicated filter selection 0: Disabled 1: Enabled (50 [ms])	0h	○	○	○
	_ x _ _	CR (Clear) dedicated filter selection 0: Disabled 1: Enabled (50 [ms])	0h	○	○	○
	x _ _ _	For manufacturer setting	0h			
PD30 *DOP1 Function selection D-1	___ x	Stop method selection for LSP (Forward rotation stroke end) off and LSN (Reverse rotation stroke end) off Select a stop method for LSP (Forward rotation stroke end) off and LSN (Reverse rotation stroke end) off 0: Quick stop 1: Slow stop	0h	○	○	
	__ x _	Base circuit status selection for RES (Reset) on 0: Base circuit shut-off 1: No base circuit shut-off	0h	○	○	○
	_ x _ _	For manufacturer setting	0h			
	x _ _ _		0h			
PD32 *DOP3 Function selection D-3	___ x	CR (Clear) selection Set CR (Clear). 0: Deleting droop pulses at the leading edge of turning on of CR 1: Continuous deleting of droop pulses while CR is on 2: Disabled (Note) Note. The setting value is available with servo amplifier with software version B7 or later.	0h	○		
	__ x _	For manufacturer setting	0h			
	_ x _ _		0h			
	x _ _ _		0h			

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode								
				P	S	T						
PD34 *DOP5 Function selection D-5	___x	Alarm code output Select if output alarm codes. When an alarm occurs, the alarm code is outputted to CN1-23, CN1-24, and CN1-49 pins. 0: Disabled 1: Enabled For details of the alarm codes, refer to chapter 8. When you select alarm code output while MBR or ALM is selected for CN1-23, CN1-24, or CN1-49 pin, [AL. 37 Parameter error] will occur.	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>						
	__x__	Selection of output device at warning occurrence Select ALM (Malfunction) output status at warning occurrence.  <table border="1" style="margin-left: auto; margin-right: auto;"> <thead> <tr> <th>Setting value</th> <th>Device status</th> </tr> </thead> <tbody> <tr> <td style="text-align: center;">0</td> <td> </td> </tr> <tr> <td style="text-align: center;">1</td> <td> </td> </tr> </tbody> </table>	Setting value	Device status	0		1		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	Setting value	Device status										
	0											
1												
__x__	For manufacturer setting	0h	/	/	/							
x__	For manufacturer setting	0h	/	/	/							
PD43 *DI11L Input device selection 11L	Any input device can be assigned to the CN1-10 pin and the CN1-37 pin. When "00" is set, PP/PP2 (Forward rotation pulse/Manual pulse generator) will be assigned. The CN1-37 pin is available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later. This parameter setting is available with servo amplifiers with software version B7 or later.											
	__xx	Position control mode - Device selection This setting is invalid.	00h	/	/	/						
	xx__	Speed control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	00h	/	○	/						
PD44 *DI11H Input device selection 11H	Any input device can be assigned to the CN1-10 pin and the CN1-37 pin. When "00" is set, PP/PP2 (Forward rotation pulse/Manual pulse generator) will be assigned. The CN1-37 pin is available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later. This parameter setting is available with servo amplifiers with software version B7 or later.											
	__xx	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	00h	/	/	○						
	xx__	For manufacturer setting	20h	/	/	/						
PD45 *DI12L Input device selection 12L	Any input device can be assigned to the CN1-35 pin and the CN1-38 pin. When "00" is set, NP/NP2 (Reverse rotation pulse/Manual pulse generator) will be assigned. The CN1-38 pin is available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later. This parameter setting is available with servo amplifiers with software version B7 or later.											
	__xx	Position control mode - Device selection This setting is invalid.	00h	/	/	/						
	xx__	Speed control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	00h	/	○	/						

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PD46 *DI12H Input device selection 12H		Any input device can be assigned to the CN1-35 pin and the CN1-38 pin. When "00" is set, NP/NP2 (Reverse rotation pulse/Manual pulse generator) will be assigned. The CN1-38 pin is available with servo amplifiers having software version B7 or later, and manufactured in May 2015 or later. This parameter setting is available with servo amplifiers with software version B7 or later.				
	-- x x	Torque control mode - Device selection Refer to table 5.9 in [Pr. PD03] for settings.	00h			○
	x x --	For manufacturer setting	2Bh			

### 5.2.5 Extension setting 2 parameters ([Pr. PE\_ \_])

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PE41 EOP3 Function selection E-3	--- x	Robust filter selection 0: Disabled 1: Enabled When you select "Enabled" of this digit, the machine resonance suppression filter 5 set in [Pr. PB51] is not available.	0h	○	○	○
	-- x --	For manufacturer setting	0h			
	- x ---		0h			
	x ----		0h			
PE44 LMCP Lost motion compensation positive-side compensation value selection		Set the lost motion compensation for when reverse rotation (CW) switches to forward rotation (CCW) in increments of 0.01% assuming the rated torque as 100%. This parameter is supported with software version C5 or later.  Setting range: 0 to 30000	0 [0.01%]	○		
PE45 LMCN Lost motion compensation negative-side compensation value selection		Set the lost motion compensation for when forward rotation (CCW) switches to reverse rotation (CW) in increments of 0.01% assuming the rated torque as 100%. This parameter is supported with software version C5 or later.  Setting range: 0 to 30000	0 [0.01%]	○		
PE46 LMFLT Lost motion filter setting		Set the time constant of the lost motion compensation filter in increments of 0.1 ms. If the time constant is set to "0", the torque is compensated with the value set in [Pr. PE44] and [Pr. PE45]. If the time constant is set to other than "0", the torque is compensated with the high-pass filter output value of the set time constant, and the lost motion compensation will continue. This parameter is supported with software version C5 or later.  Setting range: 0 to 30000	0 [0.1 ms]	○		
PE47 TOF Torque offset		Set this when canceling unbalanced torque of vertical axis. Set this assuming the rated torque of the servo motor as 100%. The torque offset does not need to be set for a machine not generating unbalanced torque. The torque offset set with this parameter will be enabled in the position control mode, speed control mode, and torque control mode. Input commands assuming torque offset for the torque control mode. This parameter is supported with software version C5 or later.  Setting range: -10000 to 10000	0 [0.01%]	○	○	○

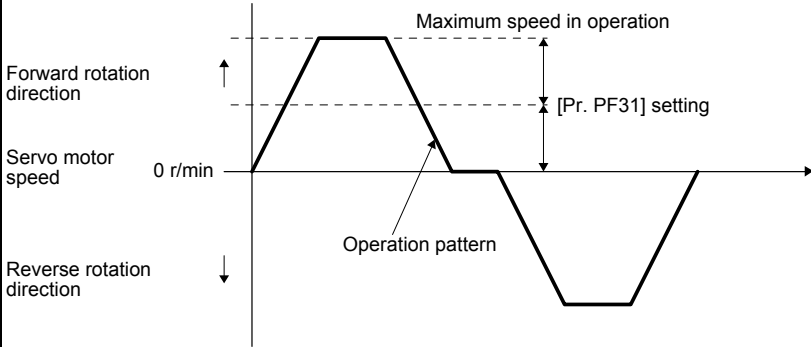
## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PE48 *LMOP Lost motion compensation function selection	___x	Lost motion compensation selection 0: disabled 1: enabled This parameter is supported with software version C5 or later.	0h	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
	__x_	Unit setting of lost motion compensation non-sensitive band 0: 1 pulse unit 1: 1 kpulse unit This parameter is supported with software version C5 or later.	0h	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
	_x__	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
PE49 LMCD Lost motion compensation timing		Set the lost motion compensation timing in increments of 0.1 ms. You can delay the timing to perform the lost motion compensation for the set time. This parameter is supported with software version C5 or later.  Setting range: 0 to 30000	0 [0.1 ms]	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>
PE50 LMCT Lost motion compensation non-sensitive band		Set the lost motion compensation non-sensitive band. When the fluctuation of droop pulses equals to or less than the setting value, the speed will be "0". The setting unit can be changed in [Pr. PE48]. Set this parameter per encoder. This parameter is supported with software version C5 or later.  Setting range: 0 to 65535	0 [pulse/ [kpulse]	<input type="radio"/>	<input type="checkbox"/>	<input type="checkbox"/>

### 5.2.6 Extension setting 3 parameters ([Pr. PF\_\_])

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode								
				P	S	T						
PF09 *FOP5 Function selection F-5	___x	Electronic dynamic brake selection 0: Disabled 3: Automatic (enabled only for specified servo motors) Refer to the following table for the specified servo motors.  <table border="1" style="margin: 10px auto;"> <thead> <tr> <th>Series</th> <th>Servo motor</th> </tr> </thead> <tbody> <tr> <td>HG-KN</td> <td>HG-KN053/HG-KN13/HG-KN23/HG-KN43</td> </tr> <tr> <td>HG-SN</td> <td>HG-SN52</td> </tr> </tbody> </table> This parameter setting is available with servo amplifiers with software version B5 or later.	Series	Servo motor	HG-KN	HG-KN053/HG-KN13/HG-KN23/HG-KN43	HG-SN	HG-SN52	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	Series	Servo motor										
	HG-KN	HG-KN053/HG-KN13/HG-KN23/HG-KN43										
	HG-SN	HG-SN52										
__x_	For manufacturer setting	0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>							
_x__		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>							
x___		0h	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>							
PF21 DRT Drive recorder switching time setting		Set a drive recorder switching time. When a USB communication is cut during using a graph function or a graph function is terminated, the function will be changed to the drive recorder function after the setting time of this parameter. When a value from "1" to "32767" is set, it will switch after the setting value. When "0" is set, it will switch after 600 s. When "-1" is set, the drive recorder function is disabled.  Setting range: -1 to 32767	0 [s]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>						
PF23 OSCL1 Vibration tough drive - Oscillation detection level		Set a filter readjustment sensitivity of [Pr. PB13 Machine resonance suppression filter 1] and [Pr. PB15 Machine resonance suppression filter 2] while the vibration tough drive is enabled. However, setting "0" will be 50%. Example: When you set "50" to the parameter, the filter will be readjusted at the time of 50% or more oscillation level.  Setting range: 0 to 100	50 [%]	<input type="radio"/>	<input type="radio"/>	<input type="checkbox"/>						

## 5. PARAMETERS

No./symbol/ name	Setting digit	Function	Initial value [unit]	Control mode		
				P	S	T
PF24 *OSCL2 Vibration tough drive function selection	___x	Oscillation detection alarm selection Select alarm or warning when an oscillation continues at a filter readjustment sensitivity level of [Pr. PF23]. The digit is continuously enabled regardless of the vibration tough drive in [Pr. PA20]. 0: [AL. 54 Oscillation detection] will occur at oscillation detection. 1: [AL. F3.1 Oscillation detection warning] will occur at oscillation detection. 2: Oscillation detection function disabled	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	__x_	For manufacturer setting	0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	_x__		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	x___		0h	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PF25 CVAT instantaneous power failure tough drive - detection time		Set the time of the [AL. 10.1 Voltage drop in the power] occurrence. To disable the parameter, select "Disabled (_ 0 _)" of "Instantaneous power failure tough drive selection" in [Pr. PA20]. When "Enabled (_ 1 _)" is selected of "Instantaneous power failure tough drive selection" in [Pr. PA20], the power should be off for the setting value of this parameter + 1.5 s or more before cycling the power to enable a parameter whose symbol is preceded by "***". Setting range: 30 to 2000	200 [ms]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PF31 FRIC Machine diagnosis function - Friction judgement speed		Set a servo motor speed to divide a friction estimation area into high and low for the friction estimation process of the machine diagnosis. However, setting "0" will be the value half of the rated speed. When your operation pattern is under rated speed, we recommend that you set half value to the maximum speed with this.  	0 [r/min]	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
		Setting range: 0 to permissible speed				



## 5. PARAMETERS

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### MEMO

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## 6. NORMAL GAIN ADJUSTMENT

### 6. NORMAL GAIN ADJUSTMENT

POINT
<ul style="list-style-type: none"> <li>● In the torque control mode, you do not need to make gain adjustment.</li> <li>● Before making gain adjustment, check that your machine is not being operated at maximum torque of the servo motor. If operated over maximum torque, the machine may vibrate and may operate unexpectedly. In addition, make gain adjustment with a safety margin considering characteristic differences of each machine. It is recommended that generated torque during operation is under 90% of the maximum torque of the servo motor.</li> </ul>

#### 6.1 Different adjustment methods

##### 6.1.1 Adjustment on a single servo amplifier

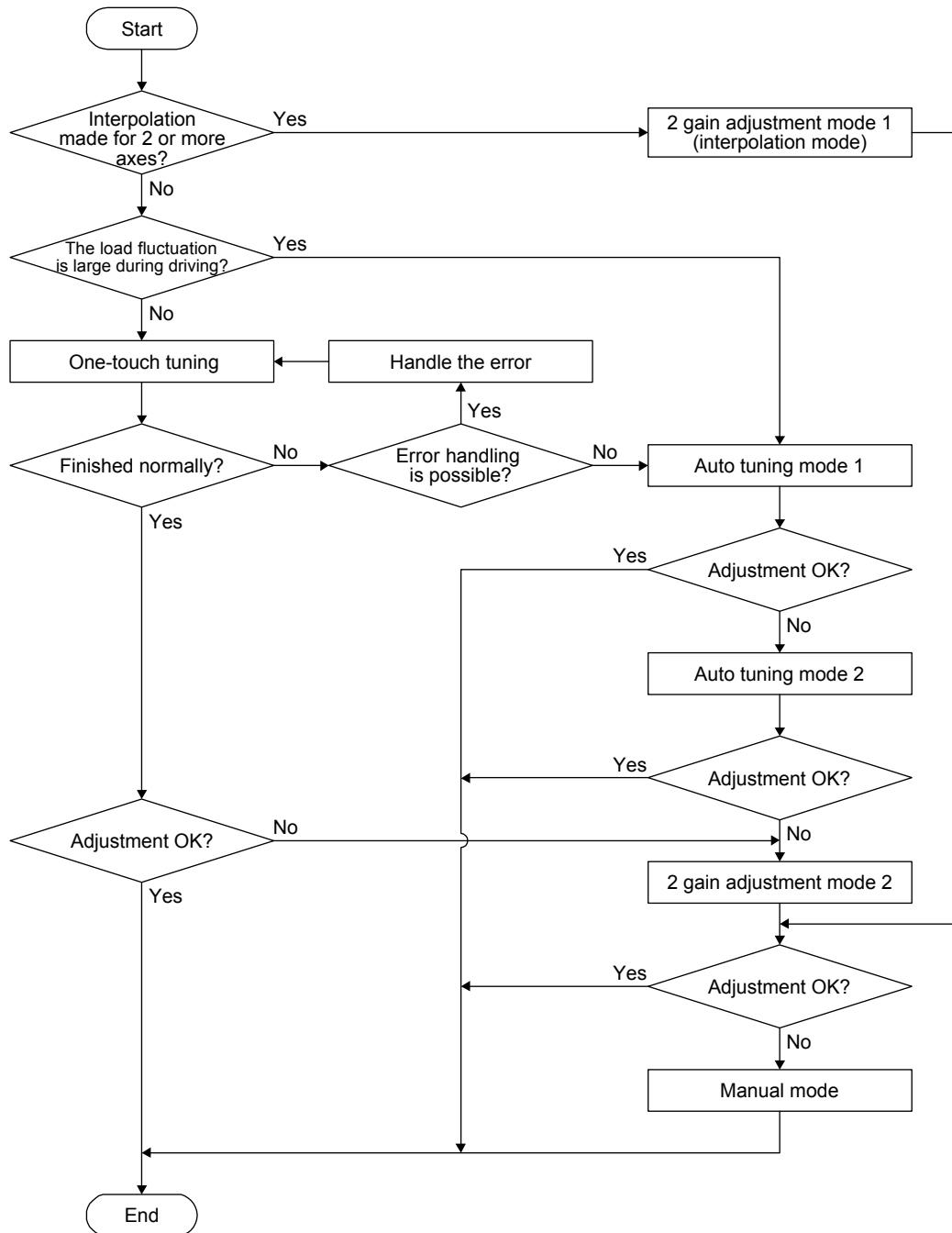
The following table shows the gain adjustment modes that can be set on a single servo amplifier. For gain adjustment, first execute "Auto tuning mode 1". If you are not satisfied with the result of the adjustment, execute "Auto tuning mode 2" and "Manual mode" in this order.

##### (1) Gain adjustment mode explanation

Gain adjustment mode	[Pr. PA08] setting	Estimation of load to motor inertia ratio	Automatically set parameters	Manually set parameters
Auto tuning mode 1 (initial value)	___ 1	Always estimated	GD2 ([Pr. PB06]) PG1 ([Pr. PB07]) PG2 ([Pr. PB08]) VG2 ([Pr. PB09]) VIC ([Pr. PB10])	RSP ([Pr. PA09])
Auto tuning mode 2	___ 2	Fixed to [Pr. PB06] value	PG1 ([Pr. PB07]) PG2 ([Pr. PB08]) VG2 ([Pr. PB09]) VIC ([Pr. PB10])	GD2 ([Pr. PB06]) RSP ([Pr. PA09])
Manual mode	___ 3		/	GD2 ([Pr. PB06]) PG1 ([Pr. PB07]) PG2 ([Pr. PB08]) VG2 ([Pr. PB09]) VIC ([Pr. PB10])
2 gain adjustment mode 1 (interpolation mode)	___ 0	Always estimated	GD2 ([Pr. PB06]) PG2 ([Pr. PB08]) VG2 ([Pr. PB09]) VIC ([Pr. PB10])	PG1 ([Pr. PB07]) RSP ([Pr. PA09])
2 gain adjustment mode 2	___ 4	Fixed to [Pr. PB06] value	PG2 ([Pr. PB08]) VG2 ([Pr. PB09]) VIC ([Pr. PB10])	GD2 ([Pr. PB06]) PG1 ([Pr. PB07]) RSP ([Pr. PA09])

## 6. NORMAL GAIN ADJUSTMENT

### (2) Adjustment sequence and mode usage



#### 6.1.2 Adjustment using MR Configurator2

This section explains the functions and adjustment using the servo amplifier with MR Configurator2.

Function	Description	Adjustment
Machine analyzer	With the machine and servo motor coupled, the characteristic of the mechanical system can be measured by giving a random vibration command from a personal computer to the servo and measuring the machine response.	You can grasp the machine resonance frequency and determine the notch frequency of the machine resonance suppression filter.

## 6. NORMAL GAIN ADJUSTMENT

### 6.2 One-touch tuning

POINT
<ul style="list-style-type: none"> <li>● When executing the one-touch tuning, check the [Pr. PA21 One-touch tuning function selection] is "___1" (initial value).</li> <li>● At start of the one-touch tuning, only when "Auto tuning mode 1 (___1)" or "2 gain adjustment mode 1 (interpolation mode) (___0)" of "Gain adjustment mode selection" is selected in [Pr. PA08], [Pr. PB06 Load to motor inertia ratio] will be estimated.</li> <li>● The amplifier command method can be used with the servo amplifier with software version C1 or later and MR Configurator2 with software version 1.45X or later.</li> <li>● When the one-touch tuning is executed in the amplifier command method, MR Configurator2 is required.</li> </ul>

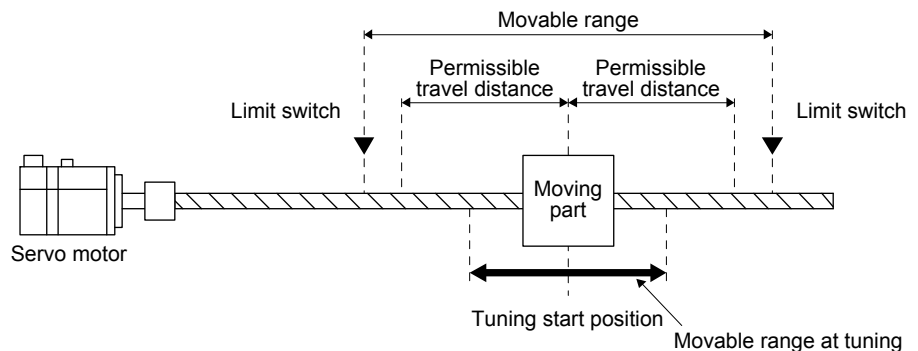
The one-touch tuning includes two methods: the user command method and the amplifier command method.

#### (1) User command method

You can execute the one-touch tuning with MR Configurator2 or push buttons. The user command method performs one-touch tuning by inputting commands from outside the servo amplifier.

#### (2) Amplifier command method

You can execute the one-touch tuning with MR Configurator2. In the amplifier command method, when you simply input a travel distance (permissible travel distance) that collision against the equipment does not occur during servo motor driving, a command for the optimum tuning will be generated inside the servo amplifier to perform one-touch tuning.



## 6. NORMAL GAIN ADJUSTMENT

The following parameters are set automatically with one-touch tuning. Also, "Gain adjustment mode selection" in [Pr. PA08] will be "2 gain adjustment mode 2 (\_ \_ \_ 4)" automatically. Other parameters will be set to an optimum value depending on the setting of [Pr. PA09 Auto tuning response].

Table 6.1 List of parameters automatically set with one-touch tuning

Parameter	Symbol	Name
PA08	ATU	Auto tuning mode
PA09	RSP	Auto tuning response
PB01	FILT	Adaptive tuning mode (adaptive filter II)
PB02	VRFT	Vibration suppression control tuning mode (advanced vibration suppression control II)
PB03	PST	Position command acceleration/ deceleration time constant (position smoothing)
PB06	GD2	Load to motor inertia ratio
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation
PB12	OVA	Overshoot amount compensation
PB13	NH1	Machine resonance suppression filter 1
PB14	NHQ1	Notch shape selection 1
PB15	NH2	Machine resonance suppression filter 2
PB16	NHQ2	Notch shape selection 2
PB17	NHF	Shaft resonance suppression filter
PB18	LPF	Low-pass filter setting
PB19	VRF11	Vibration suppression control 1 - Vibration frequency
PB20	VRF12	Vibration suppression control 1 - Resonance frequency
PB21	VRF13	Vibration suppression control 1 - Vibration frequency damping
PB22	VRF14	Vibration suppression control 1 - Resonance frequency damping
PB23	VFBF	Low-pass filter selection
PB46	NH3	Machine resonance suppression filter 3
PB47	NHQ3	Notch shape selection 3
PB48	NH4	Machine resonance suppression filter 4
PB49	NHQ4	Notch shape selection 4
PB51	NHQ5	Notch shape selection 5
PE41	EOP3	Function selection E-3

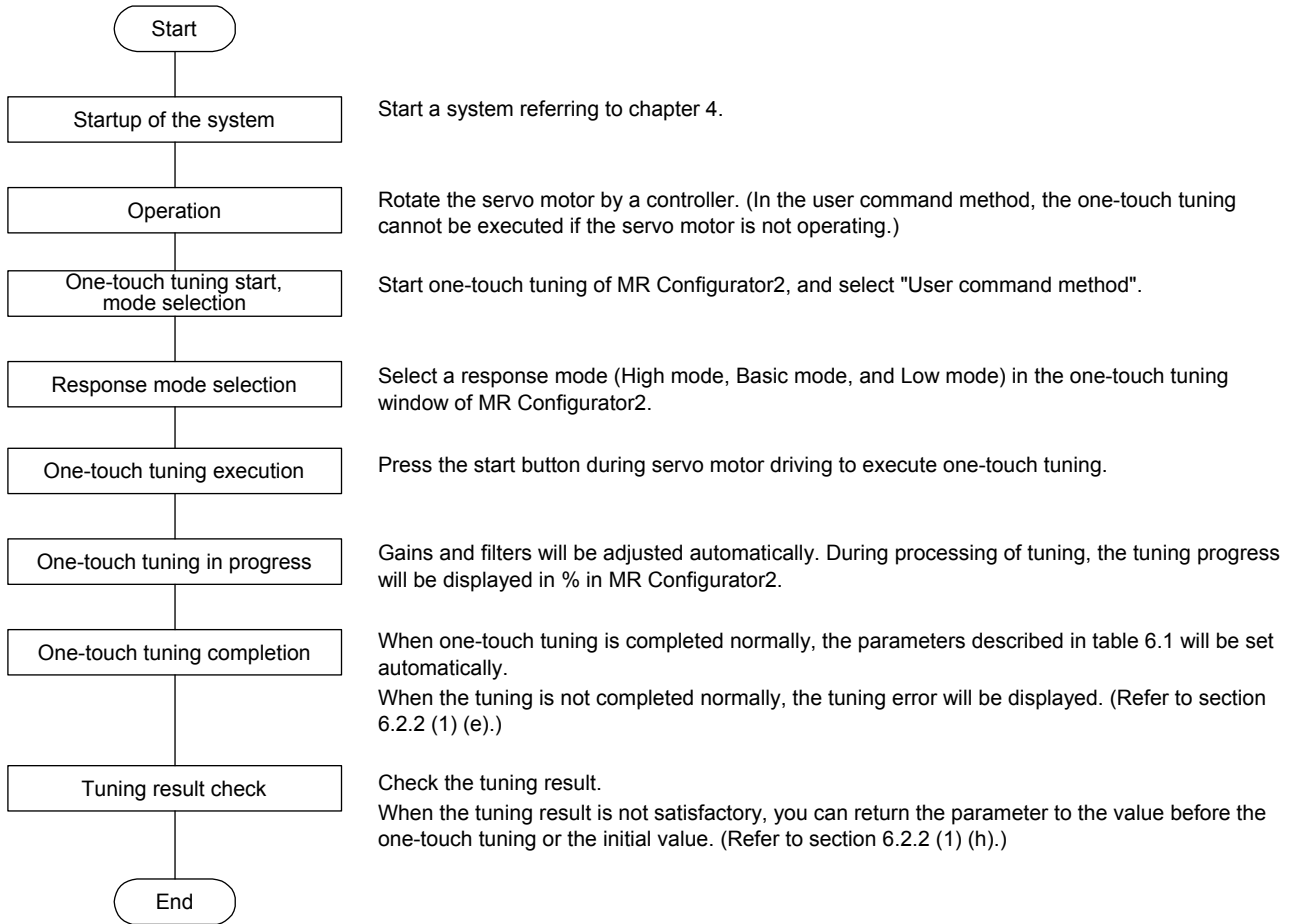
# 6. NORMAL GAIN ADJUSTMENT

## 6.2.1 One-touch tuning flowchart

### (1) User command method

#### (a) When you use MR Configurator2

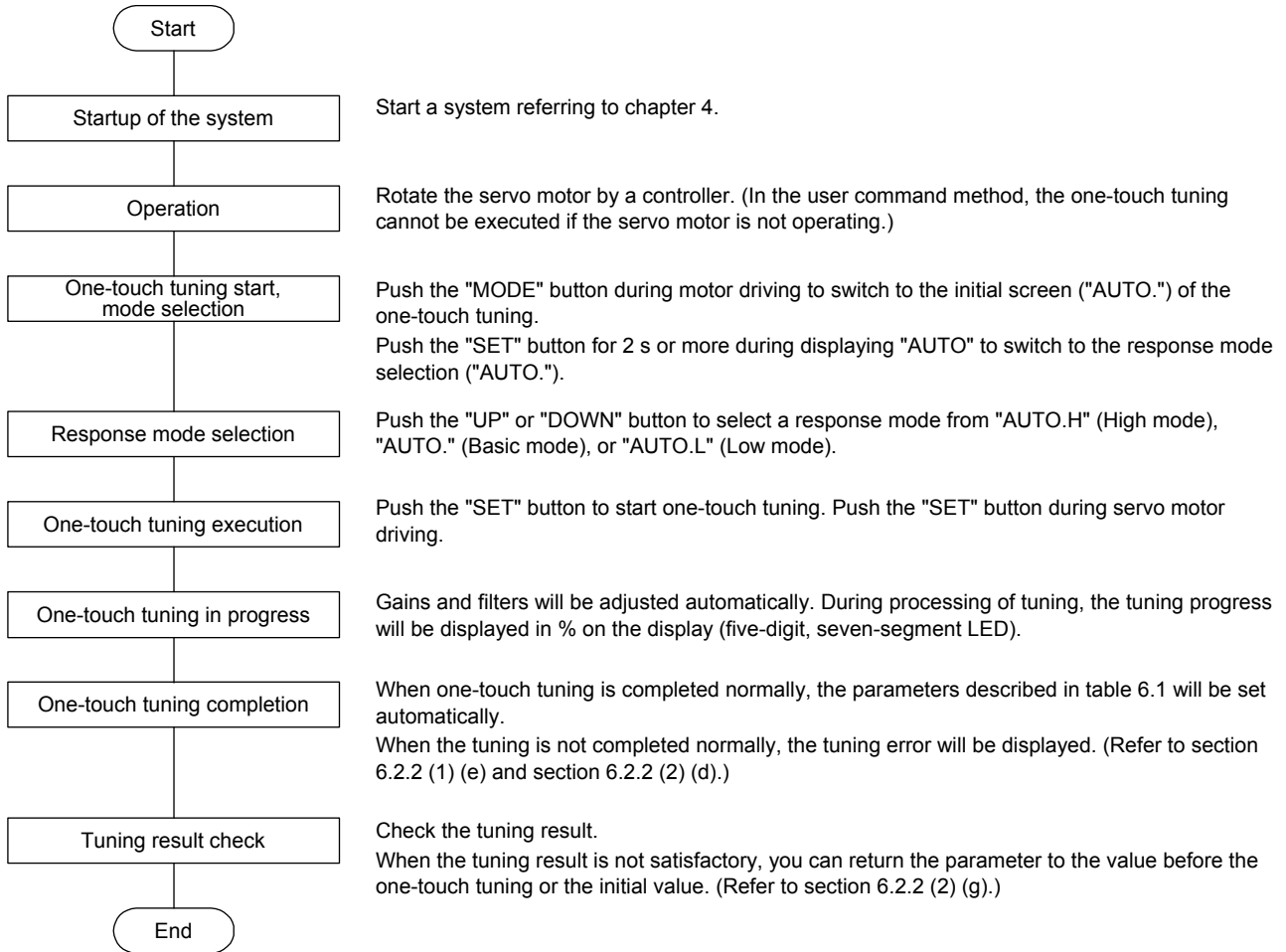
Make one-touch tuning as follows.



## 6. NORMAL GAIN ADJUSTMENT

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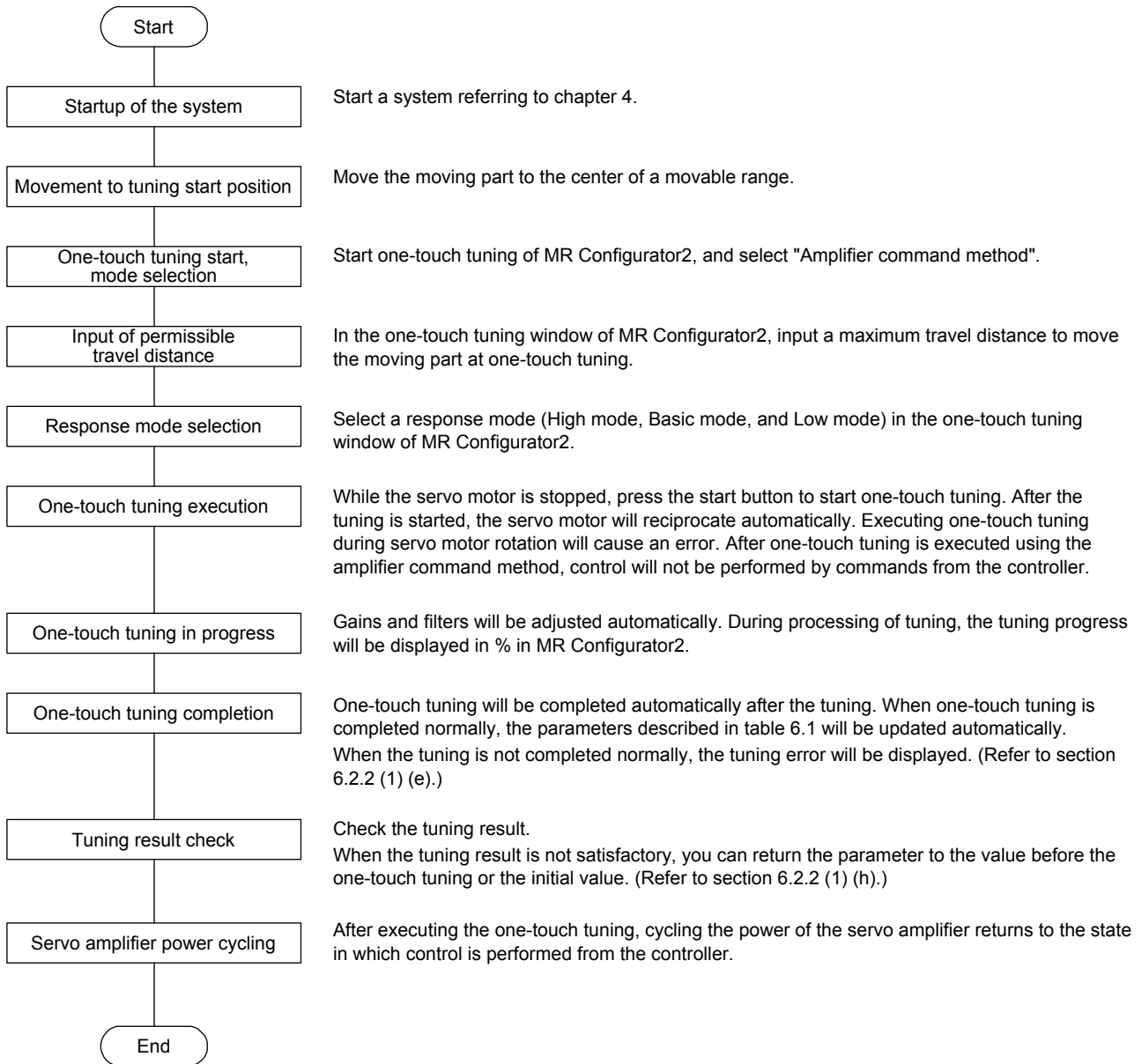
- (b) When you use push buttons  
Make one-touch tuning as follows.



## 6. NORMAL GAIN ADJUSTMENT

### (2) Amplifier command method

Make one-touch tuning as follows.





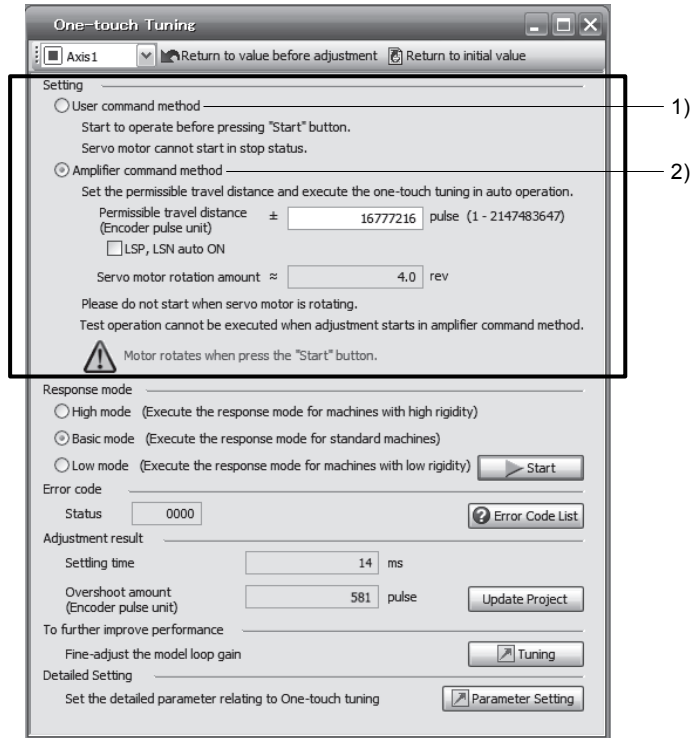
## 6. NORMAL GAIN ADJUSTMENT

### 6.2.2 Display transition and operation procedure of one-touch tuning

(1) When you use MR Configurator2

(a) Command method selection

Select a command method from two methods in the one-touch tuning window of MR Configurator2.



## 6. NORMAL GAIN ADJUSTMENT

### 1) User command method

It is recommended to input commands meeting the following conditions to the servo amplifier. If one-touch tuning is executed while commands which do not meet the conditions are inputted to the servo amplifier, the one-touch tuning error may occur.

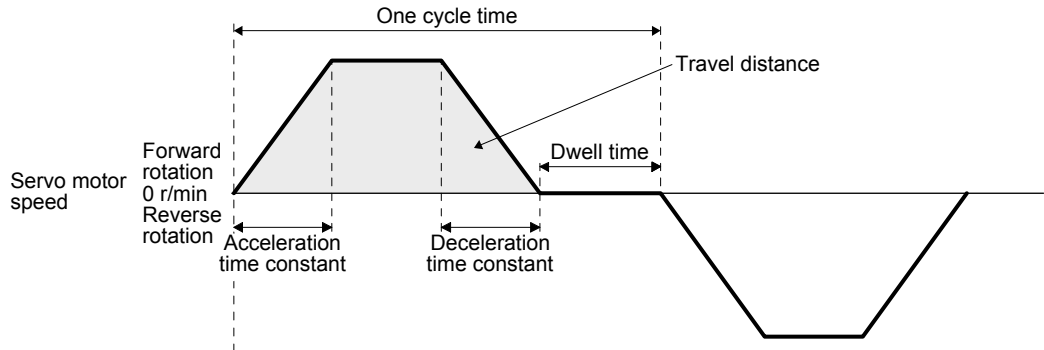


Fig. 6.1 Recommended command for one-touch tuning in the user command method

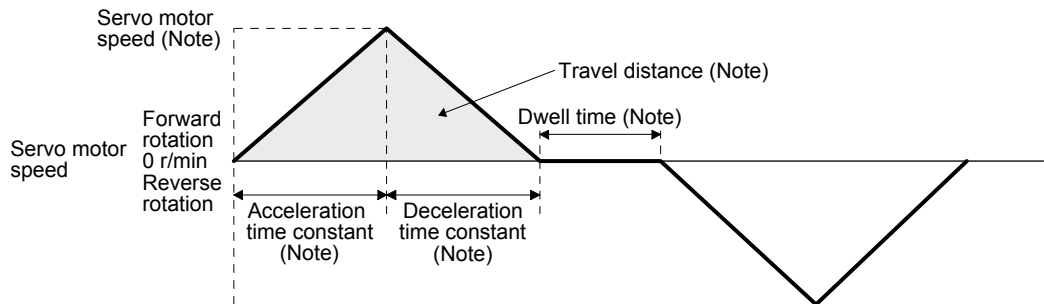
Item	Description
Travel distance	Set 100 pulses or more in encoder unit. Setting less than 100 pulses will cause the one-touch tuning error "C004".
Servo motor speed	Set 150 r/min or higher. Setting less than 150 r/min may cause the one-touch tuning error "C005".
Acceleration time constant Deceleration time constant	Set the time to reach 2000 r/min to 5 s or less. Set an acceleration time constant/deceleration time constant so that the acceleration/deceleration torque is 10% or more of the rated torque. The estimation accuracy of the load to motor inertia ratio is more improved as the acceleration/deceleration torque is larger, and the one-touch tuning result will be closer to the optimum value.
Dwell time	Set 200 ms or more. Setting a smaller value may cause the one-touch tuning error "C004".
One cycle time	Set 30 s or less. Setting over 30 s will cause the one-touch tuning error "C004".

## 6. NORMAL GAIN ADJUSTMENT

### 2) Amplifier command method

Input a permissible travel distance. Input it in the servo motor-side resolution unit. In the amplifier command method, the servo motor will be operated in a range between "current value  $\pm$  permissible travel distance". Input the permissible travel distance as large as possible within a range that the movable part does not collide against the machine. Inputting a small permissible travel distance decreases the possibility that the moving part will collide against the machine. However, the estimation accuracy of the load to motor inertia ratio may be lower, resulting in improper tuning.

Also, executing the one-touch tuning in the amplifier command method will generate a command for the following optimum tuning inside the servo amplifier to start the tuning.



Note. It will be automatically generated in the servo amplifier.

Fig. 6.2 Command generated by one-touch tuning in the amplifier command method

Item	Description
Travel distance	An optimum travel distance will be automatically set in the range not exceeding the user-inputted permissible travel distance with MR Configurator2.
Servo motor speed	A speed not exceeding 1/2 of the rated speed will be automatically set.
Acceleration time constant Deceleration time constant	An acceleration time constant/deceleration time constant will be automatically set so as not to exceed 60% of the rated torque and the torque limit value set at the start of one-touch tuning in the amplifier command method.
Dwell time	A dwell time in which the one-touch tuning error "C004" does not occur will be automatically set.

## 6. NORMAL GAIN ADJUSTMENT

### (b) Response mode selection

Select a response mode from 3 modes in the one-touch tuning window of MR Configurator2.

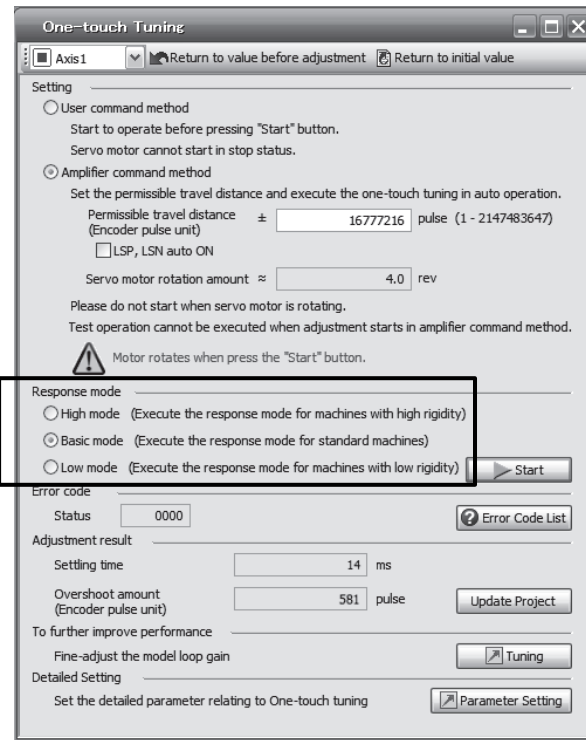


Table 6.2 Response mode explanations

Response mode	Explanation
High mode	This mode is for high-rigid system.
Basic mode	This mode is for standard system.
Low mode	This mode is for low-rigid system.

Refer to the following table for selecting a response mode.

Table 6.3 Guideline for response mode

Response mode			Response	Machine characteristic Guideline of corresponding machine
Low mode	Basic mode	High mode		
↑ ↓	↑ ↓	↑ ↓	Low response ↑ ↓ High response	

## 6. NORMAL GAIN ADJUSTMENT

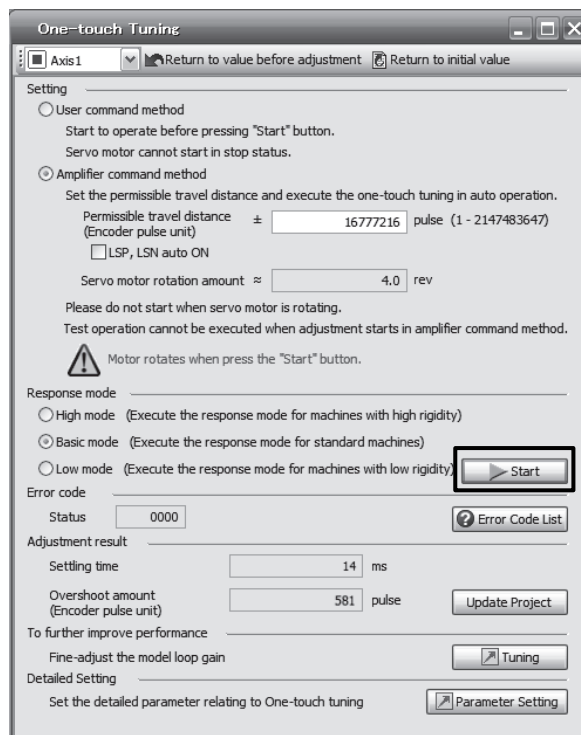
### (c) One-touch tuning execution

POINT
<ul style="list-style-type: none"><li>● For equipment in which overshoot during one-touch tuning is in the permissible level of the in-position range, changing the value of [Pr. PA25 One-touch tuning overshoot permissible level] will shorten the settling time and improve the response.</li><li>● When executing one-touch tuning in the amplifier command method, turn on EM2, LSP, and LSN. When EM2, LSP, and LSN are turned off during one-touch tuning, "C008" will be displayed at status in error code, and the one-touch tuning will be canceled. When setting LSP and LSN to automatic on, enable the check box "LSP, LSN auto ON" in the one-touch tuning window of MR Configurator2.</li></ul>

After the response mode is selected in (1) (b) in this section, clicking the start button will start one-touch tuning. If the start button is clicked while the servo motor stops, "C002" or "C004" will be displayed at status in error code. (Refer to (1) (e) in this section for error codes.)

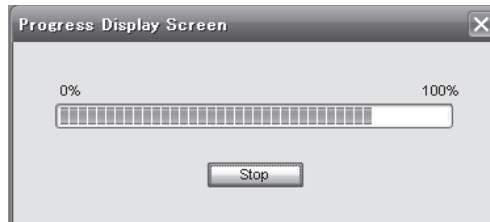
Click the start button to start the one-touch tuning in the amplifier command method with the servo-off, the servo-on will be automatically enabled, and the one-touch tuning will start. In the one-touch tuning by the amplifier command method, an optimum tuning command will be generated in the servo amplifier after servo-on. Then, the servo motor will reciprocate, and the one-touch tuning will be executed. After the tuning is completed or canceled, the servo amplifier will be the servo-off status. When the servo-on command is inputted from outside, the amplifier will be the servo-on status.

After one-touch tuning is executed using the amplifier command method, control will not be performed by commands from the controller. To return to the state in which control is performed from the controller, cycle the power.

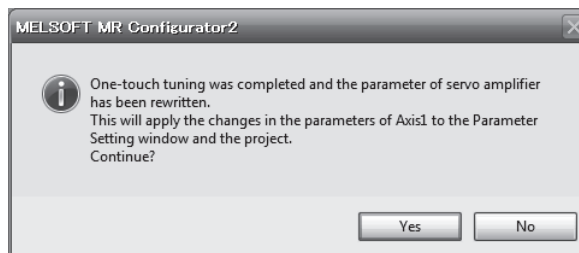


## 6. NORMAL GAIN ADJUSTMENT

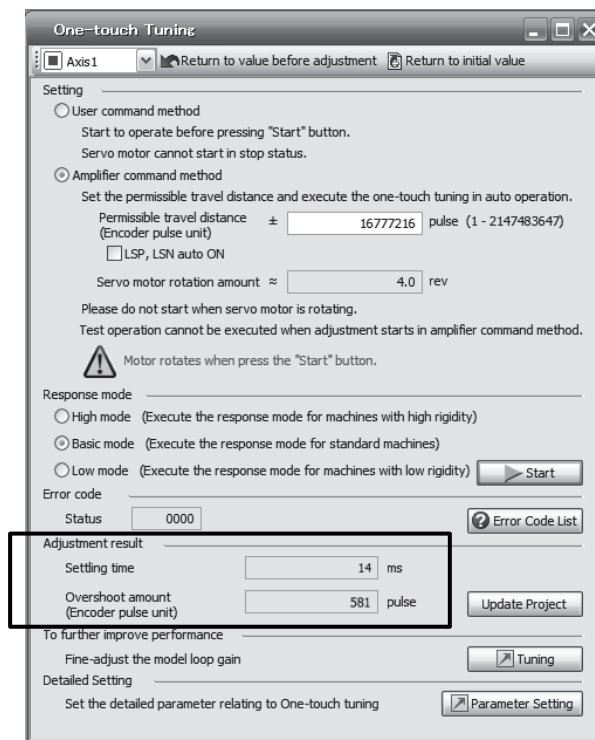
During processing of one-touch tuning, the progress will be displayed as follows. Tuning will be completed at 100%.



Completing the one-touch tuning will start writing tuning parameters to the servo amplifier, and the following window will be displayed. Select whether or not to reflect the tuning result in the project.



After the one-touch tuning is completed, "0000" will be displayed at status in error code. In addition, settling time and overshoot amount will be displayed in "Adjustment result".



## 6. NORMAL GAIN ADJUSTMENT

### (d) Stop of one-touch tuning

During one-touch tuning, clicking the stop button stops one-touch tuning. At this time, "C000" is displayed at status in error code. After the one-touch tuning is stopped, parameters will return to the values at the start of the one-touch tuning. When executing one-touch tuning again, stop the servo motor once. In addition, after returning the moving part to the tuning start position, execute it.

### (e) If an error occurs

If a tuning error occurs during tuning, one-touch tuning will be stopped. With that, the following error code will be displayed in status. Check the cause of tuning error. When executing one-touch tuning again, stop the servo motor once. In addition, after returning the moving part to the tuning start position, execute it.

Display	Name	Error detail	Corrective action example
C000	Tuning canceled	The stop button was clicked during one-touch tuning.	
C001	Overshoot exceeded	Overshoot amount is a value larger than the one set in [Pr. PA10 In-position range] and [Pr. PA25 One-touch tuning - Overshoot permissible level].	Increase the in-position range or overshoot permissible level.
C002	Servo-off during tuning	The one-touch tuning was attempted in the user command method during servo-off. The servo amplifier will be servo-off status during one-touch tuning.	When executing one-touch tuning in the user command method, turn to servo-on, and then execute it. Prevent the servo amplifier from being the servo-off status during one-touch tuning.
C003	Control mode error	1. The one-touch tuning was attempted while the torque control mode was selected in the control modes.	Select the position control mode or speed control mode for the control mode, and then execute one-touch tuning. Do not change the control mode during the one-touch tuning.
		2. During one-touch tuning, the control mode was attempted to change from the position control mode to the speed control mode.	
C004	Time-out	1. One cycle time during the operation has been over 30 s.	Set one cycle time during the operation (time from the command start to the next command start) to 30 s or less.
		2. The command speed is slow.	Set the servo motor speed to 100 r/min or higher. Error is less likely to occur as the setting speed is higher. When one-touch tuning by the amplifier command is used, set a permissible travel distance so that the servo motor speed is 100 r/min or higher. Set a permissible travel distance to two or more revolutions as a guide value to set the servo motor speed to 100 r/min.
		3. The operation interval of the continuous operation is short.	Set the stop interval during operation to 200 ms or more. Error is less likely to occur as the setting time is longer.

## 6. NORMAL GAIN ADJUSTMENT

Display	Name	Error detail	Corrective action example
C005	Load to motor inertia ratio misestimated	1. The estimation of the load to motor inertia ratio at one-touch tuning was a failure.	Drive the motor with meeting conditions as follows. <ul style="list-style-type: none"> <li>• The acceleration time constant/deceleration time constant to reach 2000 r/min is 5 s or less.</li> <li>• Speed is 150 r/min or higher.</li> <li>• The load to motor inertia ratio is 100 times or less.</li> <li>• The acceleration/deceleration torque is 10% or more of the rated torque.</li> </ul>
		2. The load to motor inertia ratio was not estimated due to an oscillation or other influences.	Set to the auto tuning mode that does not estimate the load to motor inertia ratio as follows, and then execute the one-touch tuning. <ul style="list-style-type: none"> <li>• Select "Auto tuning mode 2 ( _ _ _ 2)", "Manual mode ( _ _ _ 3)", or "2 gain adjustment mode 2 ( _ _ _ 4)" of "Gain adjustment mode selection" in [Pr. PA08].</li> <li>• Manually set [Pr. PB06 Load to motor inertia ratio] properly.</li> </ul>
C006	Amplifier command start error	One-touch tuning was attempted to start in the amplifier command method under the following speed condition. Servo motor speed: 20 r/min or higher	Execute the one-touch tuning in the amplifier command method while the servo motor is stopped.
C007	Amplifier command generation error	1. One-touch tuning was executed in the amplifier command method when the permissible travel distance is set to 100 pulses or less in the encoder pulse unit, or the distance is set not to increase the servo motor speed to 150 r/min or higher at the time of load to motor inertia ratio estimation.	Set a permissible travel distance to 100 pulses or more in the encoder pulse unit, or a distance so as to increase the servo motor speed to 150 r/min or higher at the time of load to motor inertia ratio estimation, and then execute the one-touch tuning. Set a permissible travel distance to four or more revolutions as a guide value. Load to motor inertia ratio will be estimated when "0000" or "0001" is set in [Pr. PA08 Auto tuning mode] at the start of one-touch tuning. If the permissible travel distance is short and the servo motor speed cannot be increased to 150 r/min or higher, select "Auto tuning mode 2 ( _ _ _ 2)", "Manual mode ( _ _ _ 3)", or "2 gain adjustment mode 2 ( _ _ _ 4)" of "Gain adjustment mode selection" in [Pr. PA08].
		2. The torque limit has been set to 0.	Set the torque limit value to greater than 0.
C008	Stop signal	EM2, LSP, and LSN were turned off during one-touch tuning in the amplifier command method.	Review the one-touch tuning start position and permissible travel distance for the amplifier command method. After ensuring safety, turn on EM2, LSP, and LSN.
C009	Parameter	Parameters for manufacturer setting have been changed.	Return the parameters for manufacturer setting to the initial values.
C00A	Alarm	One-touch tuning was attempted to start in the amplifier command method during alarm or warning. Alarm or warning occurred during one-touch tuning by the amplifier command method.	Start one-touch tuning when no alarm or warning occurs. Prevent alarm or warning from occurring during one-touch tuning.
C00F	One-touch tuning disabled	"One-touch tuning function selection" in [Pr. PA21] is "Disabled ( _ _ _ 0)".	Select "Enabled ( _ _ _ 1)".



## 6. NORMAL GAIN ADJUSTMENT

(f) If an alarm occurs

If an alarm occurs during tuning, one-touch tuning will be forcibly terminated. Remove the cause of the alarm and execute one-touch tuning again. When executing one-touch tuning in the amplifier command method again, return the moving part to the tuning start position.

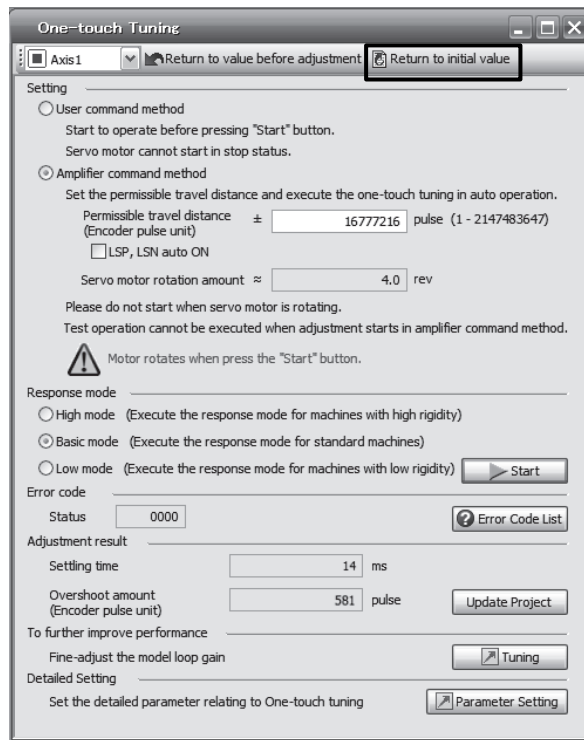
(g) If a warning occurs

If a warning which continues the motor driving occurs during one-touch tuning by the user command method, the tuning will be continued. If a warning which does not continue the motor driving occurs during the tuning, one-touch tuning will be stopped.

One-touch tuning will be stopped when warning occurs during one-touch tuning by the amplifier command method regardless of the warning type. Remove the cause of the warning, and return the moving part to the tuning start position. Then, execute the tuning again.

(h) Initializing one-touch tuning

Clicking "Return to initial value" in the one-touch tuning window of MR Configurator2 enables to return the parameter to the initial value. Refer to table 6.1 for the parameters which you can initialize. Clicking "Return to value before adjustment" in the one-touch tuning window of MR Configurator2 enables to return the parameter to the value before clicking the start button.



When the initialization of one-touch tuning is completed, the following window will be displayed. (returning to initial value)



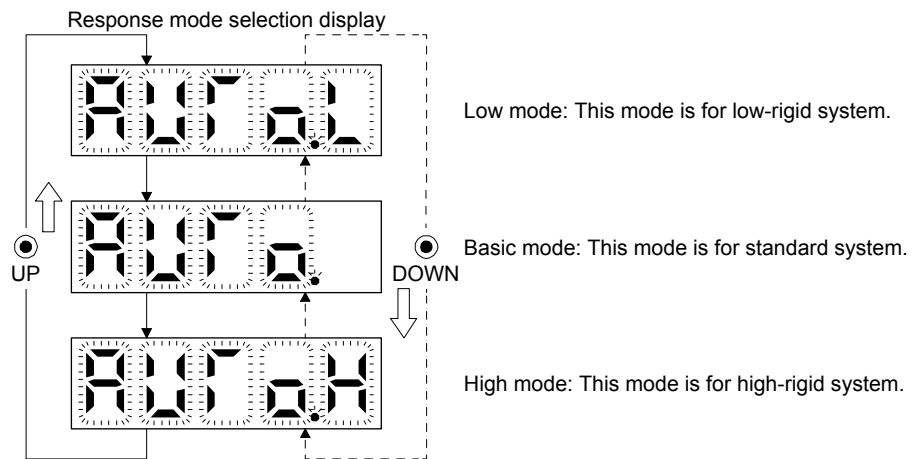
## 6. NORMAL GAIN ADJUSTMENT

(2) When you use push buttons

POINT
● Push the "MODE" and "SET" buttons at the same time for 3 s or more to switch to the response mode selection ("AUTO.") without going through the initial screen of the one-touch tuning ("AUTO").
● When you use push buttons, one-touch tuning can be executed in the user command method only. Tuning cannot be executed in the amplifier command method with the buttons.

(a) Response mode selection

Select a response mode of the one-touch tuning from 3 modes with "UP" or "DOWN". Refer to (1) (b) of this section for a guideline of response mode.

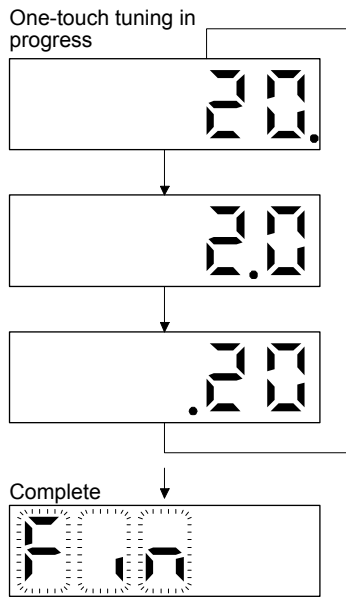


## 6. NORMAL GAIN ADJUSTMENT

### (b) One-touch tuning execution

POINT	<ul style="list-style-type: none"> <li>● For equipment in which overshoot during one-touch tuning is in the permissible level of the in-position range, changing the value of [Pr. PA25 One-touch tuning - Overshoot permissible level] will shorten the settling time and improve the response.</li> </ul>
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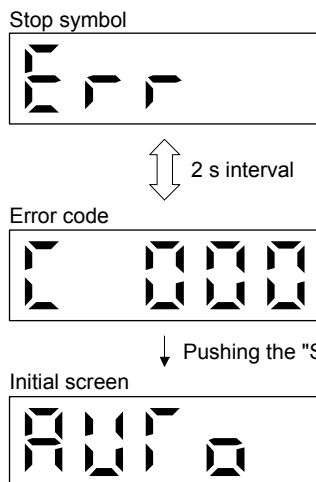
After the response mode is selected in (a), pushing the "SET" button will start one-touch tuning.



The one-touch tuning progress is displayed with 0% to 100%. The decimal point moves right to left in rotation during the tuning. To switch the display to the status display during the tuning, push the "MODE" button.

Completing the one-touch tuning will start writing the auto-tuned parameters to the servo amplifier.

### (c) Stop of one-touch tuning



The one-touch tuning mode can be stopped by pushing the "SET" button regardless of displayed item.

The stop symbol and error code "C 000" (cancel during tuning) will be displayed by turns with 2 s interval.

↓ Pushing the "SET" button will switch to the initial screen.

## 6. NORMAL GAIN ADJUSTMENT

(d) If an error occurs

Stop symbol



↕ 2 s interval

Error code



↕



If an error occurs during the one-touch tuning, the tuning will be forcibly terminated and the stop symbol and error code from "C 001" to "C 00F" will be displayed by turns with 2 s interval.

Check the error cause referring to table 6.2 of (1) (e) of this section.

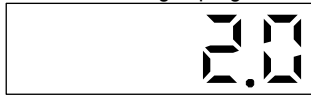
↓ Pushing the "SET" button will switch to the initial screen.

Initial screen



(e) If an alarm occurs

One-touch tuning in progress



↓

Alarm display



If an alarm occurs during tuning, one-touch tuning will be forcibly terminated and the alarm No. will be displayed.

(f) If a warning occurs

One-touch tuning in progress



↓

Alarm display (warning)



If a warning occurs during tuning, the alarm No. of the warning will be displayed. When the warning is one which continue the motor driving, the one-touch tuning will be continued.

## 6. NORMAL GAIN ADJUSTMENT

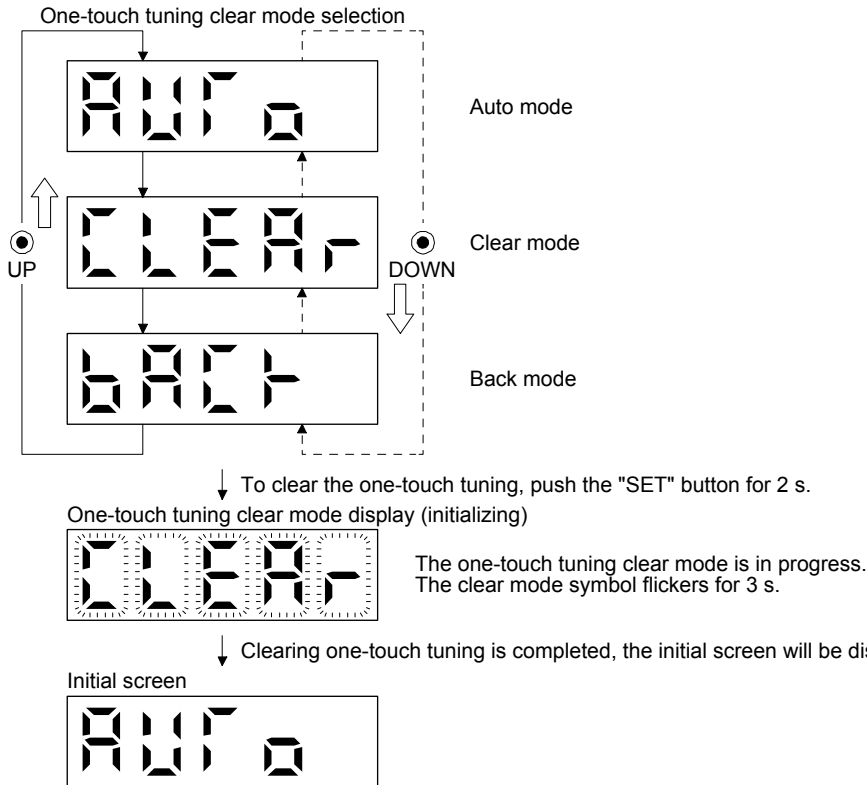
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### (g) Clearing one-touch tuning

Refer to table 6.1 for the parameters which you can clear.

You can initialize the parameters changed by the one-touch tuning with the clear mode. You can reset the parameters to before tuning with the back mode.

- 1) Switch to the initial screen "AUTO" of the one-touch tuning with the "MODE" button.
- 2) Select the clear mode or back mode with the "UP" or "DOWN" button.



## 6. NORMAL GAIN ADJUSTMENT

### 6.2.3 Caution for one-touch tuning

(1) Caution common for user command method and amplifier command method

- (a) The tuning is not available in the torque control mode.
- (b) The one-touch tuning cannot be executed while an alarm or warning which does not continue the motor driving is occurring.
- (c) You can execute the one-touch tuning during the following test operation modes marked by "○".

How to one-touch tuning	Test operation mode				
	Output signal (DO) forced output	JOG operation	Positioning operation	Motor-less operation	Program operation
MR Configurator2		○	○		○
Push buttons					

- (d) If one-touch tuning is performed when the gain switching function is enabled, vibration and/or unusual noise may occur during the tuning.

(2) Caution for amplifier command method

- (a) Starting one-touch tuning while the servo motor is rotating displays "C006" at status in error code, and the one-touch tuning cannot be executed.
- (b) One-touch tuning is not available during the test operation mode. The following test operation modes cannot be executed during one-touch tuning.
  - 1) Positioning operation
  - 2) JOG operation
  - 3) Program operation
  - 4) Machine analyzer operation
  - 5) Single-step feed
- (c) During one-touch tuning, the permissible travel distance may be exceeded due to overshoot, set a value sufficient to prevent machine collision.
- (d) When Auto tuning mode 2, Manual mode, or 2 gain adjustment mode 2 is selected in [Pr. PA08 Auto tuning mode], the load to motor inertia ratio will not be estimated. An optimum acceleration/deceleration command will be generated by [Pr. PB06 Load to motor inertia ratio] at the start of one-touch tuning. When the load to motor inertia ratio is incorrect, the optimum acceleration/deceleration command may not be generated, causing the tuning to fail.
- (e) When one-touch tuning is started by using communication, if the communication is interrupted during the tuning, the servo motor will stop, and the tuning will also stop. The parameter will return to the one at the start of the one-touch tuning.
- (f) When one-touch tuning is started during the speed control mode, the mode will be switched to the position control mode automatically. The tuning result may differ from the one obtained by executing tuning by using the speed command.

## 6. NORMAL GAIN ADJUSTMENT

### 6.3 Auto tuning

#### 6.3.1 Auto tuning mode

The servo amplifier has a real-time auto tuning function which estimates the machine characteristic (load to motor inertia ratio) in real time and automatically sets the optimum gains according to that value. This function permits ease of gain adjustment of the servo amplifier.

##### (1) Auto tuning mode 1

The servo amplifier is factory-set to the auto tuning mode 1.

In this mode, the load to motor inertia ratio of a machine is always estimated to set the optimum gains automatically.

The following parameters are automatically adjusted in the auto tuning mode 1.

Parameter	Symbol	Name
PB06	GD2	Load to motor inertia ratio
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

POINT
<ul style="list-style-type: none"><li>● The auto tuning mode 1 may not be performed properly if all of the following conditions are not satisfied.<ul style="list-style-type: none"><li>▪ Time to reach 2000 r/min is the acceleration/deceleration time constant of 5 s or less.</li><li>▪ Speed is 150 r/min or higher.</li><li>▪ The load to motor inertia ratio is 100 times or less.</li><li>▪ The acceleration/deceleration torque is 10% or more of the rated torque.</li></ul></li><li>● Under operating conditions which will impose sudden disturbance torque during acceleration/deceleration or on a machine which is extremely loose, auto tuning may not function properly, either. In such cases, use the auto tuning mode 2 or manual mode to make gain adjustment.</li></ul>

##### (2) Auto tuning mode 2

Use the auto tuning mode 2 when proper gain adjustment cannot be made by auto tuning mode 1. Since the load to motor inertia ratio is not estimated in this mode, set the value of a correct load to motor inertia ratio in [Pr. PB06].

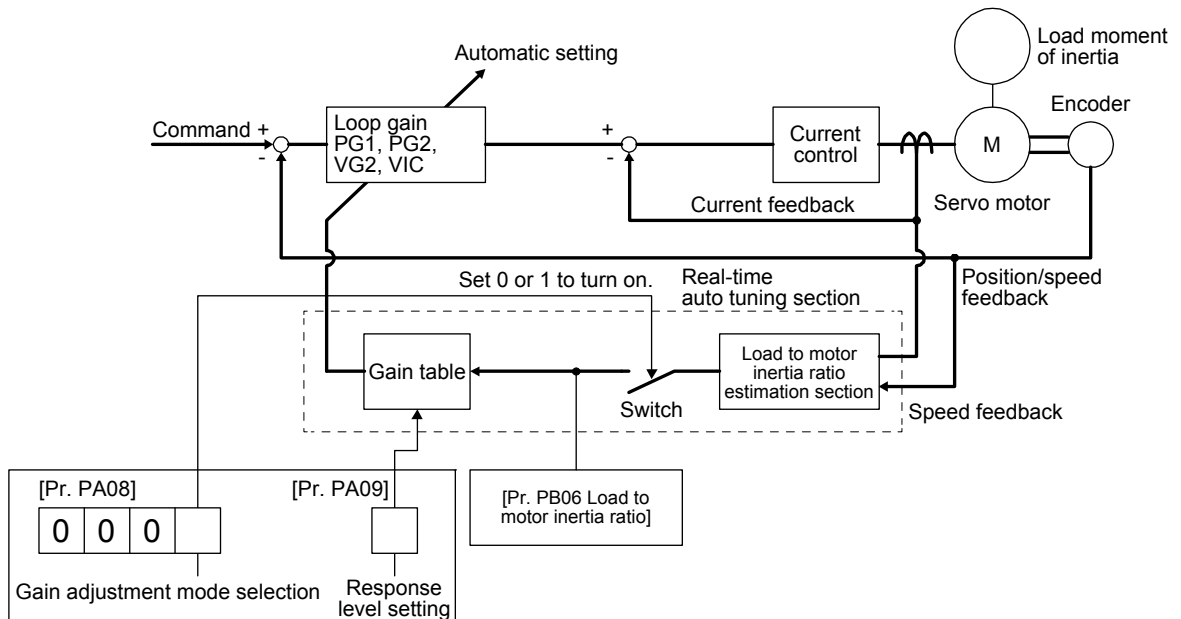
The following parameters are automatically adjusted in the auto tuning mode 2.

Parameter	Symbol	Name
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

## 6. NORMAL GAIN ADJUSTMENT

### 6.3.2 Auto tuning mode basis

The block diagram of real-time auto tuning is shown below.



When a servo motor is accelerated/decelerated, the load to motor inertia ratio estimation section always estimates the load to motor inertia ratio from the current and speed of the servo motor. The results of estimation are written to [Pr. PB06 Load to motor inertia ratio]. These results can be confirmed on the status display screen of the MR Configurator2.

If you have already known the value of the load to motor inertia ratio or failed to estimate, set "Gain adjustment mode selection" to "Auto tuning mode 2 ( \_ \_ 2)" in [Pr. PA08] to stop the estimation (turning off the switch in above diagram), and set the load to motor inertia ratio ([Pr. PB06]) manually.

From the preset load to motor inertia ratio ([Pr. PB06]) value and response ([Pr. PA09]), the optimum loop gains are automatically set on the basis of the internal gain table.

The auto tuning results are saved in the EEPROM of the servo amplifier every 60 minutes since power-on. At power-on, auto tuning is performed with the value of each loop gain saved in the EEPROM being used as an initial value.

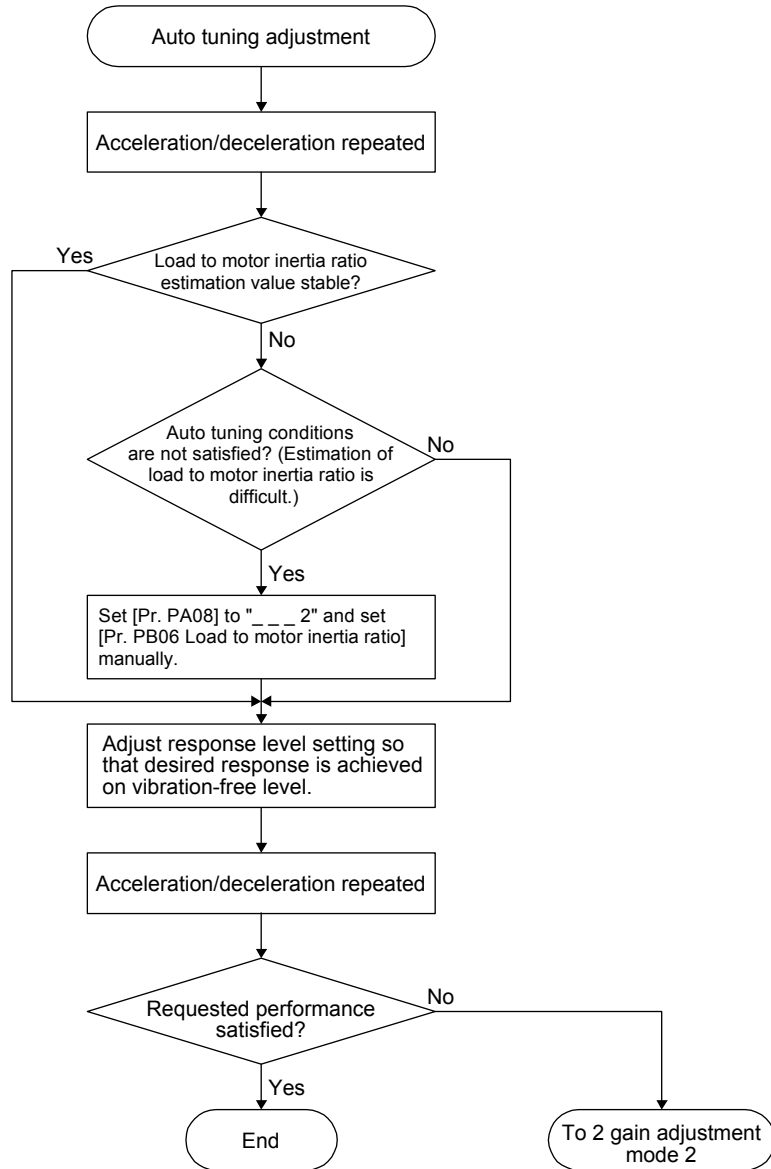
POINT
<ul style="list-style-type: none"> <li>● If sudden disturbance torque is imposed during operation, the load to motor inertia ratio may be misestimated temporarily. In such a case, set "Gain adjustment mode selection" to "Auto tuning mode 2 ( _ _ 2)" in [Pr. PA08] and then set the correct load to motor inertia ratio in [Pr. PB06].</li> <li>● When any of the auto tuning mode 1 and auto tuning mode settings is changed to the manual mode 2 setting, the current loop gains and load to motor inertia ratio estimation value are saved in the EEPROM.</li> </ul>



## 6. NORMAL GAIN ADJUSTMENT

### 6.3.3 Adjustment procedure by auto tuning

Since auto tuning is enabled before shipment from the factory, simply running the servo motor automatically sets the optimum gains that match the machine. Merely changing the response level setting value as required completes the adjustment. The adjustment procedure is as follows.



## 6. NORMAL GAIN ADJUSTMENT

### 6.3.4 Response level setting in auto tuning mode

Set the response of the whole servo system by [Pr. PA09]. As the response level setting is increased, the track ability and settling time for a command decreases, but a too high response level will generate vibration. Hence, make setting until desired response is obtained within the vibration-free range.

If the response level setting cannot be increased up to the desired response because of machine resonance beyond 100 Hz, filter tuning mode selection in [Pr. PB01] or machine resonance suppression filter in [Pr. PB13] to [Pr. PB16], and [Pr. PB46] to [Pr. PB51] may be used to suppress machine resonance.

Suppressing machine resonance may allow the response level setting to increase. Refer to section 7.1.1 and 7.1.2 for settings of the adaptive tuning mode and machine resonance suppression filter.

[Pr. PA09]

Setting value	Machine characteristic	
	Response	Guideline for machine resonance frequency [Hz]
1	↑ ↓	2.7
2		3.6
3		4.9
4		6.6
5		10.0
6		11.3
7		12.7
8		14.3
9		16.1
10		18.1
11		20.4
12		23.0
13		25.9
14		29.2
15		32.9
16		37.0
17		41.7
18		47.0
19		52.9
20	Middle response	59.6

Setting value	Machine characteristic	
	Response	Guideline for machine resonance frequency [Hz]
21	↑ ↓	67.1
22		75.6
23		85.2
24		95.9
25		108.0
26		121.7
27		137.1
28		154.4
29		173.9
30		195.9
31		220.6
32		248.5
33		279.9
34		315.3
35		355.1
36		400.0
37		446.6
38		501.2
39		571.5
40		High response

## 6. NORMAL GAIN ADJUSTMENT

### 6.4 Manual mode

If you are not satisfied with the adjustment of auto tuning, you can make simple manual adjustment with three parameters.

POINT
<p>● If machine resonance occurs, filter tuning mode selection in [Pr. PB01] or machine resonance suppression filter in [Pr. PB13] to [Pr. PB16] and [Pr. PB46] to [Pr. PB51] may be used to suppress machine resonance. (Section 7.1.1, 7.1.2)</p>

(1) For speed control

(a) Parameter

The following parameters are used for gain adjustment.

Parameter	Symbol	Name
PB06	GD2	Load to motor inertia ratio
PB07	PG1	Model loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to section 6.3.3.	
2	Change the setting of auto tuning to the manual mode ([Pr. PA08]: ___ 3).	
3	Set an estimated value to the load to motor inertia ratio. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the model loop gain, and return slightly if overshoot takes place.	Increase the model loop gain.
8	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with the adaptive tuning mode or machine resonance suppression filter and then executing steps 3 to 7.	Suppression of machine resonance Refer to section 7.1.1 and 7.1.2.
9	While checking the motor status, fine-adjust each gain.	Fine adjustment

## 6. NORMAL GAIN ADJUSTMENT

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### (c) Parameter adjustment

#### 1) [Pr. PB09 Speed loop gain]

This parameter determines the response level of the speed control loop. Increasing the setting increases the response level, but the mechanical system is liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression.

$$\text{Speed loop response frequency [Hz]} = \frac{\text{Speed loop gain}}{(1 + \text{Load to motor inertia ratio}) \times 2\pi}$$

#### 2) [Pr. PB10 Speed integral compensation]

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load to motor inertia ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression.

$$\text{Speed integral compensation setting [ms]} \geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain}/(1 + \text{Load to motor inertia ratio})}$$

#### 3) [Pr. PB07 Model loop gain]

This parameter determines the response level to a speed command. Increasing the value improves track ability to a speed command, but a too high value will make overshoot liable to occur at settling.

$$\text{Estimated model loop gain} \leq \frac{\text{Speed loop gain}}{(1 + \text{Load to motor inertia ratio})} \times \left( \frac{1}{4} \text{ to } \frac{1}{8} \right)$$

### (2) For position control

#### (a) Parameter

The following parameters are used for gain adjustment.

Parameter	Symbol	Name
PB06	GD2	Load to motor inertia ratio
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

## 6. NORMAL GAIN ADJUSTMENT

### (b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to section 6.3.3.	
2	Change the setting of auto tuning to the manual mode ([Pr. PA08]: __ _ 3).	
3	Set an estimated value to the load to motor inertia ratio. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain and the position loop gain. Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the position loop gain, and return slightly if vibration takes place.	Increase the position loop gain.
8	Increase the model loop gain, and return slightly if overshoot takes place.	Increase the model loop gain.
9	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with the adaptive tuning mode or machine resonance suppression filter and then executing steps 3 to 8.	Suppression of machine resonance Section 7.1.1 and 7.1.2
10	While checking the settling characteristic and motor status, fine-adjust each gain.	Fine adjustment

### (c) Parameter adjustment

#### 1) [Pr. PB09 Speed loop gain]

This parameter determines the response level of the speed control loop. Increasing the setting increases the response level, but the mechanical system is liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression.

$$\text{Speed loop response frequency [Hz]} = \frac{\text{Speed loop gain}}{(1 + \text{Load to motor inertia ratio}) \times 2\pi}$$

#### 2) [Pr. PB10 Speed integral compensation]

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load to motor inertia ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression.

$$\text{Speed integral compensation setting [ms]} \geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain}/(1 + \text{Load to motor inertia ratio})}$$

## 6. NORMAL GAIN ADJUSTMENT

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3) [Pr. PB08 Position loop gain]

This parameter determines the response level to a disturbance to the position control loop. Increasing the position loop gain increases the response level to a disturbance, but the mechanical system is liable to vibrate.

$$\text{Position loop gain guideline} \leq \frac{\text{Speed loop gain}}{(1 + \text{Load to motor inertia ratio})} \times \left( \frac{1}{4} \text{ to } \frac{1}{8} \right)$$

4) [Pr. PB07 Model loop gain]

This parameter determines the response level to a position command. Increasing the value improves track ability to a position command, but a too high value will make overshoot liable to occur at settling.

$$\text{Estimated model loop gain} \leq \frac{\text{Speed loop gain}}{(1 + \text{Load to motor inertia ratio})} \times \left( \frac{1}{4} \text{ to } \frac{1}{8} \right)$$

## 6. NORMAL GAIN ADJUSTMENT

### 6.5 2 gain adjustment mode

Use the 2 gain adjustment mode to match the position loop gains of the axes when performing the interpolation operation of servo motors of two or more axes for an X-Y table or the like. In this mode, manually set the model loop gain that determines command track ability. Other parameters for gain adjustment are set automatically.

#### (1) 2 gain adjustment mode 1

For the 2 gain adjustment mode 1, manually set the model loop gain that determines command track ability. The mode constantly estimates the load to motor inertia ratio, and automatically set other parameters for gain adjustment to optimum gains using auto tuning response.

The following parameters are used for 2 gain adjustment mode 1.

##### (a) Automatically adjusted parameter

The following parameters are automatically adjusted by auto tuning.

Parameter	Symbol	Name
PB06	GD2	Load to motor inertia ratio
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

##### (b) Manually adjusted parameter

The following parameters are adjustable manually.

Parameter	Symbol	Name
PA09	RSP	Auto tuning response
PB07	PG1	Model loop gain

#### (2) 2 gain adjustment mode 2

Use 2 gain adjustment mode 2 when proper gain adjustment cannot be made with 2 gain adjustment mode 1. Since the load to motor inertia ratio is not estimated in this mode, set the value of a proper load to motor inertia ratio in [Pr. PB06].

The following parameters are used for 2 gain adjustment mode 2.

##### (a) Automatically adjusted parameter

The following parameters are automatically adjusted by auto tuning.

Parameter	Symbol	Name
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

##### (b) Manually adjusted parameter

The following parameters are adjustable manually.

Parameter	Symbol	Name
PA09	RSP	Auto tuning response
PB06	GD2	Load to motor inertia ratio
PB07	PG1	Model loop gain

## 6. NORMAL GAIN ADJUSTMENT

### (3) Adjustment procedure of 2 gain adjustment mode

POINT
<ul style="list-style-type: none"> <li>● Set the same value in [Pr. PB07 Model loop gain] for the axis used in 2 gain adjustment mode.</li> </ul>

Step	Operation	Description
1	Set to the auto tuning mode.	Select the auto tuning mode 1.
2	During operation, increase the response level setting value in [Pr. PA09], and return the setting if vibration occurs.	Adjustment in auto tuning mode 1
3	Check value of the model loop gain and the load to motor inertia ratio in advance.	Check the upper setting limits.
4	Set the 2 gain adjustment mode 1 ([Pr. PA08]: ___ 0).	Select the 2 gain adjustment mode 1 (interpolation mode).
5	When the load to motor inertia ratio is different from the design value, select the 2 gain adjustment mode 2 ([Pr. PA08]: ___ 4) and then set the load to motor inertia ratio manually in [Pr. PB06].	Check the load to motor inertia ratio.
6	Set the model loop gain of all the axes to be interpolated to the same value. At that time, adjust to the setting value of the axis, which has the smallest model loop gain.	Set model loop gain.
7	Considering the interpolation characteristic and motor status, fine-adjust the model loop gain and response level setting.	Fine adjustment

### (4) Parameter adjustment

[Pr. PB07 Model loop gain]

This parameter determines the response level of the position control loop. Increasing the value improves track ability to a position command, but a too high value will make overshoot liable to occur at settling.

The droop pulse value is determined by the following expression.

$$\text{Number of droop pulses [pulse]} = \frac{\text{Position command frequency [pulse/s]}}{\text{Model loop gain setting}}$$

$$\text{Position command frequency} = \frac{\text{Speed [r/min]}}{60} \times \text{Encoder resolution (number of pulses per servo motor revolution)}$$



6. NORMAL GAIN ADJUSTMENT

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MEMO

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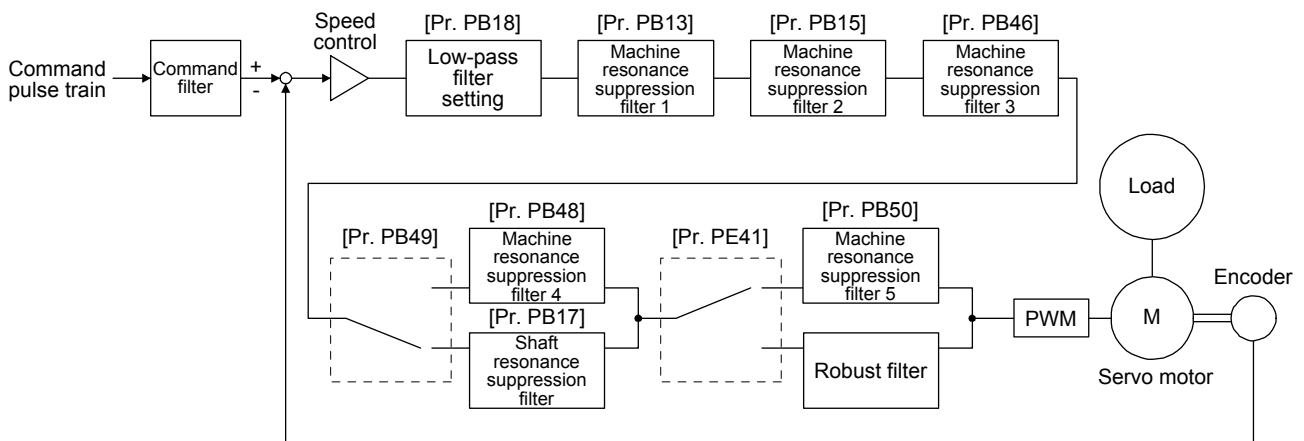
## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7. SPECIAL ADJUSTMENT FUNCTIONS

POINT
<ul style="list-style-type: none"> <li>● The functions given in this chapter need not be used normally. Use them if you are not satisfied with the machine status after making adjustment in the methods in chapter 6.</li> </ul>

#### 7.1 Filter setting

The following filters are available with MR-JE servo amplifiers.



##### 7.1.1 Machine resonance suppression filter

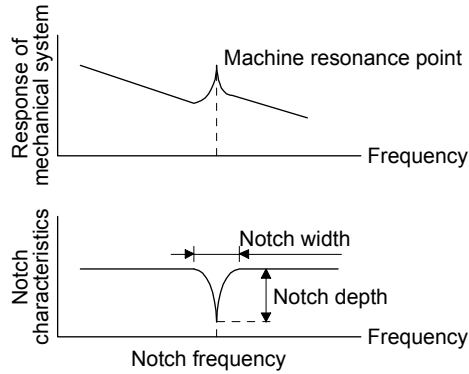
POINT
<ul style="list-style-type: none"> <li>● The machine resonance suppression filter is a delay factor for the servo system. Therefore, vibration may increase if you set an incorrect resonance frequency or set notch characteristics too deep or too wide.</li> <li>● If the frequency of machine resonance is unknown, decrease the notch frequency from higher to lower ones in order. The optimum notch frequency is set at the point where vibration is minimal.</li> <li>● A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.</li> <li>● A wider notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.</li> <li>● The machine characteristic can be grasped beforehand by the machine analyzer on MR Configurator2. This allows the required notch frequency and notch characteristics to be determined.</li> </ul>

If a mechanical system has a unique resonance point, increasing the servo system response level may cause the mechanical system to produce resonance (vibration or unusual noise) at that resonance frequency. Using the machine resonance suppression filter and adaptive tuning can suppress the resonance of the mechanical system. The setting range is 10 Hz to 4500 Hz.

## 7. SPECIAL ADJUSTMENT FUNCTIONS

### (1) Function

The machine resonance suppression filter is a filter function (notch filter) which decreases the gain of the specific frequency to suppress the resonance of the mechanical system. You can set the gain decreasing frequency (notch frequency), gain decreasing depth and width.



You can set five machine resonance suppression filters at most.

Filter	Setting parameter	Precaution	Parameter that is reset with vibration tough drive function	Parameter automatically adjusted with one-touch tuning
Machine resonance suppression filter 1	PB01/PB13/PB14	The filter can be set automatically with "Filter tuning mode selection" in [Pr. PB01].	PB13	PB01/PB13/PB14
Machine resonance suppression filter 2	PB15/PB16		PB15	PB15/PB16
Machine resonance suppression filter 3	PB46/PB47		PB46/PB47	
Machine resonance suppression filter 4	PB48/PB49	Enabling the machine resonance suppression filter 4 disables the shaft resonance suppression filter. Using the shaft resonance suppression filter is recommended because it is adjusted properly depending on the usage situation. The shaft resonance suppression filter is enabled for the initial setting.		PB48/PB49
Machine resonance suppression filter 5	PB50/PB51	Enabling the robust filter disables the machine resonance suppression filter 5. The robust filter is disabled for the initial setting.		

## 7. SPECIAL ADJUSTMENT FUNCTIONS

---

### (2) Parameter

#### (a) Machine resonance suppression filter 1 ([Pr. PB13] and [Pr. PB14])

Set the notch frequency, notch depth and notch width of the machine resonance suppression filter 1 ([Pr. PB13] and [Pr. PB14])

When you select "Manual setting ( \_ \_ \_ 2)" of "Filter tuning mode selection" in [Pr. PB01], the setting of the machine resonance suppression filter 1 is enabled.

#### (b) Machine resonance suppression filter 2 ([Pr. PB15] and [Pr. PB16])

To use this filter, select "Enabled ( \_ \_ \_ 1)" of "Machine resonance suppression filter 2 selection" in [Pr. PB16].

How to set the machine resonance suppression filter 2 ([Pr. PB15] and [Pr. PB16]) is the same as for the machine resonance suppression filter 1 ([Pr. PB13] and [Pr. PB14]).

#### (c) Machine resonance suppression filter 3 ([Pr. PB46] and [Pr. PB47])

To use this filter, select "Enabled ( \_ \_ \_ 1)" of "Machine resonance suppression filter 3 selection" in [Pr. PB47].

How to set the machine resonance suppression filter 3 ([Pr. PB46] and [Pr. PB47]) is the same as for the machine resonance suppression filter 1 ([Pr. PB13] and [Pr. PB14]).

#### (d) Machine resonance suppression filter 4 ([Pr. PB48] and [Pr. PB49])

To use this filter, select "Enabled ( \_ \_ \_ 1)" of "Machine resonance suppression filter 4 selection" in [Pr. PB49]. However, enabling the machine resonance suppression filter 4 disables the shaft resonance suppression filter.

How to set the machine resonance suppression filter 4 ([Pr. PB48] and [Pr. PB49]) is the same as for the machine resonance suppression filter 1 ([Pr. PB13] and [Pr. PB14]).

#### (e) Machine resonance suppression filter 5 ([Pr. PB50] and [Pr. PB51])

To use this filter, select "Enabled ( \_ \_ \_ 1)" of "Machine resonance suppression filter 5 selection" in [Pr. PB51]. However, enabling the robust filter ([Pr. PE41: \_ \_ \_ 1]) disables the machine resonance suppression filter 5.

How to set the machine resonance suppression filter 5 ([Pr. PB50] and [Pr. PB51]) is the same as for the machine resonance suppression filter 1 ([Pr. PB13] and [Pr. PB14]).

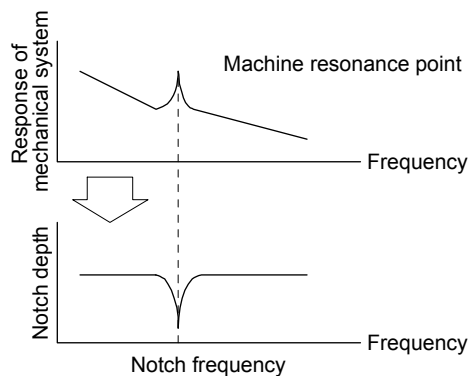
## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.1.2 Adaptive filter II

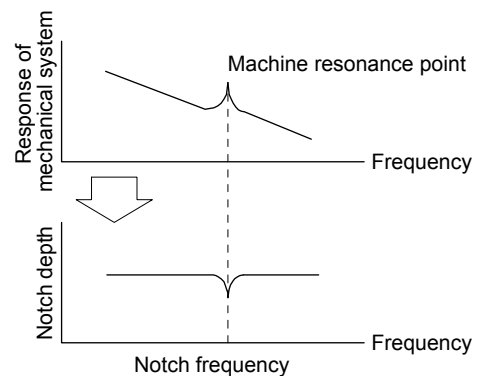
POINT
<ul style="list-style-type: none"> <li>● The machine resonance frequency which adaptive filter II (adaptive tuning) can respond to is about 100 Hz to 2.25 kHz. As for the resonance frequency out of the range, set manually.</li> <li>● When adaptive tuning is executed, vibration sound increases as an excitation signal is forcibly applied for several seconds.</li> <li>● When adaptive tuning is executed, machine resonance is detected for a maximum of 10 s and a filter is generated. After filter generation, the adaptive tuning mode automatically shifts to the manual setting.</li> <li>● Adaptive tuning generates the optimum filter with the currently set control gains. If vibration occurs when the response setting is increased, execute adaptive tuning again.</li> <li>● During adaptive tuning, a filter having the best notch depth at the set control gain is generated. To allow a filter margin against machine resonance, increase the notch depth in the manual setting.</li> <li>● Adaptive vibration suppression control may provide no effect on a mechanical system which has complex resonance characteristics.</li> <li>● Adaptive tuning in the high accuracy mode is available with servo amplifiers with software version C5 or later. The frequency is estimated more accurately in the high accuracy mode compared to the standard mode. However, the tuning sound may be larger in the high accuracy mode.</li> </ul>

#### (1) Function

Adaptive filter II (adaptive tuning) is a function in which the servo amplifier detects machine vibration for a predetermined period of time and sets the filter characteristics automatically to suppress mechanical system vibration. Since the filter characteristics (frequency, depth) are set automatically, you need not be conscious of the resonance frequency of a mechanical system.



When machine resonance is large and frequency is low



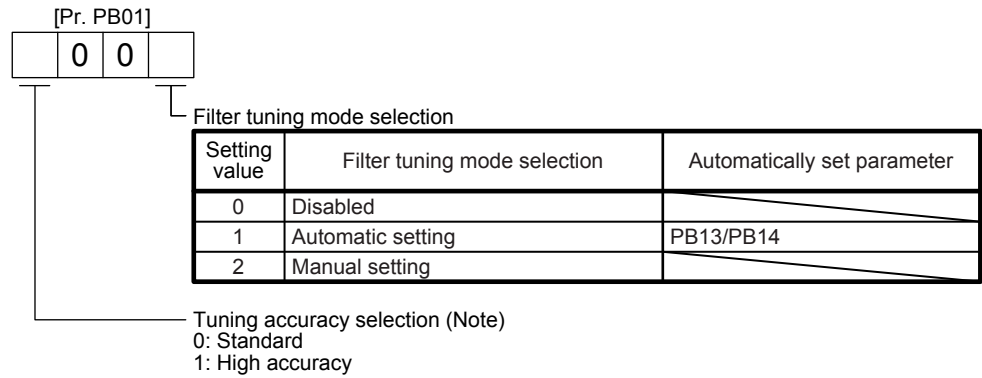
When machine resonance is small and frequency is high

## 7. SPECIAL ADJUSTMENT FUNCTIONS

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### (2) Parameter

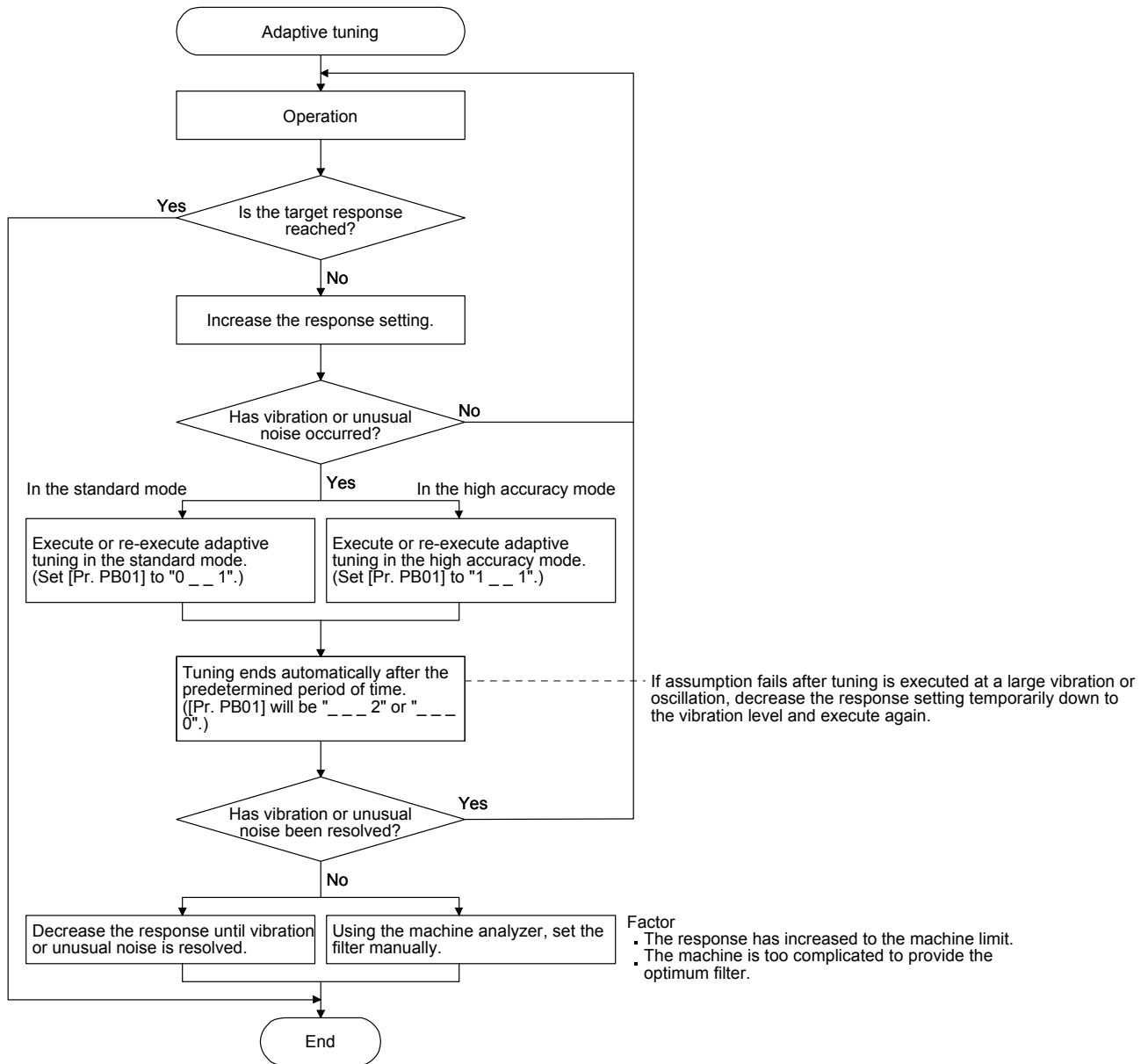
Select how to set the filter tuning in [Pr. PB01 Adaptive tuning mode (adaptive filter II)].



Note. This digit is available with servo amplifier with software version C5 or later.

# 7. SPECIAL ADJUSTMENT FUNCTIONS

## (3) Adaptive tuning mode procedure



## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.1.3 Shaft resonance suppression filter

POINT
<p>● This filter is set properly by default according to servo motor you use and load moment of inertia. It is recommended that [Pr. PB23] be set to "___ 0" (automatic setting) because changing "Shaft resonance suppression filter selection" in [Pr. PB23] or [Pr. PB17 Shaft resonance suppression filter] may lower the performance.</p>

#### (1) Function

When a load is mounted to the servo motor shaft, resonance by shaft torsion during driving may generate a mechanical vibration at high frequency. The shaft resonance suppression filter suppresses the vibration.

When you select "Automatic setting", the filter will be set automatically on the basis of the servo motor you use and the load to motor inertia ratio. The disabled setting increases the response of the servo amplifier for high resonance frequency.

#### (2) Parameter

Set "Shaft resonance suppression filter selection" in [Pr. PB23].

[Pr. PB23]

0	1	0	
---	---	---	--

Shaft resonance suppression filter selection  
 0: Automatic setting  
 1: Manual setting  
 2: Disabled

To set [Pr. PB17 Shaft resonance suppression filter] automatically, select "Automatic setting".

To set [Pr. PB17 Shaft resonance suppression filter] manually, select "Manual setting". The setting values are as follows.

Shaft resonance suppression filter setting frequency selection

Setting value	Frequency [Hz]	Setting value	Frequency [Hz]
__ 0 0	Disabled	__ 1 0	562
__ 0 1	Disabled	__ 1 1	529
__ 0 2	4500	__ 1 2	500
__ 0 3	3000	__ 1 3	473
__ 0 4	2250	__ 1 4	450
__ 0 5	1800	__ 1 5	428
__ 0 6	1500	__ 1 6	409
__ 0 7	1285	__ 1 7	391
__ 0 8	1125	__ 1 8	375
__ 0 9	1000	__ 1 9	360
__ 0 A	900	__ 1 A	346
__ 0 B	818	__ 1 B	333
__ 0 C	750	__ 1 C	321
__ 0 D	692	__ 1 D	310
__ 0 E	642	__ 1 E	300
__ 0 F	600	__ 1 F	290



## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.1.4 Low-pass filter

#### (1) Function

When a ball screw or the like is used, resonance of high frequency may occur as the response level of the servo system is increased. To prevent this, the low-pass filter is enabled for a torque command as the initial value. The filter frequency of the low-pass filter is automatically adjusted to the value in the following equation.

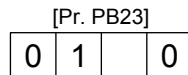
$$\text{Filter frequency ([rad/s])} = \frac{VG2}{1 + GD2} \times 8$$

However, when an automatically adjusted value is smaller than VG2, the filter frequency will be the VG2 value.

To set [Pr. PB18] manually, select "Manual setting ( \_ \_ 1 \_ )" of "Low-pass filter selection" in [Pr. PB23].

#### (2) Parameter

Set "Low-pass filter selection" in [Pr. PB23].



Low-pass filter selection  
 0: Automatic setting  
 1: Manual setting  
 2: Disabled

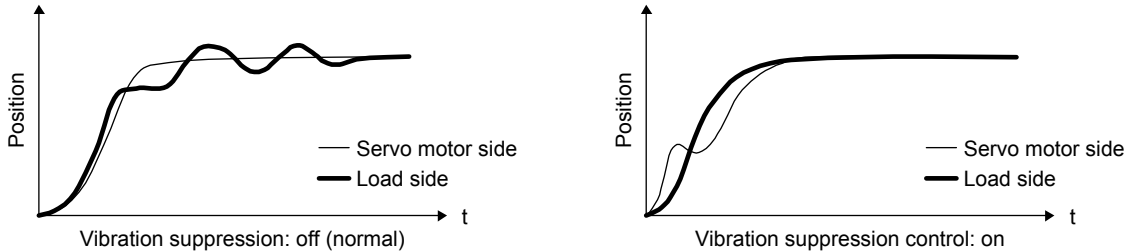
### 7.1.5 Advanced vibration suppression control II

POINT	
●	The function is enabled when "Gain adjustment mode selection" in [Pr. PA08] is "Auto tuning mode 2 ( _ _ _ 2)", "Manual mode ( _ _ _ 3)", or "2 gain adjustment mode 2 ( _ _ _ 4)".
●	The machine resonance frequency supported in the vibration suppression control tuning mode is 1.0 Hz to 100.0 Hz. As for the vibration out of the range, set manually.
●	Stop the servo motor before changing the vibration suppression control-related parameters. Otherwise, it may cause an unexpected operation.
●	For positioning operation during execution of vibration suppression control tuning, provide a stop time to ensure a stop after vibration damping.
●	Vibration suppression control tuning may not make normal estimation if the residual vibration at the servo motor side is small.
●	Vibration suppression control tuning sets the optimum parameter with the currently set control gains. When the response setting is increased, set vibration suppression control tuning again.
●	When using the vibration suppression control 2, set " _ _ _ 1" in [Pr. PA24].

## 7. SPECIAL ADJUSTMENT FUNCTIONS

### (1) Function

Use the vibration suppression control to further suppress load-side vibration, such as work-side vibration and base shake. The servo motor-side operation is adjusted for positioning so that the machine does not vibrate.



When the advanced vibration suppression control II ([Pr. PB02 Vibration suppression control tuning mode]) is executed, the vibration frequency at load side is automatically estimated to suppress machine side vibration two times at most.

In the vibration suppression control tuning mode, this mode shifts to the manual setting after the positioning operation is performed the predetermined number of times. For manual setting, adjust the vibration suppression control 1 with [Pr. PB19] to [Pr. PB22] and vibration suppression control 2 with [Pr. PB52] to [Pr. PB55].

### (2) Parameter

Set [Pr. PB02 Vibration suppression control tuning mode (advanced vibration suppression control II)]. When you use a vibration suppression control, set "Vibration suppression control 1 tuning mode selection". When you use two vibration suppression controls, set "Vibration suppression control 2 tuning mode selection" in addition.

[Pr. PB02]  
0 0

Vibration suppression control 1 tuning mode

Setting value	Vibration suppression control 1 tuning mode selection	Automatically set parameter
__ _ 0	Disabled	
__ _ 1	Automatic setting	PB19/PB20/PB21/PB22
__ _ 2	Manual setting	

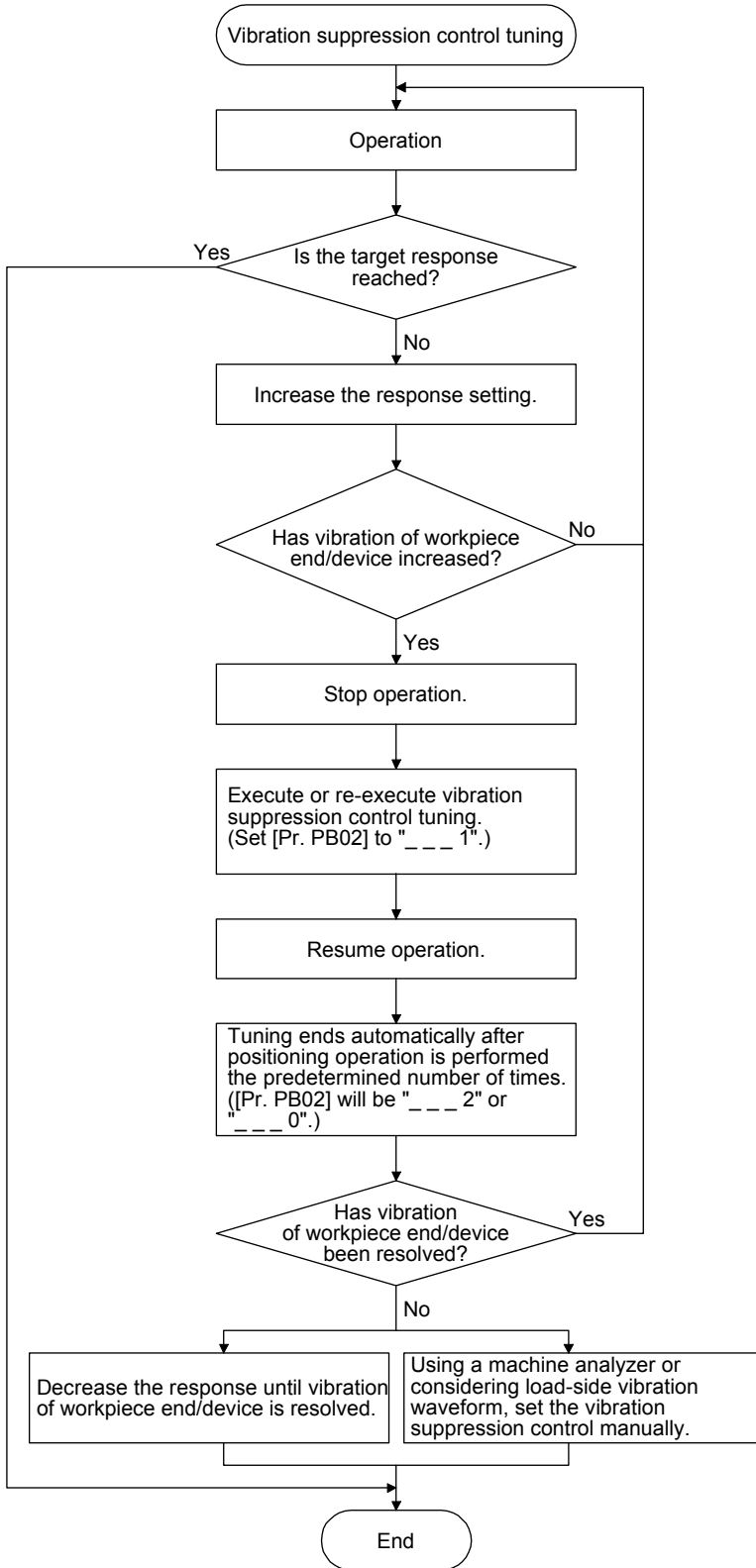
Vibration suppression control 2 tuning mode

Setting value	Vibration suppression control 2 tuning mode selection	Automatically set parameter
__ 0 _	Disabled	
__ 1 _	Automatic setting	PB52/PB53/PB54/PB55
__ 2 _	Manual setting	

# 7. SPECIAL ADJUSTMENT FUNCTIONS

## (3) Vibration suppression control tuning procedure

The following flow chart is for the vibration suppression control 1. For the vibration suppression control 2, set " \_\_ 1 \_" in [Pr. PB02] to execute the vibration suppression control tuning.



- Factor
- Estimation cannot be made as load-side vibration has not been transmitted to the servo motor side.
  - The response of the model loop gain has increased to the load-side vibration frequency (vibration suppression control limit).

## 7. SPECIAL ADJUSTMENT FUNCTIONS

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### (4) Vibration suppression control manual mode

POINT
<ul style="list-style-type: none"> <li>● When load-side vibration does not show up in servo motor-side vibration, the setting of the servo motor-side vibration frequency does not produce an effect.</li> <li>● When the anti-resonance frequency and resonance frequency can be confirmed using the machine analyzer or external equipment, do not set the same value but set different values to improve the vibration suppression performance.</li> </ul>

Measure work-side vibration and device shake with the machine analyzer or external measuring instrument, and set the following parameters to adjust vibration suppression control manually.

Setting item	Vibration suppression control 1	Vibration suppression control 2
Vibration suppression control - Vibration frequency	[Pr. PB19]	[Pr. PB52]
Vibration suppression control - Resonance frequency	[Pr. PB20]	[Pr. PB53]
Vibration suppression control - Vibration frequency damping	[Pr. PB21]	[Pr. PB54]
Vibration suppression control - Resonance frequency damping	[Pr. PB22]	[Pr. PB55]

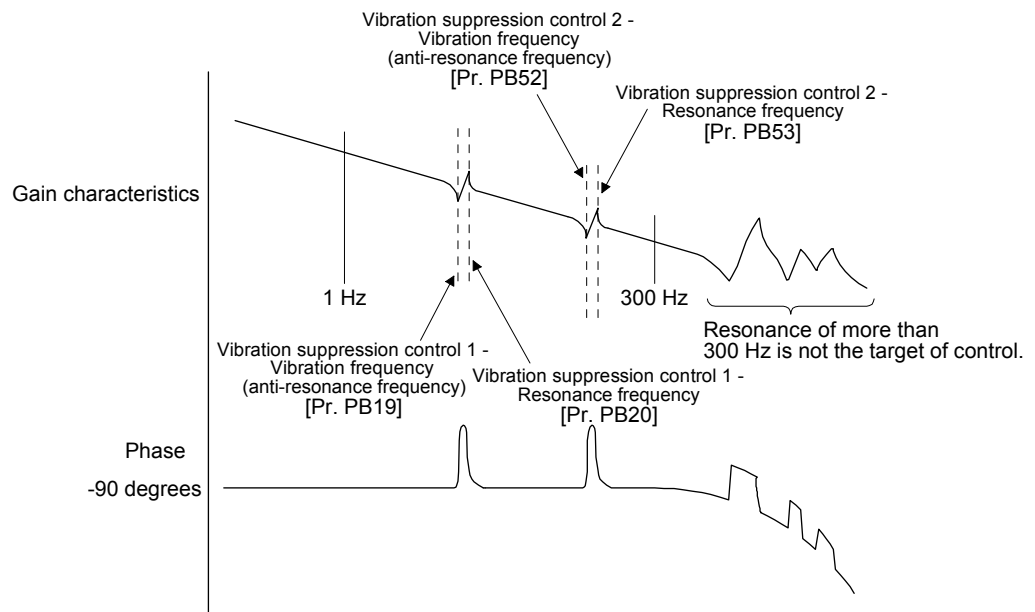
## 7. SPECIAL ADJUSTMENT FUNCTIONS

- Step 1. Select "Manual setting ( \_ \_ 2 )" of "Vibration suppression control 1 tuning mode selection" or "Manual setting ( \_ \_ 2 \_ )" of "Vibration suppression control 2 tuning mode selection" in [Pr. PB02].
- Step 2. Set "Vibration suppression control - Vibration frequency" and "Vibration suppression control - Resonance frequency" as follows.

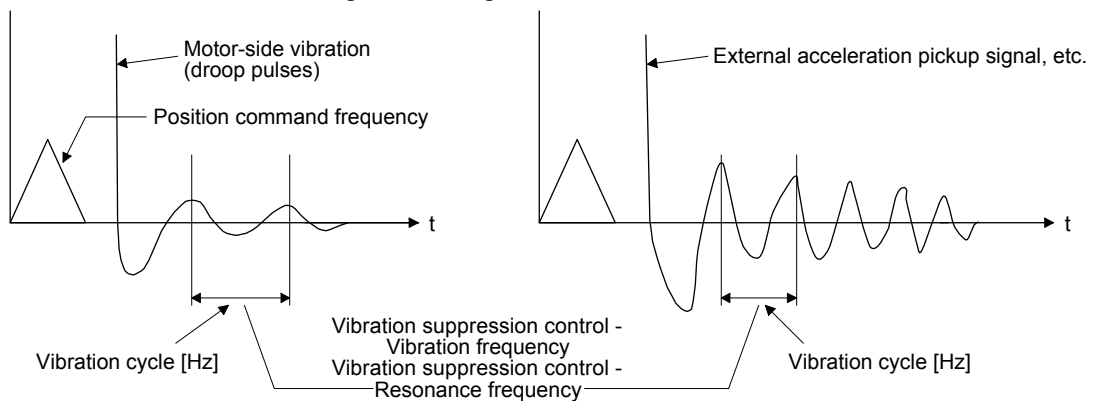
However, the value of [Pr. PB07 Model loop gain], vibration frequency, and resonance frequency have the following usable range and recommended range.

Vibration suppression control	Usable range	Recommended setting range
Vibration suppression control 1	$[Pr. PB19] > 1/2\pi \times (0.9 \times [Pr. PB07])$ $[Pr. PB20] > 1/2\pi \times (0.9 \times [Pr. PB07])$	$[Pr. PB19] > 1/2\pi \times (1.5 \times [Pr. PB07])$ $[Pr. PB20] > 1/2\pi \times (1.5 \times [Pr. PB07])$
Vibration suppression control 2	When $[Pr. PB19] < [Pr. PB52]$ , $[Pr. PB52] > (5.0 + 0.1 \times [Pr. PB07])$ $[Pr. PB53] > (5.0 + 0.1 \times [Pr. PB07])$ $1.1 < [Pr. PB52]/[Pr. PB19] < 5.5$ $[Pr. PB07] < 2\pi (0.3 \times [Pr. PB19] + 1/8 \times [Pr. PB52])$	When $[Pr. PB19] < [Pr. PB52]$ , $[Pr. PB52], [Pr. PB53] > 6.25 \text{ Hz}$ $1.1 < [Pr. PB52]/[Pr. PB19] < 4$ $[Pr. PB07] < 1/3 \times (4 \times [Pr. PB19] + 2 \times [Pr. PB52])$

- (a) When a vibration peak can be confirmed with machine analyzer using MR Configurator2, or external equipment.



- (b) When vibration can be confirmed using monitor signal or external sensor



Set the same value.

- Step 3. Fine-adjust "Vibration suppression control - Vibration frequency damping" and "Vibration suppression control - Resonance frequency damping".

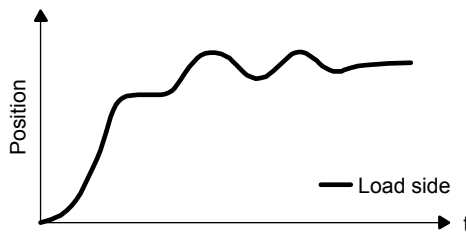
## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.1.6 Command notch filter

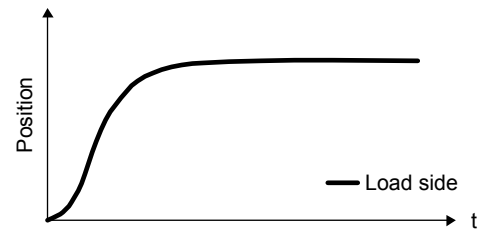
POINT
<ul style="list-style-type: none"><li>● By using the advanced vibration suppression control II and the command notch filter, the load-side vibration of three frequencies can be suppressed.</li><li>● The frequency range of machine vibration, which can be supported by the command notch filter, is between 4.5 Hz and 2250 Hz. Set a frequency close to the machine vibration frequency and within the range.</li><li>● When [Pr. PB45 Command notch filter] is changed during the positioning operation, the changed setting is not reflected. The setting is reflected approximately 150 ms after the servo motor stops (after servo-lock).</li></ul>

#### (1) Function

Command notch filter has a function that lowers the gain of the specified frequency contained in a position command. By lowering the gain, load-side vibration, such as work-side vibration and base shake, can be suppressed. Which frequency to lower the gain and how deep to lower the gain can be set.



Command notch filter: disabled



Command notch filter: enabled

## 7. SPECIAL ADJUSTMENT FUNCTIONS

### (2) Parameter

Set [Pr. PB45 Command notch filter] as shown below. For the command notch filter setting frequency, set the closest value to the vibration frequency [Hz] at the load side.

[Pr. PB45]

0			
---	--	--	--

Notch depth

Setting value	Depth [dB]
0	-40.0
1	-24.1
2	-18.1
3	-14.5
4	-12.0
5	-10.1
6	-8.5
7	-7.2
8	-6.0
9	-5.0
A	-4.1
B	-3.3
C	-2.5
D	-1.8
E	-1.2
F	-0.6

Command notch filter setting frequency

Setting value	Frequency [Hz]
00	Disabled
01	2250
02	1125
03	750
04	562
05	450
06	375
07	321
08	281
09	250
0A	225
0B	204
0C	187
0D	173
0E	160
0F	150
10	140
11	132
12	125
13	118
14	112
15	107
16	102
17	97
18	93
19	90
1A	86
1B	83
1C	80
1D	77
1E	75
1F	72
20	70
21	66
22	62
23	59
24	56
25	53
26	51
27	48
28	46
29	45
2A	43
2B	41
2C	40
2D	38
2E	37
2F	36
30	35.2
31	33.1
32	31.3
33	29.6
34	28.1
35	26.8
36	25.6
37	24.5
38	23.4
39	22.5
3A	21.6
3B	20.8
3C	20.1
3D	19.4
3E	18.8
3F	18.2
40	17.6
41	16.5
42	15.6
43	14.8
44	14.1
45	13.4
46	12.8
47	12.2
48	11.7
49	11.3
4A	10.8
4B	10.4
4C	10.0
4D	9.7
4E	9.4
4F	9.1
50	8.8
51	8.3
52	7.8
53	7.4
54	7.0
55	6.7
56	6.4
57	6.1
58	5.9
59	5.6
5A	5.4
5B	5.2
5C	5.0
5D	4.9
5E	4.7
5F	4.5

### 7.2 Gain switching function

You can switch gains with the function. You can switch gains during rotation and during stop, and can use an input device to switch gains during operation.

#### 7.2.1 Applications

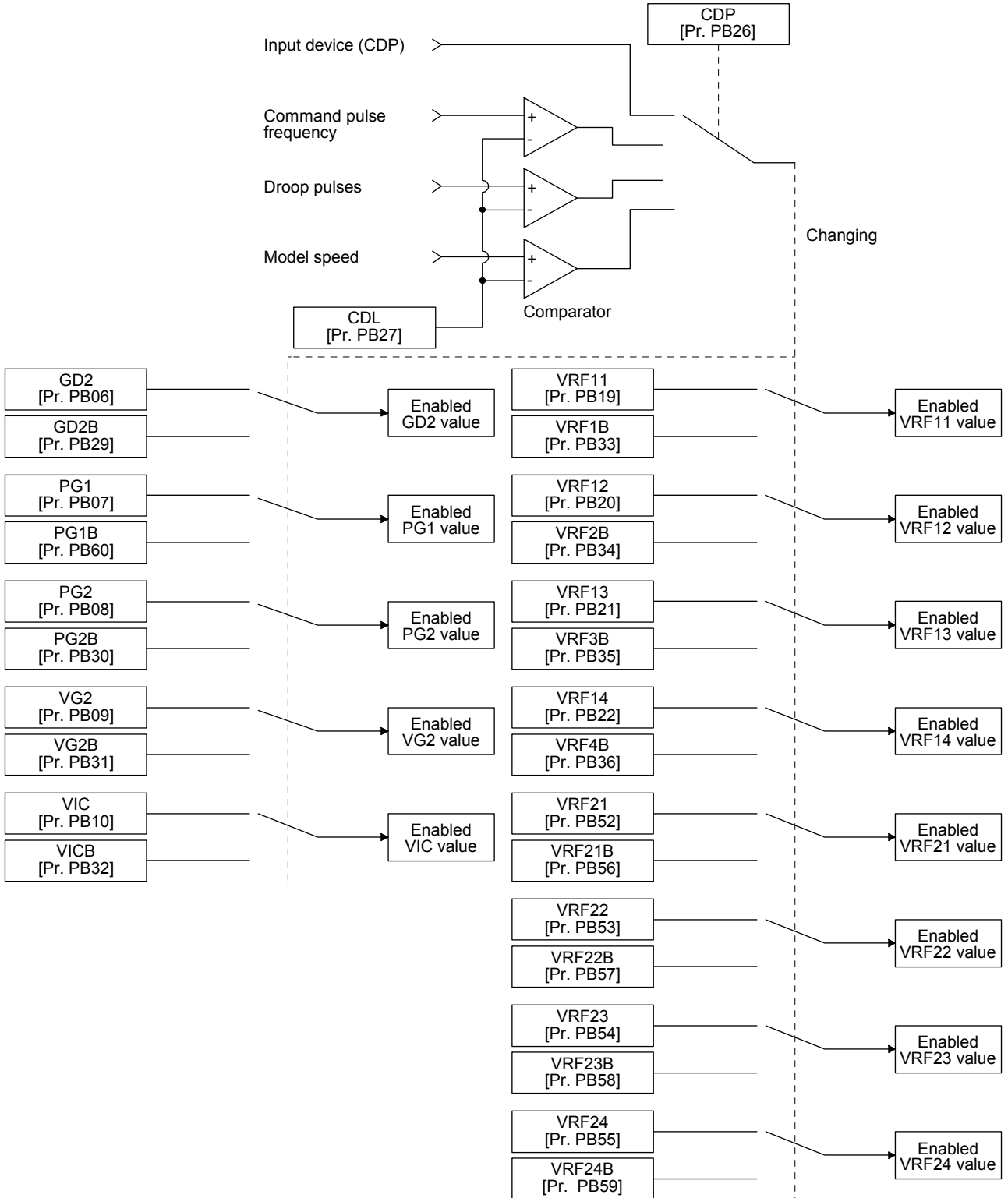
The following shows when you use the function.

- (1) You want to increase the gains during servo-lock but decrease the gains to reduce noise during rotation.
- (2) You want to increase the gains during settling to shorten the stop settling time.
- (3) You want to change the gains using an input device to ensure stability of the servo system since the load to motor inertia ratio varies greatly during a stop (e.g. a large load is mounted on a carrier).

# 7. SPECIAL ADJUSTMENT FUNCTIONS

## 7.2.2 Function block diagram

The control gains, load to motor inertia ratio, and vibration suppression control settings are changed according to the conditions selected by [Pr. PB26 Gain switching function] and [Pr. PB27 Gain switching condition].





## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.2.3 Parameter

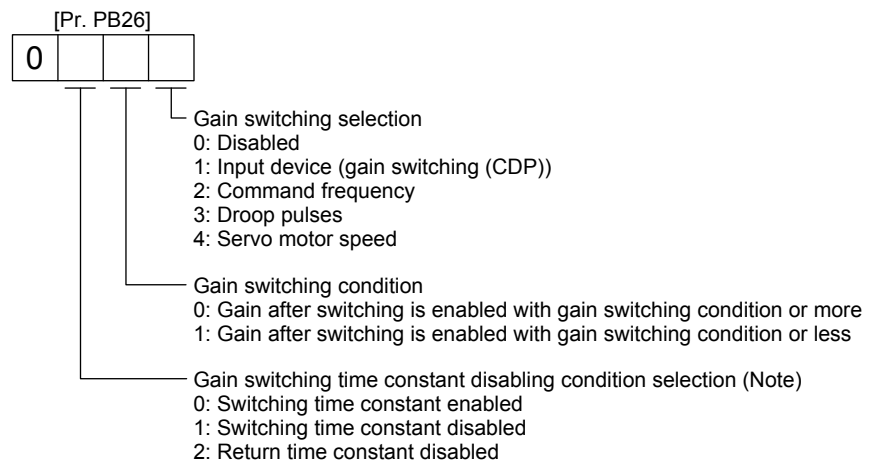
When using the gain switching function, always select "Manual mode ( \_ \_ \_ 3)" of "Gain adjustment mode selection" in [Pr. PA08 Auto tuning mode]. The gain switching function cannot be used in the auto tuning mode.

#### (1) Parameter for setting gain switching condition

Parameter	Symbol	Name	Unit	Description
PB26	CDP	Gain switching function		Select the changing condition.
PB27	CDL	Gain switching condition	[kpulse/s] /[pulse] /[r/min]	Set the changing condition values.
PB28	CDT	Gain switching time constant	[ms]	Set the filter time constant for a gain change at changing.

#### (a) [Pr. PB26 Gain switching function]

Set the gain switching condition. Select the switching condition in the first to third digits.



Note. This parameter setting is available with servo amplifiers with software version B4 or later.

#### (b) [Pr. PB27 Gain switching condition]

Set a level to switch gains with [Pr. PB27] after you select "Command frequency", "Droop pulses", or "Servo motor speed" in the gain switching selection of [Pr. PB26 Gain switching function].

The setting unit is as follows.

Gain switching condition	Unit
Command frequency	[kpulse/s]
Droop pulses	[pulse]
Servo motor speed	[r/min]

#### (c) [Pr. PB28 Gain switching time constant]

You can set the primary delay filter to each gain at gain switching. Use this parameter to suppress shock given to the machine if the gain difference is large at gain switching, for example.

## 7. SPECIAL ADJUSTMENT FUNCTIONS

### (2) Switchable gain parameter

Loop gain	Before switching			After switching		
	Parameter	Symbol	Name	Parameter	Symbol	Name
Load to motor inertia ratio	PB06	GD2	Load to motor inertia ratio	PB29	GD2B	Load to motor inertia ratio after gain switching
Model loop gain	PB07	PG1	Model loop gain	PB60	PG1B	Gain switching Model loop gain
Position loop gain	PB08	PG2	Position loop gain	PB30	PG2B	Position loop gain after gain switching
Speed loop gain	PB09	VG2	Speed loop gain	PB31	VG2B	Speed loop gain after gain switching
Speed integral compensation	PB10	VIC	Speed integral compensation	PB32	VICB	Gain switching Speed integral compensation
Vibration suppression control 1 Used to set the value of the after-changing vibration suppression control vibration frequency setting.	PB19	VRF11	Vibration suppression control 1 Used to set the value of the after-changing vibration suppression control vibration frequency setting.	PB33	VRF1B	Vibration suppression control 1 - Vibration frequency after gain switching
Vibration suppression control 1 - Resonance frequency	PB20	VRF12	Vibration suppression control 1 - Resonance frequency	PB34	VRF2B	Vibration suppression control 1 - Resonance frequency after gain switching
Vibration suppression control 1 - Vibration frequency damping	PB21	VRF13	Vibration suppression control 1 - Vibration frequency damping	PB35	VRF3B	Vibration suppression control 1 - Vibration frequency damping after gain switching
Vibration suppression control 1 - Resonance frequency damping	PB22	VRF14	Vibration suppression control 1 - Resonance frequency damping	PB36	VRF4B	Vibration suppression control 1 - Resonance frequency damping after gain switching
Vibration suppression control 2 - Vibration frequency	PB52	VRF21	Vibration suppression control 2 - Vibration frequency	PB56	VRF21B	Vibration suppression control 2 - Vibration frequency after gain switching
Vibration suppression control 2 - Resonance frequency	PB53	VRF22	Vibration suppression control 2 - Resonance frequency	PB57	VRF22B	Vibration suppression control 2 - Resonance frequency after gain switching
Vibration suppression control 2 - Vibration frequency damping	PB54	VRF23	Vibration suppression control 2 - Vibration frequency damping	PB58	VRF23B	Vibration suppression control 2 - Vibration frequency damping after gain switching
Vibration suppression control 2 - Resonance frequency damping	PB55	VRF24	Vibration suppression control 2 - Resonance frequency damping	PB59	VRF24B	Vibration suppression control 2 - Resonance frequency damping after gain switching

(a) [Pr. PB06] to [Pr. PB10]

These parameters are the same as in ordinary manual adjustment. Gain switching allows the values of load to motor inertia ratio, position loop gain, model loop gain, speed loop gain, and speed integral compensation to be switched.

(b) [Pr. PB19] to [Pr. PB22]/[Pr. PB52] to [Pr. PB55]

These parameters are the same as in ordinary manual adjustment. You can switch the vibration frequency, resonance frequency, vibration frequency damping, and resonance frequency damping by switching gain during motor stop.

## 7. SPECIAL ADJUSTMENT FUNCTIONS

- (c) [Pr. PB29 Load to motor inertia ratio after gain switching]  
Set the load to motor inertia ratio after gain switching. If the load to motor inertia ratio does not change, set it to the same value as [Pr. PB06 Load to motor inertia ratio].
- (d) [Pr. PB30 Position loop gain after gain switching], [Pr. PB31 Speed loop gain after gain switching], and [Pr. PB32 Speed integral compensation after gain switching]  
Set the values of after switching position loop gain, speed loop gain and speed integral compensation.
- (e) Vibration suppression control after gain switching ([Pr. PB33] to [Pr. PB36]/[Pr. PB56] to [Pr. PB59])/[Pr. PB60 Model loop gain after gain switching]  
The gain switching vibration suppression control and gain switching model loop gain are used only with input device (CDP) on/off.  
You can switch the vibration frequency, resonance frequency, vibration frequency damping, resonance frequency damping, and model loop gain of the vibration suppression control 1 and vibration suppression control 2.

### 7.2.4 Gain switching procedure

This operation will be described by way of setting examples.

#### (1) When you choose switching by input device (CDP)

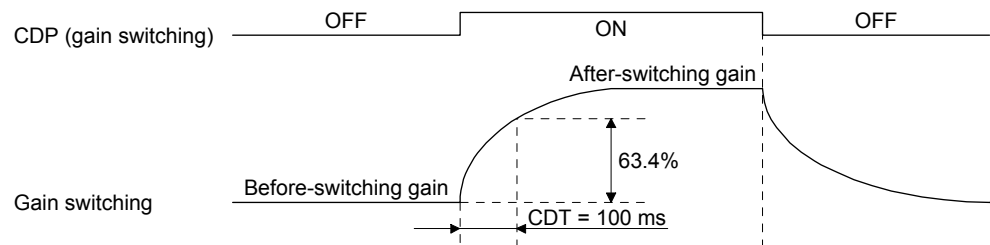
##### (a) Setting

Parameter	Symbol	Name	Setting value	Unit
PB06	GD2	Load to motor inertia ratio	4.00	[Multiplier]
PB07	PG1	Model loop gain	100	[rad/s]
PB08	PG2	Position loop gain	120	[rad/s]
PB09	VG2	Speed loop gain	3000	[rad/s]
PB10	VIC	Speed integral compensation	20	[ms]
PB19	VRF11	Vibration suppression control 1 - Vibration frequency	50	[Hz]
PB20	VRF12	Vibration suppression control 1 - Resonance frequency	50	[Hz]
PB21	VRF13	Vibration suppression control 1 - Vibration frequency damping	0.20	
PB22	VRF14	Vibration suppression control 1 - Resonance frequency damping	0.20	
PB52	VRF21	Vibration suppression control 2 - Vibration frequency	20	[Hz]
PB53	VRF22	Vibration suppression control 2 - Resonance frequency	20	[Hz]
PB54	VRF23	Vibration suppression control 2 - Vibration frequency damping	0.10	
PB55	VRF24	Vibration suppression control 2 - Resonance frequency damping	0.10	
PB29	GD2B	Load to motor inertia ratio after gain switching	10.00	[Multiplier]
PB60	PG1B	Model loop gain after gain switching	50	[rad/s]
PB30	PG2B	Position loop gain after gain switching	84	[rad/s]
PB31	VG2B	Speed loop gain after gain switching	4000	[rad/s]
PB32	VICB	Speed integral compensation after gain switching	50	[ms]
PB26	CDP	Gain switching function	0001 (Switch by input device (CDP) on/off.)	

## 7. SPECIAL ADJUSTMENT FUNCTIONS

Parameter	Symbol	Name	Setting value	Unit
PB28	CDT	Gain switching time constant	100	[ms]
PB33	VRF1B	Vibration suppression control 1 - Vibration frequency after gain switching	60	[Hz]
PB34	VRF2B	Vibration suppression control 1 - Resonance frequency after gain switching	60	[Hz]
PB35	VRF3B	Vibration suppression control 1 - Vibration frequency damping after gain switching	0.15	
PB36	VRF4B	Vibration suppression control 1 - Resonance frequency damping after gain switching	0.15	
PB56	VRF21B	Vibration suppression control 2 - Vibration frequency after gain switching	30	[Hz]
PB57	VRF22B	Vibration suppression control 2 - Resonance frequency after gain switching	30	[Hz]
PB58	VRF23B	Vibration suppression control 2 - Vibration frequency damping after gain switching	0.05	
PB59	VRF24B	Vibration suppression control 2 - Resonance frequency damping after gain switching	0.05	

(b) Switching timing chart



Model loop gain	100	→	50	→	100
Load to motor inertia ratio	4.00	→	10.00	→	4.00
Position loop gain	120	→	84	→	120
Speed loop gain	3000	→	4000	→	3000
Speed integral compensation	20	→	50	→	20
Vibration suppression control 1 - Vibration frequency	50	→	60	→	50
Vibration suppression control 1 - Resonance frequency	50	→	60	→	50
Vibration suppression control 1 - Vibration frequency damping	0.20	→	0.15	→	0.20
Vibration suppression control 1 - Resonance frequency damping	0.20	→	0.15	→	0.20
Vibration suppression control 2 - Vibration frequency	20	→	30	→	20
Vibration suppression control 2 - Resonance frequency	20	→	30	→	20
Vibration suppression control 2 - Vibration frequency damping	0.10	→	0.05	→	0.10
Vibration suppression control 2 - Resonance frequency damping	0.10	→	0.05	→	0.10

## 7. SPECIAL ADJUSTMENT FUNCTIONS

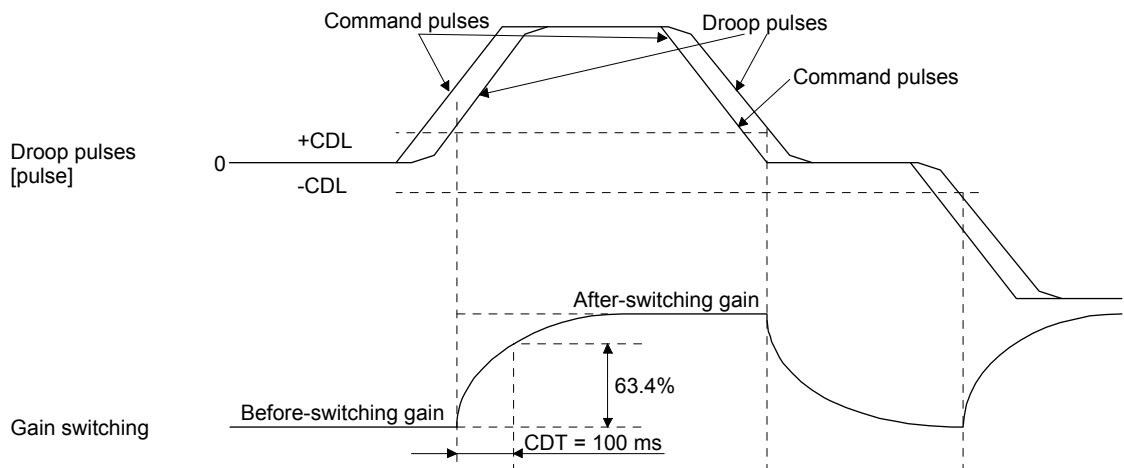
### (2) When you choose switching by droop pulses

The vibration suppression control after gain switching and model loop gain after gain switching cannot be used.

#### (a) Setting

Parameter	Symbol	Name	Setting value	Unit
PB06	GD2	Load to motor inertia ratio	4.00	[Multiplier]
PB08	PG2	Position loop gain	120	[rad/s]
PB09	VG2	Speed loop gain	3000	[rad/s]
PB10	VIC	Speed integral compensation	20	[ms]
PB29	GD2B	Load to motor inertia ratio after gain switching	10.00	[Multiplier]
PB30	PG2B	Position loop gain after gain switching	84	[rad/s]
PB31	VG2B	Speed loop gain after gain switching	4000	[rad/s]
PB32	VICB	Speed integral compensation after gain switching	50	[ms]
PB26	CDP	Gain switching selection	0003 (switching by droop pulses)	
PB27	CDL	Gain switching condition	50	[pulse]
PB28	CDT	Gain switching time constant	100	[ms]

#### (b) Switching timing chart



Load to motor inertia ratio	4.00	→	10.00	→	4.00	→	10.00
Position loop gain	120	→	84	→	120	→	84
Speed loop gain	3000	→	4000	→	3000	→	4000
Speed integral compensation	20	→	50	→	20	→	50

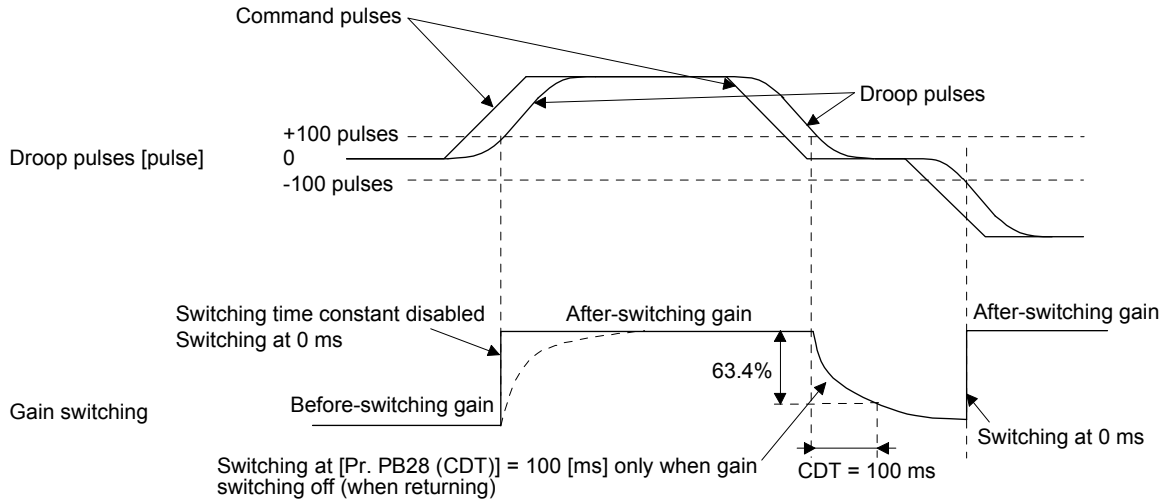
## 7. SPECIAL ADJUSTMENT FUNCTIONS

(3) When the gain switching time constant is disabled

(a) Gain switching time constant disabled was selected.

The gain switching time constant is disabled. The time constant is enabled at gain return.

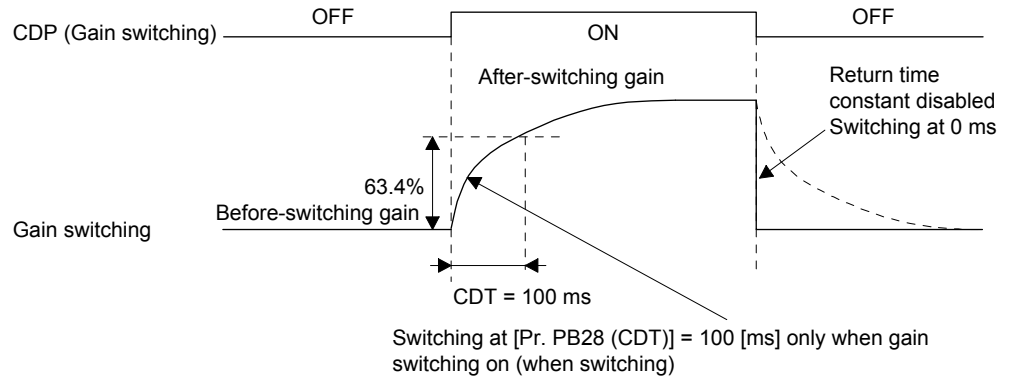
The following example shows for [Pr. PB26 (CDP)] = 0103, [Pr. PB27 (CDL)] = 100 [pulse], and [Pr. PB28 (CDT)] = 100 [ms].



(b) Gain return time constant disabled was selected.

The gain switching time constant is enabled. The time constant is disabled at gain return.

The following example shows for [Pr. PB26 (CDP)] = 0201, [Pr. PB27 (CDL)] = 0, and [Pr. PB28 (CDT)] = 100 [ms].



## 7. SPECIAL ADJUSTMENT FUNCTIONS

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### 7.3 Tough drive function

POINT
●Set enable/disable of the tough drive function with [Pr. PA20 Tough drive setting]. (Refer to section 5.2.1.)

This function makes the equipment continue operating even under the condition that an alarm occurs. The tough drive functions are the vibration tough drive and the instantaneous power failure tough drive.

#### 7.3.1 Vibration tough drive function

This function prevents vibration by resetting a filter instantaneously when machine resonance occurs due to varied machine resonance frequency caused by machine aging.

To reset the machine resonance suppression filters with the function, [Pr. PB13 Machine resonance suppression filter 1] and [Pr. PB15 Machine resonance suppression filter 2] should be set in advance. Set [Pr. PB13] and [Pr. PB15] as follows.

(1) One-touch tuning execution (section 6.2)

(2) Manual setting (section 5.2.2)

The vibration tough drive function operates when a detected machine resonance frequency is within  $\pm 30\%$  for a value set in [Pr. PB13 Machine resonance suppression filter 1] or [Pr. PB15 Machine resonance suppression filter 2].

To set a detection level of the function, set sensitivity in [Pr. PF23 Vibration tough drive - Oscillation detection level].

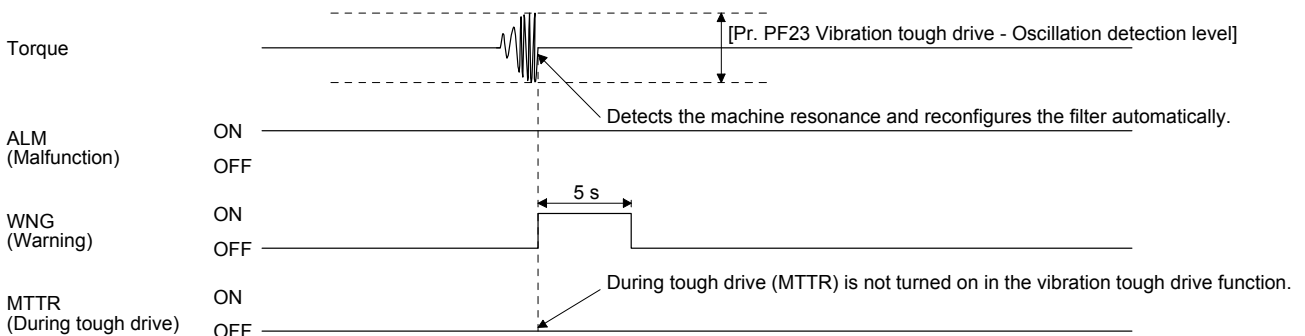
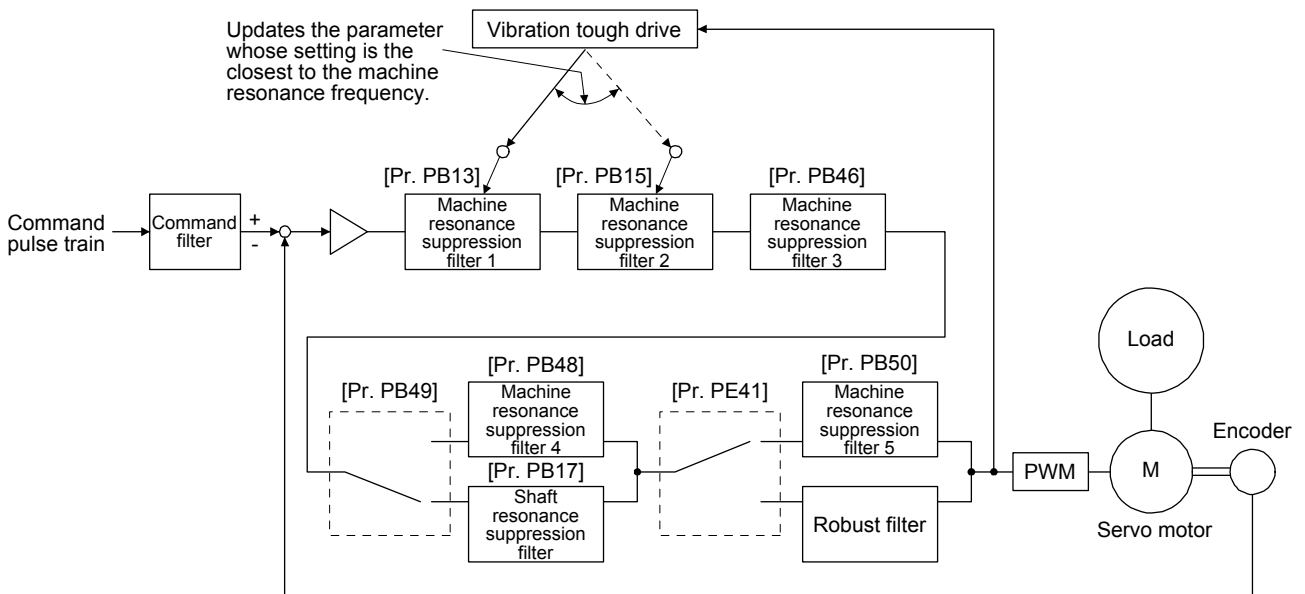
POINT
●Resetting [Pr. PB13] and [Pr. PB15] by the vibration tough drive function is performed constantly. However, the number of write times to the EEPROM is limited to once per hour.
●The vibration tough drive function does not reset [Pr. PB46 Machine resonance suppression filter 3], [Pr. PB48 Machine resonance suppression filter 4], and [Pr. PB50 Machine resonance suppression filter 5].
●The vibration tough drive function does not detect a vibration of 100 Hz or less.

# 7. SPECIAL ADJUSTMENT FUNCTIONS

The following shows the function block diagram of the vibration tough drive function.

The function detects machine resonance frequency and compare it with [Pr. PB13] and [Pr. PB15], and reset a machine resonance frequency of a parameter whose set value is closer.

Filter	Setting parameter	Precaution	Parameter that is reset with vibration tough drive function
Machine resonance suppression filter 1	PB01/PB13/PB14	The filter can be set automatically with "Filter tuning mode selection" in [Pr. PB01].	PB13
Machine resonance suppression filter 2	PB15/PB16		PB15
Machine resonance suppression filter 3	PB46/PB47		
Machine resonance suppression filter 4	PB48/PB49	Enabling the machine resonance suppression filter 4 disables the shaft resonance suppression filter. Using the shaft resonance suppression filter is recommended because it is adjusted properly depending on the usage situation. The shaft resonance suppression filter is enabled for the initial setting.	
Machine resonance suppression filter 5	PB50/PB51	Enabling the robust filter disables the machine resonance suppression filter 5. The robust filter is disabled for the initial setting.	





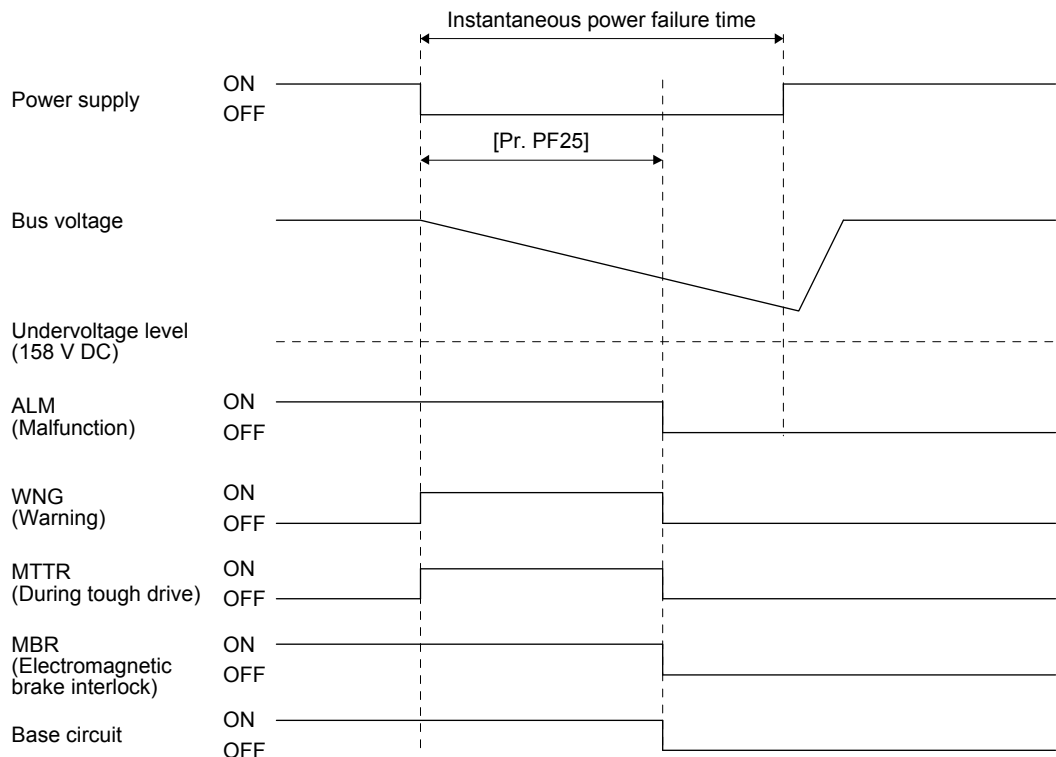
## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.3.2 Instantaneous power failure tough drive function

The instantaneous power failure tough drive function avoids [AL. 10 Undervoltage] even when an instantaneous power failure occurs during operation. When the instantaneous power failure tough drive activates, the function will increase the tolerance against instantaneous power failure using the electrical energy charged in the capacitor in the servo amplifier and will change an alarm level of [AL. 10 Undervoltage] simultaneously. The [AL. 10.1 Voltage drop in the power] detection time for the power supply can be changed by [Pr. PF25 Instantaneous power failure tough drive - detection time]. In addition, [AL. 10.2 Bus voltage drop] detection level for the bus voltage is changed automatically.

POINT
<ul style="list-style-type: none"> <li>● MBR (Electromagnetic brake interlock) will not turn off during the instantaneous power failure tough drive.</li> <li>● Selecting "Enabled ( _ _ _ 1)" for "Torque limit function selection at instantaneous power failure" in [Pr. PA26] will limit torques to save electric energy when an instantaneous power failure occurs during operation and will make [AL. 10 Undervoltage] less likely to occur.</li> <li>● When the load of instantaneous power failure is large, [AL. 10.2] caused by the bus voltage drop may occur regardless of the set value of [Pr. PF25 Instantaneous power failure tough drive - Detection time].</li> </ul>

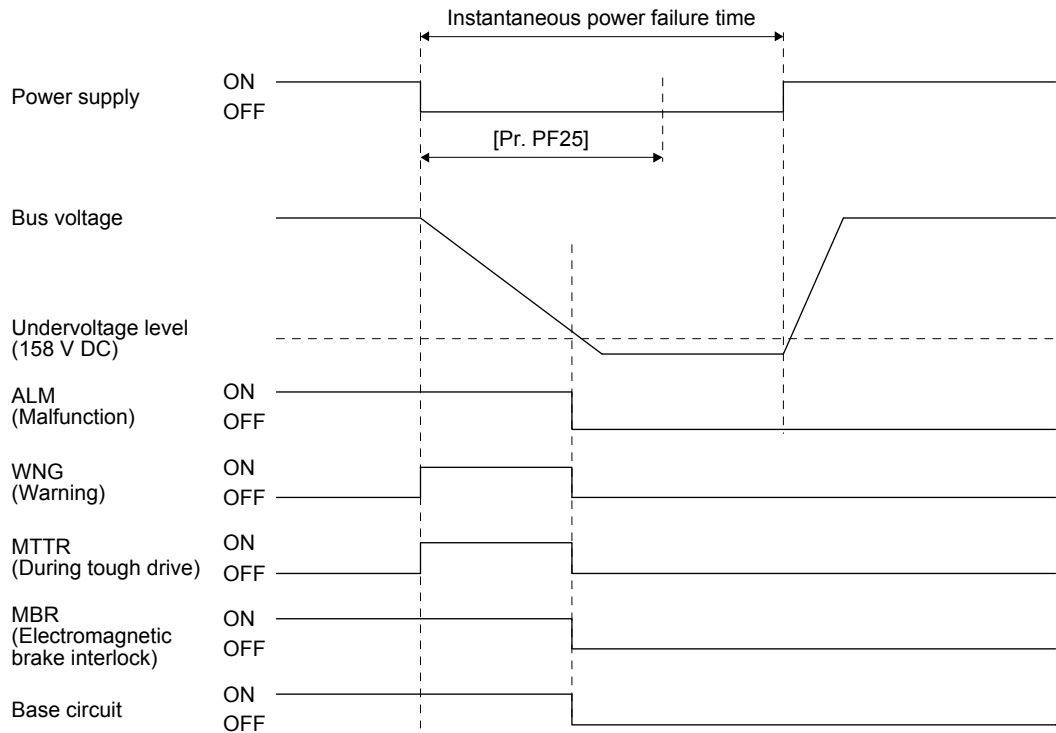
- (1) Instantaneous power failure time > [Pr. PF25 Instantaneous power failure tough drive - detection time]  
 The alarm occurs when the instantaneous power failure time exceeds [Pr. PF25 Instantaneous power failure tough drive - detection time].  
 MTTR (During tough drive) turns on after the instantaneous power failure is detected.  
 MBR (Electromagnetic brake interlock) turns off when the alarm occurs.



## 7. SPECIAL ADJUSTMENT FUNCTIONS

(2) Instantaneous power failure time < [Pr. PF25 Instantaneous power failure tough drive - detection time]  
 Operation status differs depending on how bus voltage decrease.

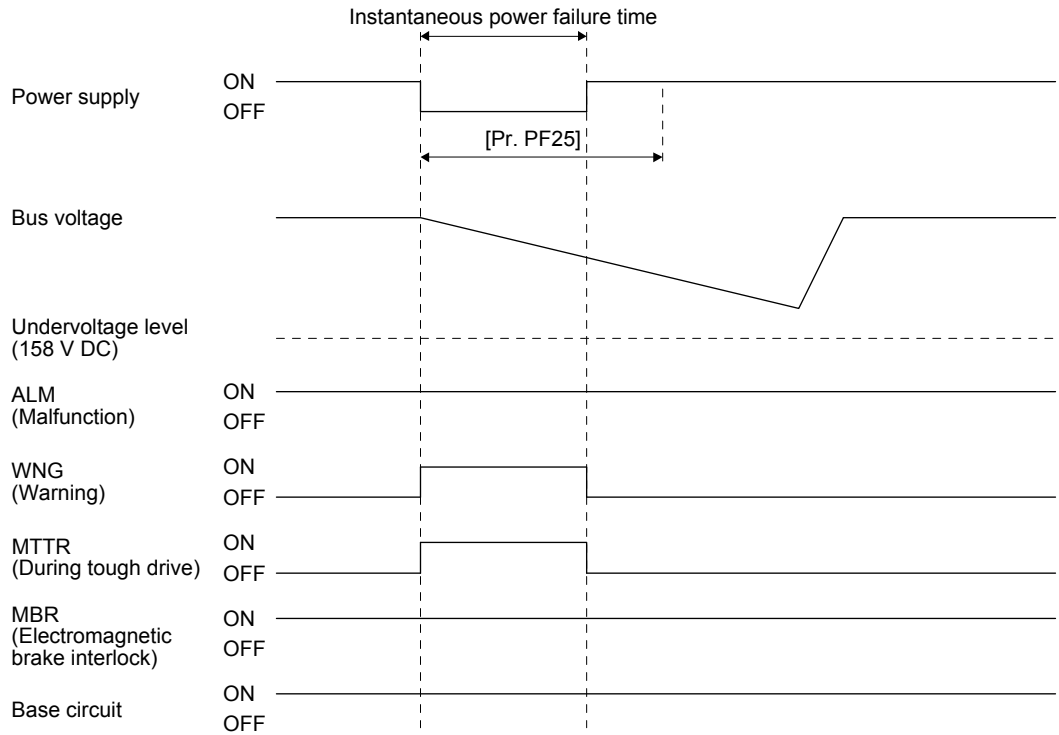
(a) When the bus voltage decreases lower than 158 V DC within the instantaneous power failure time  
 [AL. 10 Undervoltage] occurs when the bus voltage decrease lower than 158 V DC regardless of the  
 enabled instantaneous power failure tough drive.



## 7. SPECIAL ADJUSTMENT FUNCTIONS

(b) When the bus voltage does not decrease lower than 158 V DC within the instantaneous power failure time

The operation continues without alarming.



## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.4 Model adaptive control disabled

POINT
<ul style="list-style-type: none"> <li>● Change the parameters while the servo motor stops.</li> <li>● When setting auto tuning response ([Pr. PA09]), change the setting value one by one to adjust it while checking operation status of the servo motor.</li> <li>● This is used with servo amplifiers with software version B4 or later. Check the software version of the servo amplifier using MR Configurator2.</li> </ul>

#### (1) Summary

The servo amplifier has a model adaptive control. The servo amplifier has a virtual motor model and drives the servo motor following the output of the motor model in the model adaptive control. At model adaptive control disabled, the servo amplifier drives the motor with PID control without using the model adaptive control.

The following shows the available parameters at model adaptive control disabled.

Parameter	Symbol	Name
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

#### (2) Parameter setting

Set [Pr. PB25] to "\_\_\_2".

#### (3) Restrictions

The following functions are not available at model adaptive control disabled.

Function	Explanation
Forced stop deceleration function ([Pr. PA04])	Disabling the model adaptive control while the forced stop deceleration function is enabled, [AL. 37] will occur. The forced stop deceleration function is enabled at factory setting. Set [Pr. PA04] to "0___" (Forced stop deceleration function disabled).
Vibration suppression control 1 ([Pr. PB02]/[Pr. PB19]/[Pr. PB20]) Vibration suppression control 2 ([Pr. PB02]/[Pr. PB52]/[Pr. PB53])	The vibration suppression control uses the model adaptive control. Disabling the model adaptive control will also disable the vibration suppression control.
Overshoot amount compensation ([Pr. PB12])	The overshoot amount compensation uses data used by the model adaptive control. Disabling the model adaptive control will also disable the overshoot amount compensation.

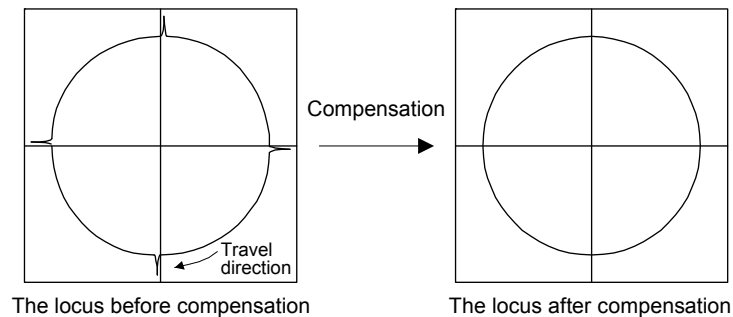
## 7. SPECIAL ADJUSTMENT FUNCTIONS

### 7.5 Lost motion compensation function

POINT
<ul style="list-style-type: none"> <li>● The lost motion compensation function is enabled only in the position control mode.</li> <li>● The lost motion compensation function is available with servo amplifiers with software version C5 or later.</li> </ul>

The lost motion compensation function corrects response delays (caused by a non-sensitive band due to friction, twist, expansion, and backlash) caused when the machine travel direction is reversed. This function contributes to improvement for protrusions that occur at a quadrant change and streaks that occur at a quadrant change during circular cutting.

This function is effective when a high follow-up performance is required such as drawing an arc with an X-Y table.

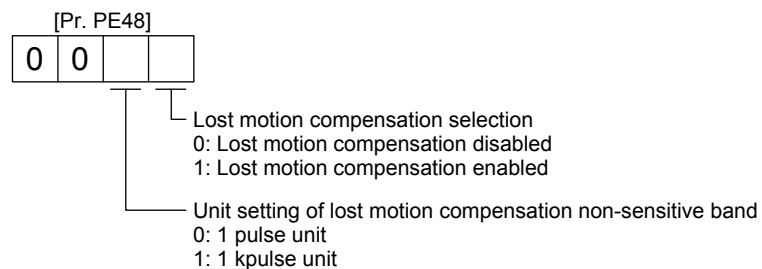


#### (1) Parameter setting

Setting [Pr. PE44] to [Pr. PE50] enables the lost motion compensation function.

##### (a) Lost motion compensation function selection ([Pr. PE48])

Select the lost motion compensation function.



##### (b) Lost motion compensation ([Pr. PE44]/[Pr. PE45])

Set the same value for the lost motion compensation for each of when the forward rotation switches to the reverse rotation and when the reverse rotation switches to the forward rotation. When the heights of protrusions differ depending on the travel direction, set the different compensation for each travel direction. Set a value twice the usual friction torque and adjust the value while checking protrusions.

##### (c) Torque offset ([Pr. PE47])

For a vertical axis, unbalanced torque occurs due to the gravity. Although setting the torque offset is usually unnecessary, setting unbalanced torque of a machine as a torque offset cancels the unbalanced torque. The torque offset does not need to be set for a machine not generating unbalanced torque.

## 7. SPECIAL ADJUSTMENT FUNCTIONS

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(d) Lost motion compensation timing ([Pr. PE49])

You can set the delay time of the lost motion compensation start timing with this parameter. When a protrusion occurs belatedly, set the lost motion compensation timing corresponding to the protrusion occurrence timing.

(e) Lost motion compensation non-sensitive band ([Pr. PE50])

When the travel direction reverses frequently around the zero speed, unnecessary lost motion compensation is triggered by the travel direction switching. By setting the lost motion compensation non-sensitive band, the speed is recognized as 0 when the fluctuation of the droop pulses is the setting value or less. This prevents unnecessary lost motion compensation.

When the value of this parameter is changed, the compensation timing is changed. Adjust the value of Lost motion compensation timing ([Pr. PE49]).

(f) Lost motion filter setting ([Pr. PE46])

Changing the value of this parameter is usually unnecessary. When a value other than 0.0 ms is set in this parameter, the high-pass filter output value of the set time constant is applied to the compensation and lost motion compensation continues.

(2) Adjustment procedure of the lost motion compensation function

(a) Measuring the load current

Measure the load currents during the forward direction feed and reverse direction feed with MR Configurator2.

(b) Setting the lost motion compensation

Calculate the friction torque from the measurement result of (2) (a) of this section and set a value twice the friction torque in [Pr. PE44] and [Pr. PE45] as lost motion compensation.

$$\text{Friction torque [\%]} = \frac{|\text{(load current during feed in the forward rotation direction [\%])} - \text{(load current during feed in the reverse rotation direction [\%])}|}{2}$$

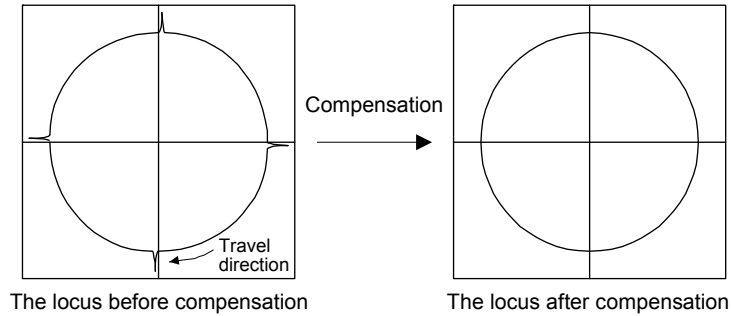
(c) Checking protrusions

Drive the servo motor and check that the protrusions are corrected.

## 7. SPECIAL ADJUSTMENT FUNCTIONS

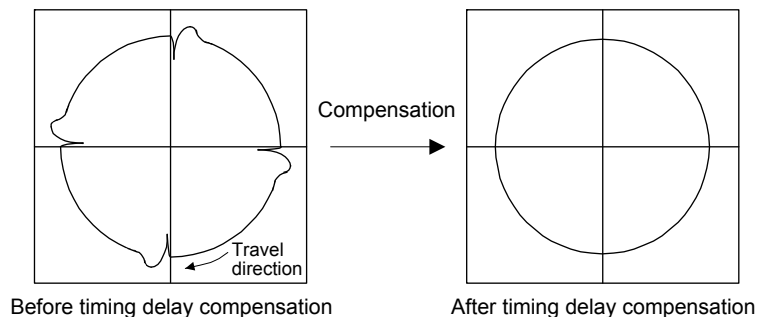
### (d) Adjusting the lost motion compensation

When protrusions still occur, the compensation is insufficient. Increase the lost motion compensation by approximately 0.5% until the protrusions are eliminated. When notches occur, the compensation is excessive. Decrease the lost motion compensation by approximately 0.5% until the notches are eliminated. Different values can be set as the compensation for each of when the forward rotation (CCW) switches to the reverse rotation (CW) and when the reverse rotation (CW) switches to the forward rotation (CCW).



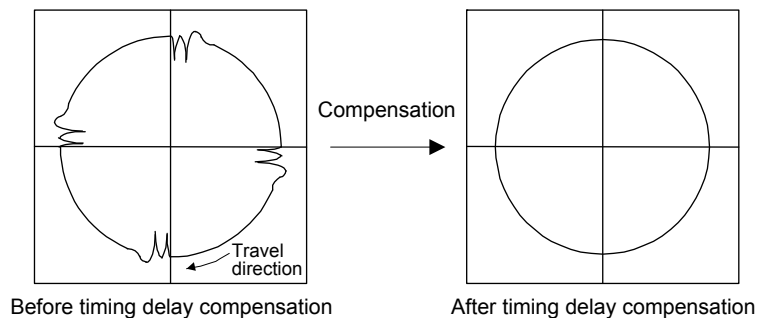
### (e) Adjusting the lost motion compensation timing

When the machine has low rigidity, the speed loop gain is set lower than the standard setting value, or the servo motor is rotating at high speed, quadrant projections may occur behind the quadrant change points. In this case, you can suppress the quadrant projections by delaying the lost motion compensation timing with [Pr. PE49 Lost motion compensation timing]. Increase the setting value of [Pr. PE49] from 0 ms (initial value) by approximately 0.5 ms to adjust the compensation timing.



### (f) Adjusting the lost motion compensation non-sensitive band

When the lost motion is compensated twice around a quadrant change point, set [Pr. PE50 Lost motion compensation non-sensitive band]. Increase the setting value so that the lost motion is not compensated twice. Setting [Pr. PE50] may change the compensation timing. Adjust the lost motion compensation timing of (2) (e) of this section.



## 8. TROUBLESHOOTING

### 8. TROUBLESHOOTING

POINT
<ul style="list-style-type: none"> <li>● Refer to "MELSERVO-JE Servo Amplifier Instruction Manual (Troubleshooting)" for details of alarms and warnings.</li> <li>● As soon as an alarm occurs, turn SON (Servo-on) off and interrupt the power.</li> <li>● [AL. 37 Parameter error] and warnings (except [AL. F0 Tough drive warning]) are not recorded in the alarm history.</li> </ul>

When an error occurs during operation, the corresponding alarm or warning is displayed. When an alarm or the warning displayed, refer to "MELSERVO-JE Servo Amplifier Instruction Manual (Troubleshooting)" to remove the failure. When an alarm occurs, ALM (Malfunction) will turn off.

#### 8.1 Explanations of the lists

(1) No./Name/Detail No./Detail name

Indicates the No./name/detail No./detail name of alarms or warnings.

(2) Stop method

For the alarms and warnings in which "SD" is written in the stop method column, the servo motor stops with the dynamic brake after forced stop deceleration. For the alarms and warnings in which "DB" or "EDB" is written in the stop method column, the servo motor stops with the dynamic brake without forced stop deceleration.

(3) Alarm deactivation

After its cause has been removed, the alarm can be deactivated in any of the methods marked ○ in the alarm deactivation column. Warnings are automatically canceled after the cause of occurrence is removed. Alarms are deactivated by alarm reset or power cycling.

Alarm deactivation	Explanation
Alarm reset	<ol style="list-style-type: none"> <li>1. Turn on RES (Reset) with an input device.</li> <li>2. Push the "SET" button while the display of the servo amplifier is in the current alarm display mode.</li> <li>3. Click "Occurring Alarm Reset" in the "Alarm Display" window of MR Configurator2.</li> </ol>
Power cycling	Turn off the power, check that the 5-digit, 7-segment LED display is off, and then turn on the power.

(4) Alarm code

To output alarm codes, set [Pr. PD34] to "\_\_\_1". Alarm codes are outputted by turning on/off bit 0 to bit 2. Warnings ([AL. 90] to [AL. F3]) do not have alarm codes. The alarm codes in the following table will be outputted when they occur. The alarm codes will not be outputted in normal condition.



# 8. TROUBLESHOOTING

## 8.2 Alarm list

	No.	Name	Detail No.	Detail name	Stop method (Note 2, 3)	Alarm deactivation		Alarm code		
						Alarm reset	Power cycling	ACD2 (Bit 2)	ACD1 (Bit 1)	ACD0 (Bit 0)
Alarm	10	Undervoltage	10.1	Voltage drop in the power	EDB	○	○	0	1	0
			10.2	Bus voltage drop	SD	○	○			
	12	Memory error 1 (RAM)	12.1	RAM error 1	DB	○	○	0	0	0
			12.2	RAM error 2	DB	○	○			
			12.3	RAM error 3	DB	○	○			
			12.4	RAM error 4	DB	○	○			
			12.5	RAM error 5	DB	○	○			
	13	Clock error	13.1	Clock error 1	DB	○	○	0	0	0
			13.2	Clock error 2	DB	○	○			
	14	Control process error	14.1	Control process error 1	DB	○	○	0	0	0
			14.2	Control process error 2	DB	○	○			
			14.3	Control process error 3	DB	○	○			
			14.4	Control process error 4	DB	○	○			
			14.5	Control process error 5	DB	○	○			
			14.6	Control process error 6	DB	○	○			
			14.7	Control process error 7	DB	○	○			
			14.8	Control process error 8	DB	○	○			
			14.9	Control process error 9	DB	○	○			
	15	Memory error 2 (EEP-ROM)	15.1	EEP-ROM error at power on	DB	○	○	0	0	0
			15.2	EEP-ROM error during operation	DB	○	○			
	16	Encoder initial communication error 1	16.1	Encoder initial communication - Receive data error 1	DB	○	○	1	1	0
			16.2	Encoder initial communication - Receive data error 2	DB	○	○			
			16.3	Encoder initial communication - Receive data error 3	DB	○	○			
			16.5	Encoder initial communication - Transmission data error 1	DB	○	○			
			16.6	Encoder initial communication - Transmission data error 2	DB	○	○			
			16.7	Encoder initial communication - Transmission data error 3	DB	○	○			
			16.A	Encoder initial communication - Process error 1	DB	○	○			
			16.B	Encoder initial communication - Process error 2	DB	○	○			
			16.C	Encoder initial communication - Process error 3	DB	○	○			
			16.D	Encoder initial communication - Process error 4	DB	○	○			
			16.E	Encoder initial communication - Process error 5	DB	○	○			
			16.F	Encoder initial communication - Process error 6	DB	○	○			
			17	Board error	17.1	Board error 1	DB			
17.3	Board error 2	DB			○	○				
17.4	Board error 3	DB			○	○				
17.5	Board error 4	DB			○	○				
17.6	Board error 5	DB			○	○				
19	Memory error 3 (Flash-ROM)	19.1	Flash-ROM error 1	DB	○	○	0	0	0	
		19.2	Flash-ROM error 2	DB	○	○				
1A	Servo motor combination error	1A.1	Servo motor combination error 1	DB	○	○	1	1	0	
1E	Encoder initial communication error 2	1E.1	Encoder malfunction	DB	○	○	1	1	0	
1F	Encoder initial communication error 3	1F.1	Incompatible encoder	DB	○	○	1	1	0	

## 8. TROUBLESHOOTING

	No.	Name	Detail No.	Detail name	Stop method (Note 2, 3)	Alarm deactivation		Alarm code		
						Alarm reset	Power cycling	ACD2 (Bit 2)	ACD1 (Bit 1)	ACD0 (Bit 0)
Alarm	20	Encoder normal communication error 1	20.1	Encoder normal communication - Receive data error 1	EDB	<input type="checkbox"/>	<input type="checkbox"/>	1	1	0
			20.2	Encoder normal communication - Receive data error 2	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			20.3	Encoder normal communication - Receive data error 3	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			20.5	Encoder normal communication - Transmission data error 1	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			20.6	Encoder normal communication - Transmission data error 2	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			20.7	Encoder normal communication - Transmission data error 3	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			20.9	Encoder normal communication - Receive data error 4	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			20.A	Encoder normal communication - Receive data error 5	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
	21	Encoder normal communication error 2	21.1	Encoder data error 1	EDB	<input type="checkbox"/>	<input type="checkbox"/>	1	1	0
			21.2	Encoder data update error	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			21.3	Encoder data waveform error	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			21.5	Encoder hardware error 1	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			21.6	Encoder hardware error 2	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
			21.9	Encoder data error 2	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
	24	Main circuit error	24.1	Ground fault detected at hardware detection circuit	DB	<input type="checkbox"/>	<input type="checkbox"/>	1	0	0
			24.2	Ground fault detected at software detection function	DB	<input type="checkbox"/>	<input type="checkbox"/>			
	25	Absolute position erased	25.1	Servo motor encoder - Absolute position erased	DB	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	30	Regenerative error	30.1	Regeneration heat error	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)	0	0	1
			30.2	Regeneration signal error	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
			30.3	Regeneration feedback signal error	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
	31	Overspeed	31.1	Abnormal motor speed	SD	<input type="checkbox"/>	<input type="checkbox"/>	1	0	1
	32	Overcurrent	32.1	Overcurrent detected at hardware detection circuit (during operation)	DB	<input type="checkbox"/>	<input type="checkbox"/>	1	0	0
			32.2	Overcurrent detected at software detection function (during operation)	DB	<input type="checkbox"/>	<input type="checkbox"/>			
			32.3	Overcurrent detected at hardware detection circuit (during a stop)	DB	<input type="checkbox"/>	<input type="checkbox"/>			
			32.4	Overcurrent detected at software detection function (during a stop)	DB	<input type="checkbox"/>	<input type="checkbox"/>			
	33	Overvoltage	33.1	Main circuit voltage error	EDB	<input type="checkbox"/>	<input type="checkbox"/>	0	0	1
	34	SSCNET receive error 1	34.1	SSCNET receive data error	SD	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
			34.2	SSCNET connector connection error	SD	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
			34.3	SSCNET communication data error	SD	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
			34.4	Hardware error signal detection	SD	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	35	Command frequency error	35.1	Command frequency error	SD	<input type="checkbox"/>	<input type="checkbox"/>	1	0	1
	36	SSCNET receive error 2	36.1	Continuous communication data error	SD	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
	37	Parameter error	37.1	Parameter setting range error	DB	<input type="checkbox"/>	<input type="checkbox"/>	0	0	0
			37.2	Parameter combination error	DB	<input type="checkbox"/>	<input type="checkbox"/>			
			37.3	Point table setting error	DB	<input type="checkbox"/>	<input type="checkbox"/>			
	39	Program error	39.1	Program error	DB	<input type="checkbox"/>	<input type="checkbox"/>	0	0	0
			39.2	Instruction argument external error	DB	<input type="checkbox"/>	<input type="checkbox"/>			
			39.3	Register No. error	DB	<input type="checkbox"/>	<input type="checkbox"/>			
			39.4	Non-correspondence instruction error	DB	<input type="checkbox"/>	<input type="checkbox"/>			

## 8. TROUBLESHOOTING

	No.	Name	Detail No.	Detail name	Stop method (Note 2, 3)	Alarm deactivation		Alarm code		
						Alarm reset	Power cycling	ACD2 (Bit 2)	ACD1 (Bit 1)	ACD0 (Bit 0)
Alarm	3E	Operation mode error	3E.1	Operation mode error	DB	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
			3E.6	Operation mode switch error	DB	<input type="checkbox"/>	<input type="checkbox"/>	0	0	0
	45	Main circuit device overheat	45.1	Main circuit device overheat error 1	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)	0	1	1
	46	Servo motor overheat	46.1	Abnormal temperature of servo motor 1	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)	0	1	1
			46.5	Abnormal temperature of servo motor 3	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
			46.6	Abnormal temperature of servo motor 4	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
	47	Cooling fan error	47.2	Cooling fan speed reduction error	SD	<input type="checkbox"/>	<input type="checkbox"/>	0	1	1
	50	Overload 1	50.1	Thermal overload error 1 during operation	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)	0	1	1
			50.2	Thermal overload error 2 during operation	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
			50.3	Thermal overload error 4 during operation	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
			50.4	Thermal overload error 1 during a stop	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
			50.5	Thermal overload error 2 during a stop	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
			50.6	Thermal overload error 4 during a stop	SD	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
	51	Overload 2	51.1	Thermal overload error 3 during operation	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)	0	1	1
			51.2	Thermal overload error 3 during a stop	DB	<input type="checkbox"/> (Note 1)	<input type="checkbox"/> (Note 1)			
	52	Error excessive	52.1	Excess droop pulse 1	SD	<input type="checkbox"/>	<input type="checkbox"/>	1	0	1
			52.3	Excess droop pulse 2	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			52.4	Error excessive during 0 torque limit	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			52.5	Excess droop pulse 3	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
	54	Oscillation detection	54.1	Oscillation detection error	EDB	<input type="checkbox"/>	<input type="checkbox"/>	0	1	1
	56	Forced stop error	56.2	Over speed during forced stop	EDB	<input type="checkbox"/>	<input type="checkbox"/>	1	1	0
			56.3	Estimated distance over during forced stop	EDB	<input type="checkbox"/>	<input type="checkbox"/>			
	61	Operation error	61.1	Point table setting range error	DB	<input type="checkbox"/>	<input type="checkbox"/>	1	0	1
	8A	USB communication time-out error/serial communication time- out error/Modbus-RTU communication time- out error	8A.1	USB communication time-out error/serial communication time- out error	SD	<input type="checkbox"/>	<input type="checkbox"/>	0	0	0
			8A.2	Modbus-RTU communication time- out error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
	8E	USB communication error/serial communication error/Modbus-RTU communication error	8E.1	USB communication receive error/serial communication receive error	SD	<input type="checkbox"/>	<input type="checkbox"/>	0	0	0
			8E.2	USB communication checksum error/serial communication checksum error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			8E.3	USB communication character error/serial communication character error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			8E.4	USB communication command error/serial communication command error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			8E.5	USB communication data number error/serial communication data number error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			8E.6	Modbus-RTU communication receive error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
			8E.7	Modbus-RTU communication message frame error	SD	<input type="checkbox"/>	<input type="checkbox"/>			
8E.8			Modbus-RTU communication CRC error	SD	<input type="checkbox"/>	<input type="checkbox"/>				
888/ 88888	Watchdog	88_/ 8888_	Watchdog	DB	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	

## 8. TROUBLESHOOTING

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Note 1. Leave for about 30 minutes of cooling time after removing the cause of occurrence.

2. The following shows three stop methods of DB, EDB, and SD.

DB: Dynamic brake stop (For a servo amplifier without the dynamic brake, the servo motor coasts.)

EDB: Electronic dynamic brake stop (available with specified servo motors)

Refer to the following table for the specified servo motors. The stop method for other than the specified servo motors is DB.

Setting [Pr. PF09] to "(\_ \_ \_ 3)" enables the electronic dynamic brake.

Series	Servo motor
HG-KN	HG-KN053/HG-KN13/HG-KN23/HG-KN43
HG-SN	HG-SN52

SD: Forced stop deceleration

3. This is applicable when [Pr. PA04] is set to the initial value. The stop method of SD can be changed to DB using [Pr. PA04].

## 8. TROUBLESHOOTING

### 8.3 Warning list

	No.	Name	Detail No.	Detail name	Stop method (Note 2, 3)
Warning	90	Home position return incomplete warning	90.1	Home position return incomplete	
			90.2	Home position return abnormal termination	
			90.5	Z-phase unpassed	
	91	Servo amplifier overheat warning (Note 1)	91.1	Main circuit device overheat warning	
	92	Battery cable disconnection warning	92.1	Encoder battery cable disconnection warning	
			92.3	Battery degradation	
	96	Home position setting warning	96.1	In-position warning at home positioning	
			96.2	Command input warning at home positioning	
			96.3	Servo off warning at home positioning	
	97	Positioning specification warning	97.1	Program operation disabled warning	
	98	Software limit warning	98.1	Forward rotation-side software stroke limit reached	
			98.2	Reverse rotation-side software stroke limit reached	
	99	Stroke limit warning	99.1	Forward rotation stroke end off	(Note 4)
			99.2	Reverse rotation stroke end off	(Note 4)
	9B	Error excessive warning	9B.1	Excess droop pulse 1 warning	
			9B.3	Excess droop pulse 2 warning	
			9B.4	Error excessive warning during 0 torque limit	
	9F	Battery warning	9F.1	Low battery	
	E0	Excessive regeneration warning	E0.1	Excessive regeneration warning	
	E1	Overload warning 1	E1.1	Thermal overload warning 1 during operation	
			E1.2	Thermal overload warning 2 during operation	
			E1.3	Thermal overload warning 3 during operation	
			E1.4	Thermal overload warning 4 during operation	
			E1.5	Thermal overload warning 1 during a stop	
			E1.6	Thermal overload warning 2 during a stop	
			E1.7	Thermal overload warning 3 during a stop	
E1.8			Thermal overload warning 4 during a stop		
E3	Absolute position counter warning	E3.2	Absolute position counter warning		
		E3.5	Encoder absolute positioning counter warning		
E4	Parameter warning	E4.1	Parameter setting range error warning		
E6	Servo forced stop warning	E6.1	Forced stop warning	SD	
E7	Controller forced stop warning	E7.1	Controller forced stop input warning	SD	
E8	Cooling fan speed reduction warning	E8.1	Decreased cooling fan speed warning		

## 8. TROUBLESHOOTING

	No.	Name	Detail No.	Detail name	Stop method (Note 2, 3)
Warning	E9	Main circuit off warning	E9.1	Servo-on signal on during main circuit off	DB
			E9.2	Bus voltage drop during low speed operation	DB
			E9.3	Ready-on signal on during main circuit off	DB
	EC	Overload warning 2	EC.1	Overload warning 2	
	ED	Output watt excess warning	ED.1	Output watt excess warning	
	F0	Tough drive warning	F0.1	Instantaneous power failure tough drive warning	
			F0.3	Vibration tough drive warning	
	F2	Drive recorder - Miswriting warning	F2.1	Drive recorder - Area writing time-out warning	
			F2.2	Drive recorder - Data miswriting warning	
	F3	Oscillation detection warning	F3.1	Oscillation detection warning	
	F5	Simple cam function - Cam data miswriting warning	F5.1	Cam data - Area writing time-out warning	
			F5.2	Cam data - Area miswriting warning	
			F5.3	Cam data checksum error	
	F6	Simple cam function - Cam control warning	F6.1	Cam axis one cycle current value restoration failed	
			F6.2	Cam axis feed current value restoration failed	
			F6.3	Cam unregistered error	
			F6.4	Cam control data setting range error	
			F6.5	Cam No. external error	
			F6.6	Cam control inactive	

Note 1. Leave for about 30 minutes of cooling time after removing the cause of occurrence.

2. The following shows two stop methods of DB and SD.

DB: Dynamic brake stop (For a servo amplifier without the dynamic brake, the servo motor coasts.)

SD: Forced stop deceleration

3. This is applicable when [Pr. PA04] is set to the initial value. The stop method of SD can be changed to DB using [Pr. PA04].

4. Quick stop or slow stop can be selected using [Pr. PD30].

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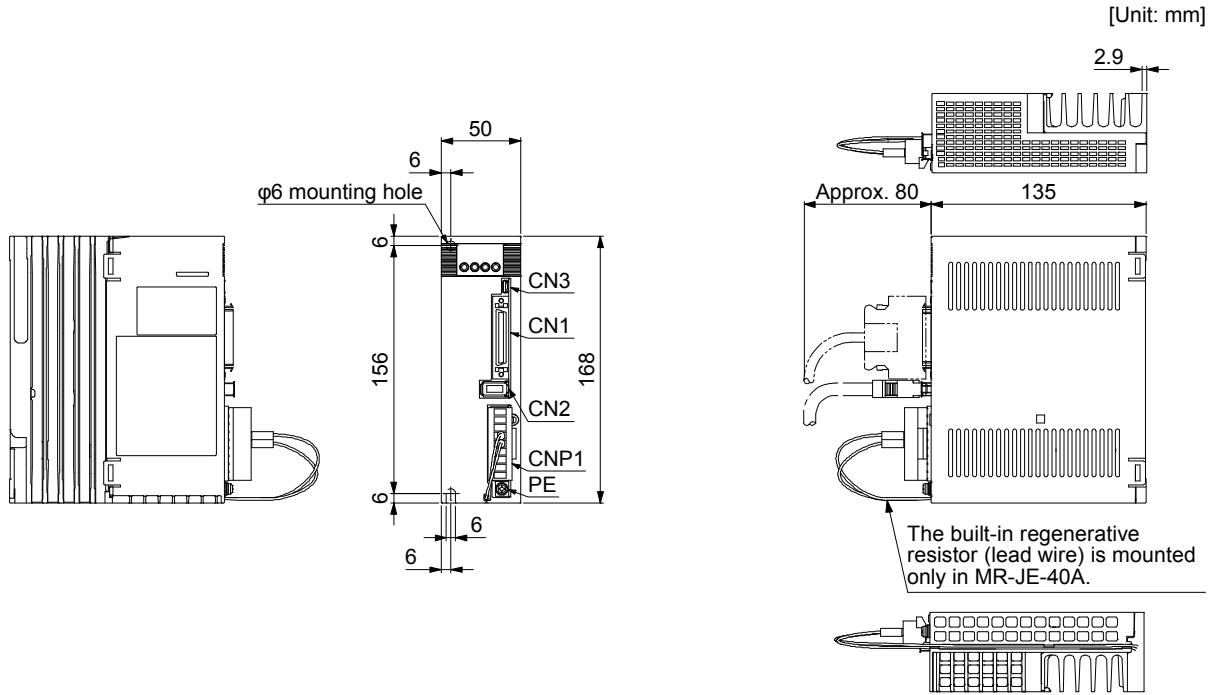
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# 9. DIMENSIONS

## 9. DIMENSIONS

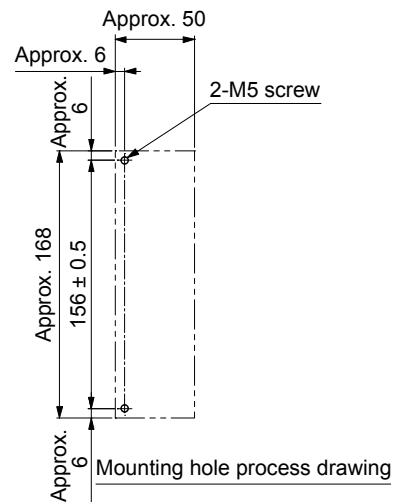
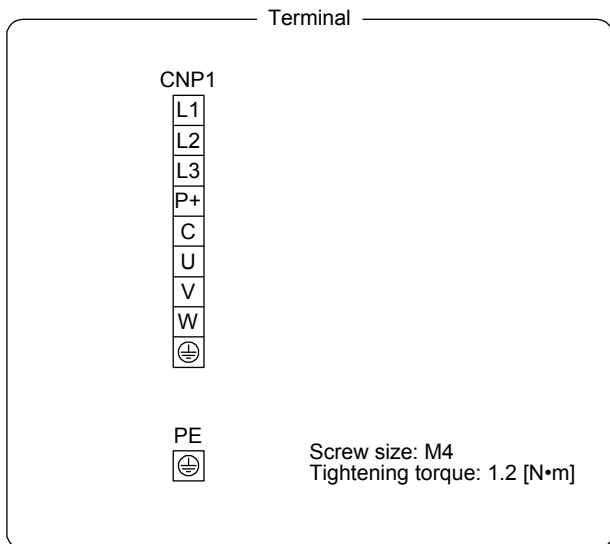
### 9.1 Servo amplifier

#### (1) MR-JE-10A to MR-JE-40A



Mass: 0.8 [kg]

Mounting screw  
Screw size: M5  
Tightening torque: 3.24 [N•m]

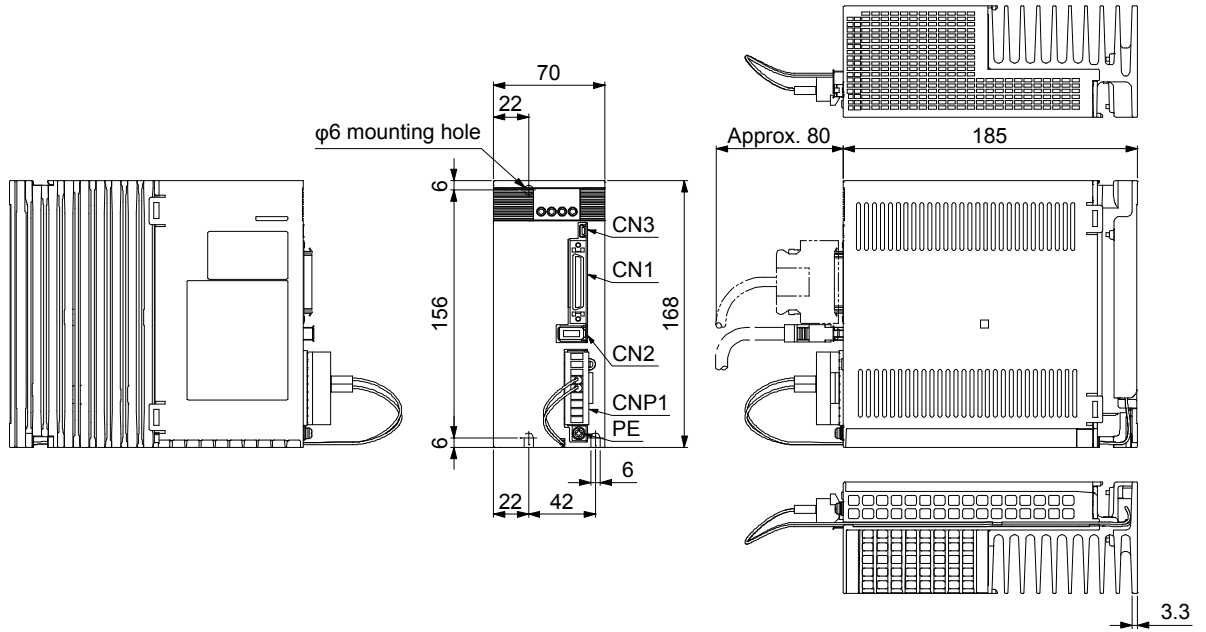




# 9. DIMENSIONS

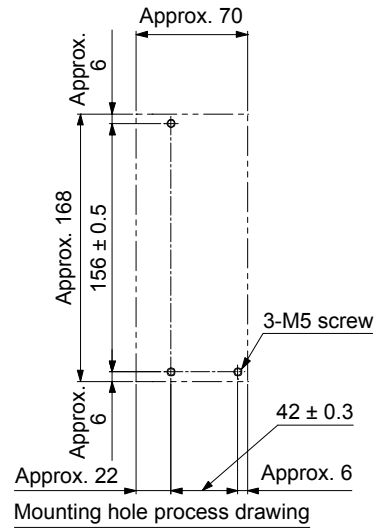
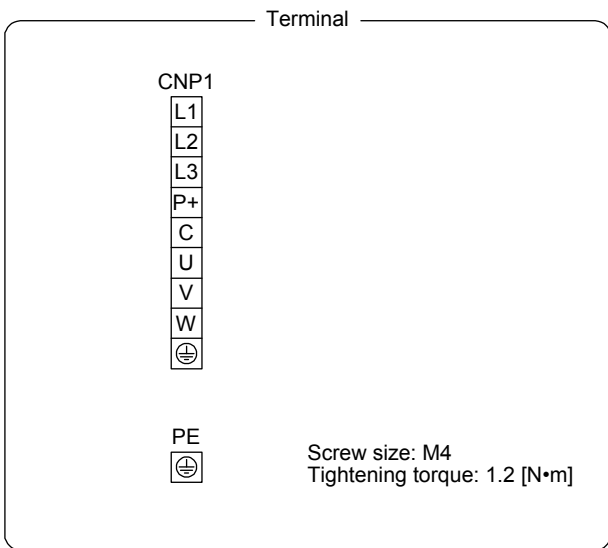
(2) MR-JE-70A/MR-JE-100A

[Unit: mm]



Mass: 1.5 [kg]

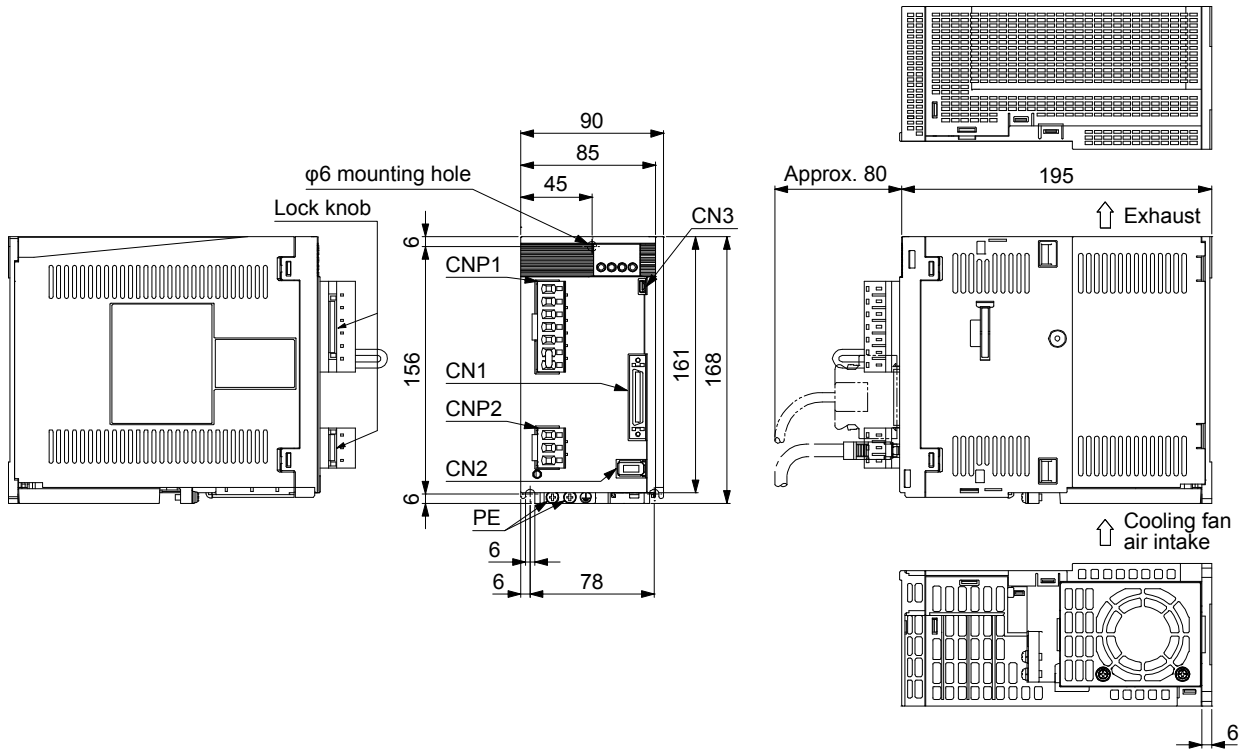
Mounting screw  
Screw size: M5  
Tightening torque: 3.24 [N•m]



# 9. DIMENSIONS

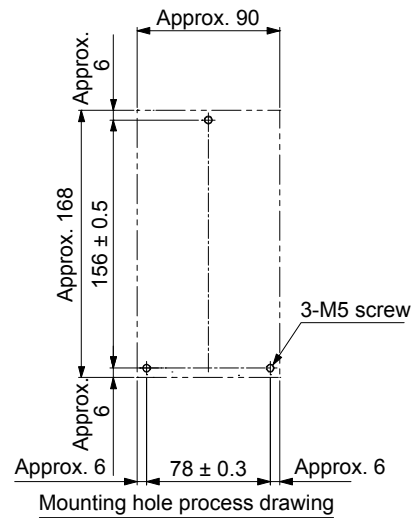
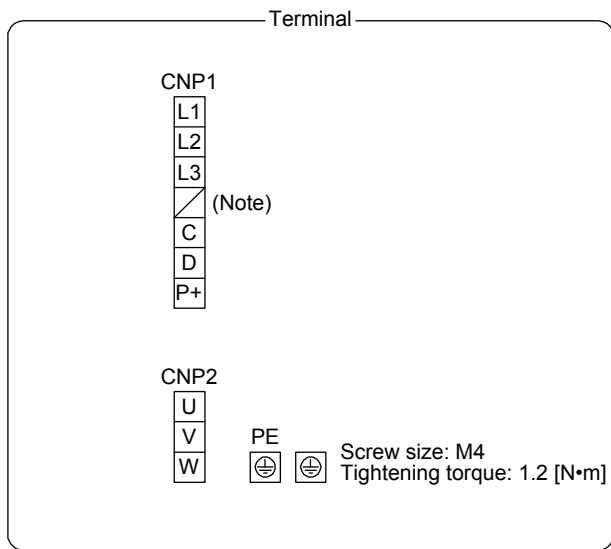
## (3) MR-JE-200A/MR-JE-300A

[Unit: mm]



Mass: 2.1 [kg]

Mounting screw  
Screw size: M5  
Tightening torque: 3.24 [N·m]



Note. The servo amplifiers without the N- terminal will be available sequentially from the December 2016 production.

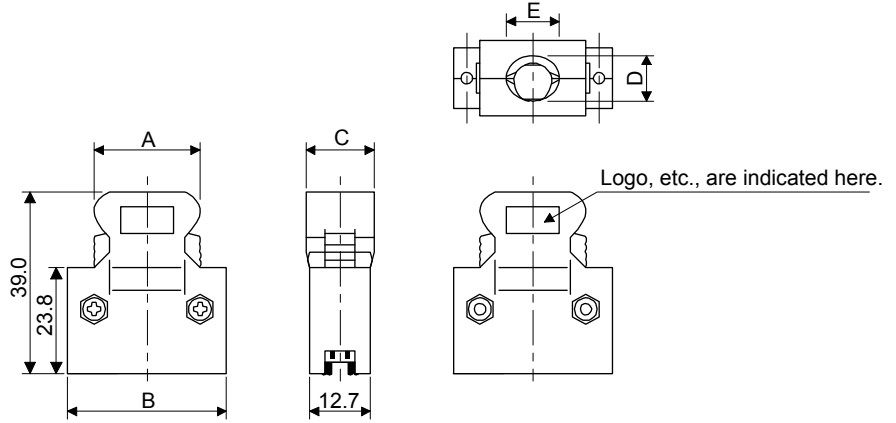
# 9. DIMENSIONS

## 9.2 Connector

### (1) Miniature delta ribbon (MDR) system (3M)

#### (a) One-touch lock type

[Unit: mm]

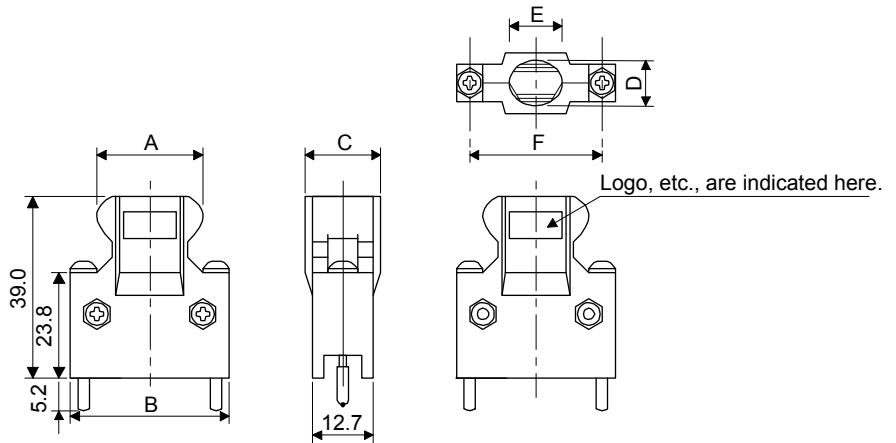


Connector	Shell kit	Variable dimensions				
		A	B	C	D	E
10150-3000PE	10350-52F0-008	41.1	52.4	18.0	14.0	17.0

#### (b) Jack screw M2.6 type

This is not available as option.

[Unit: mm]



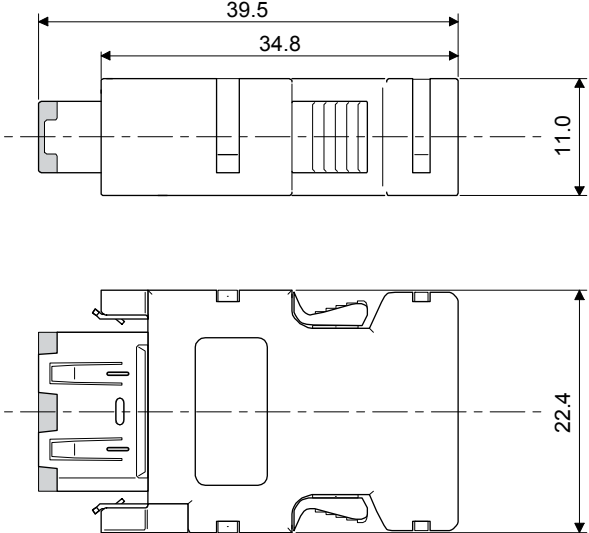
Connector	Shell kit	Variable dimensions					
		A	B	C	D	E	F
10150-3000PE	10350-52A0-008	41.1	52.4	18.0	14.0	17.0	46.5

# 9. DIMENSIONS

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- (2) SCR connector system (3M)  
Receptacle: 36210-0100PL  
Shell kit: 36310-3200-008

[Unit: mm]



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# 10. CHARACTERISTICS

## 10. CHARACTERISTICS

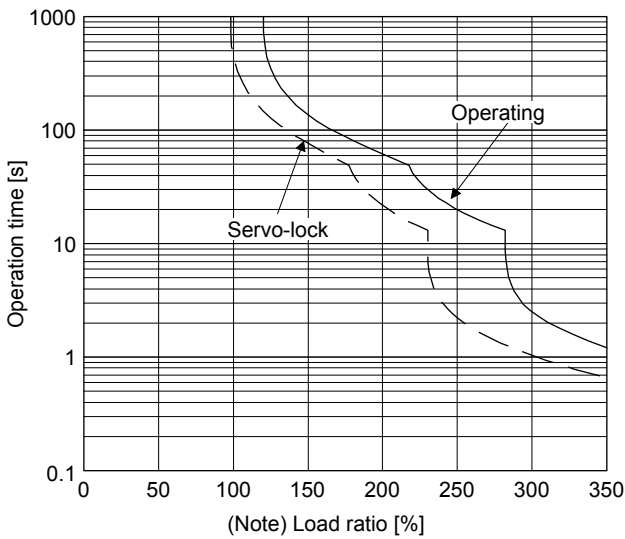
### 10.1 Overload protection characteristics

An electronic thermal is built in the servo amplifier to protect the servo motor, servo amplifier and servo motor power wires from overloads.

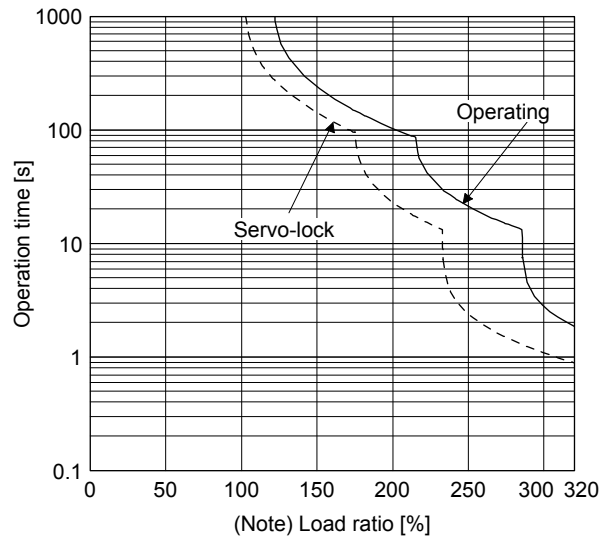
[AL. 50 Overload 1] occurs if overload operation performed is above the electronic thermal protection curve shown in fig. 10.1. [AL. 51 Overload 2] occurs if the maximum current is applied continuously for several seconds due to machine collision, etc. Use the equipment on the left-side area of the continuous or broken line in the graph.

For the system where the unbalanced torque occurs, such as a vertical axis system, the unbalanced torque of the machine should be kept at 70% or lower of the motor's rated torque.

This servo amplifier has servo motor overload protective function. (The servo motor overload current (full load current) is set on the basis of 120% rated current of the servo amplifier.)

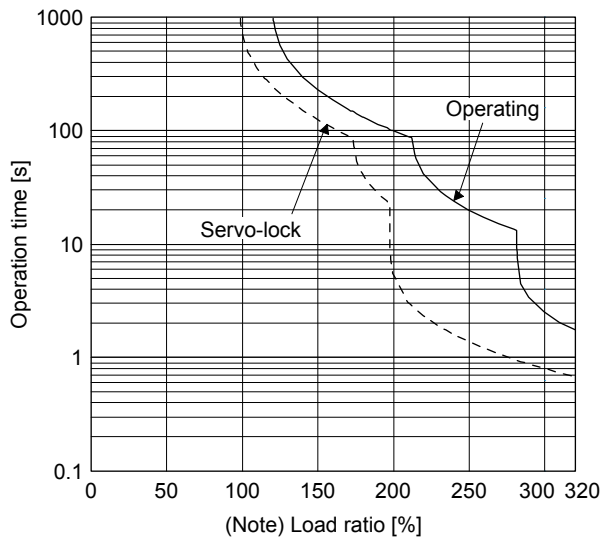


HG-KN13\_



HG-KN23\_, HG-KN43\_, HG-KN73\_  
HG-SN52\_, HG-SN102\_

## 10. CHARACTERISTICS



HG-SN152\_, HG-SN202\_, HG-SN302\_

Note. If operation that generates torque more than 100% of the rating is performed with an abnormally high frequency in a servo motor stop status (servo-lock status) or in a 30 r/min or less low-speed operation status, the servo amplifier may malfunction regardless of the electronic thermal protection.

Fig. 10.1 Electronic thermal protection characteristics

### 10.2 Power supply capacity and generated loss

#### (1) Amount of heat generated by the servo amplifier

Table 10.1 indicates servo amplifiers' power supply capacities and losses generated under rated load. For thermal design of an enclosed type cabinet, use the values in the table in consideration for the worst operating conditions. The actual amount of generated heat will be intermediate between values at rated torque and servo-off according to the duty used during operation. When the servo motor is run at less than the rated speed, the power supply capacity will be smaller than the value in the table, but the servo amplifier's generated heat will not change.

Table 10.1 Power supply capacity and generated loss per servo motor at rated output

Servo amplifier	Servo motor	(Note 1) Power supply capacity [kVA]	(Note 2) Servo amplifier-generated heat [W]		Area required for heat dissipation [m <sup>2</sup> ]
			At rated output	With servo-off	
MR-JE-10A	HG-KN13_	0.3	25	15	0.5
MR-JE-20A	HG-KN23_	0.5	25	15	0.5
MR-JE-40A	HG-KN43_	0.9	35	15	0.7
MR-JE-70A	HG-KN73_	1.3	50	15	1.0
	HG-SN52_	1.0	40	15	0.8
MR-JE-100A	HG-SN102_	1.7	50	15	1.0
MR-JE-200A	HG-SN152_	2.5	90	20	1.8
	HG-SN202_	3.5			
MR-JE-300A	HG-SN302_	4.8	120	20	2.4

Note 1. The power supply equipment capacity changes with the power supply impedance. This value is applicable when the power factor improving AC reactor is not used.

Note 2. Heat generated during regeneration is not included in the servo amplifier-generated heat. To calculate heat generated by the regenerative option, refer to section 11.2.

## 10. CHARACTERISTICS

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(2) Heat dissipation area for an enclosed type cabinet

The enclosed type cabinet (hereafter called the cabinet) which will contain the servo amplifier should be designed to ensure that its temperature rise is within +10 °C at the ambient temperature of 40 °C. Calculate the necessary cabinet dissipation area (allowing a margin of approximately 5 °C for the ambient temperature of 55 °C maximum) with equation (10.1).

$$A = \frac{P}{K \cdot \Delta T} \dots\dots\dots (10.1)$$

- A : Heat dissipation area [m<sup>2</sup>]
- P : Loss generated in the cabinet [W]
- ΔT : Difference between internal and ambient temperatures [°C]
- K : Heat dissipation coefficient [5 to 6]

When calculating the heat dissipation area with equation 10.1, assume that P is the sum of all losses generated in the cabinet. Refer to table 10.1 for heat generated by the servo amplifier. "A" indicates the effective area for heat dissipation, but if the cabinet is directly installed on an insulated wall, that extra amount must be added to the cabinet's surface area. The required heat dissipation area will vary with the conditions in the cabinet. If convection in the cabinet is poor and heat builds up, effective heat dissipation will not be possible. Therefore, arrangement of the equipment in the cabinet and the use of a cooling fan should be considered. Table 10.1 lists the cabinet dissipation area for each servo amplifier (guideline) when the servo amplifier is operated at the ambient temperature of 40 °C under rated load.

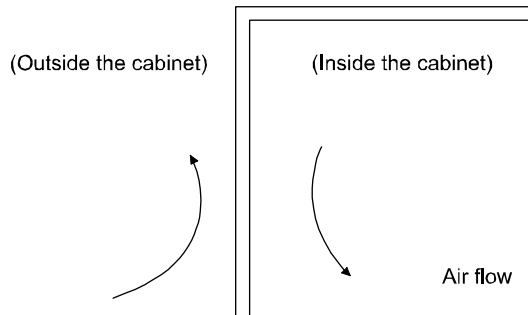


Fig. 10.2 Temperature distribution in an enclosed type cabinet

When air flows along the outer wall of the cabinet, effective heat exchange will be possible, because the temperature slope inside and outside the cabinet will be steeper.



# 10. CHARACTERISTICS

## 10.3 Dynamic brake characteristics

POINT
<ul style="list-style-type: none"> <li>● Do not use dynamic brake to stop in a normal operation as it is the function to stop in emergency.</li> <li>● For a machine operating at the recommended load to motor inertia ratio or less, the estimated number of usage times of the dynamic brake is 1000 times while the machine decelerates from the rated speed to a stop once in 10 minutes.</li> <li>● Be sure to enable EM1 (Forced stop 1) after servo motor stops when using EM1 (Forced stop 1) frequently in other than emergency.</li> <li>● The coasting distance of HG-KN series and HG-SN series servo motors may be different from that of HF-KN series and HF-SN series.</li> </ul>

### 10.3.1 Dynamic brake operation

#### (1) Calculation of coasting distance

Fig. 10.3 shows the pattern in which the servo motor comes to a stop when the dynamic brake is operated. Use equation 10.2 to calculate an approximate coasting distance to a stop. The dynamic brake time constant  $\tau$  varies with the servo motor and machine operation speeds. (Refer to (2) of this section.)

A working part generally has a friction force. Therefore, actual coasting distance will be shorter than a maximum coasting distance calculated with the following equation.

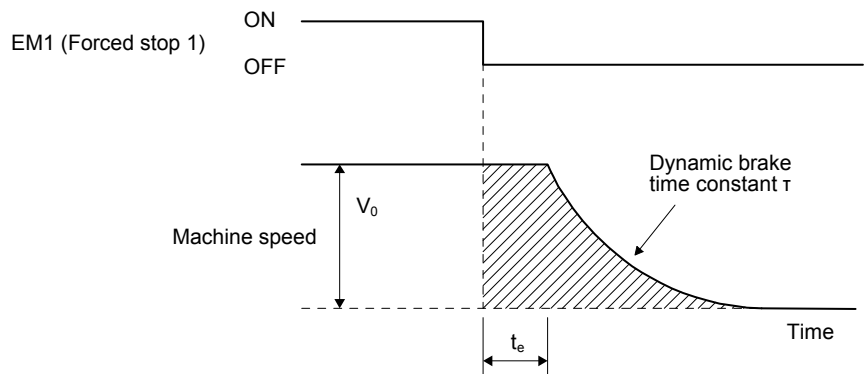


Fig. 10.3 Dynamic brake operation diagram

$$L_{\max} = \frac{V_0}{60} \cdot \left\{ t_e + \tau \left( 1 + \frac{J_L}{J_M} \right) \right\} \dots \dots \dots (10.2)$$

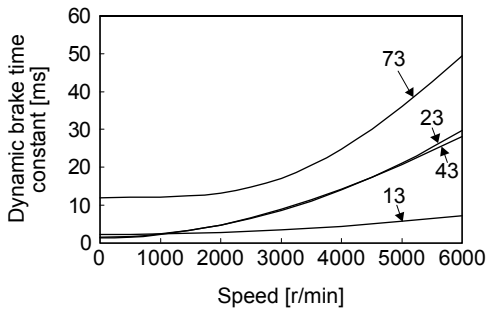
- $L_{\max}$ : Maximum coasting distance ..... [mm]
- $V_0$ : Machine's fast feed speed ..... [mm/min]
- $J_M$ : Moment of inertia of the servo motor ..... [ $\times 10^{-4}$  kg·m<sup>2</sup>]
- $J_L$ : Load moment of inertia converted into equivalent value on servo motor shaft ..... [ $\times 10^{-4}$  kg·m<sup>2</sup>]
- $\tau$ : Dynamic brake time constant ..... [s]
- $t_e$ : Delay time of control section ..... [s]

There is internal relay delay time of about 10 ms.

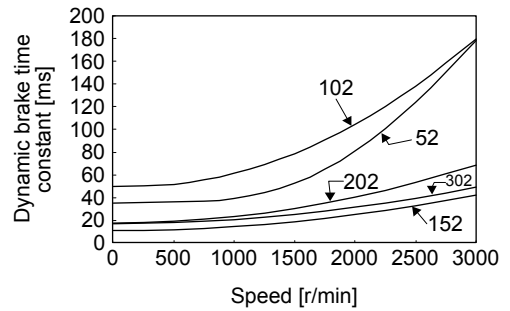
# 10. CHARACTERISTICS

## (2) Dynamic brake time constant

The following shows necessary dynamic brake time constant  $\tau$  for equation 10.2.



HG-KN series



HG-SN series

### 10.3.2 Permissible load to motor inertia when the dynamic brake is used

Use the dynamic brake under the load to motor inertia ratio indicated in the following table. If the ratio is higher than this value, the dynamic brake may burn. If there is a possibility that the ratio may exceed the value, contact your local sales office.

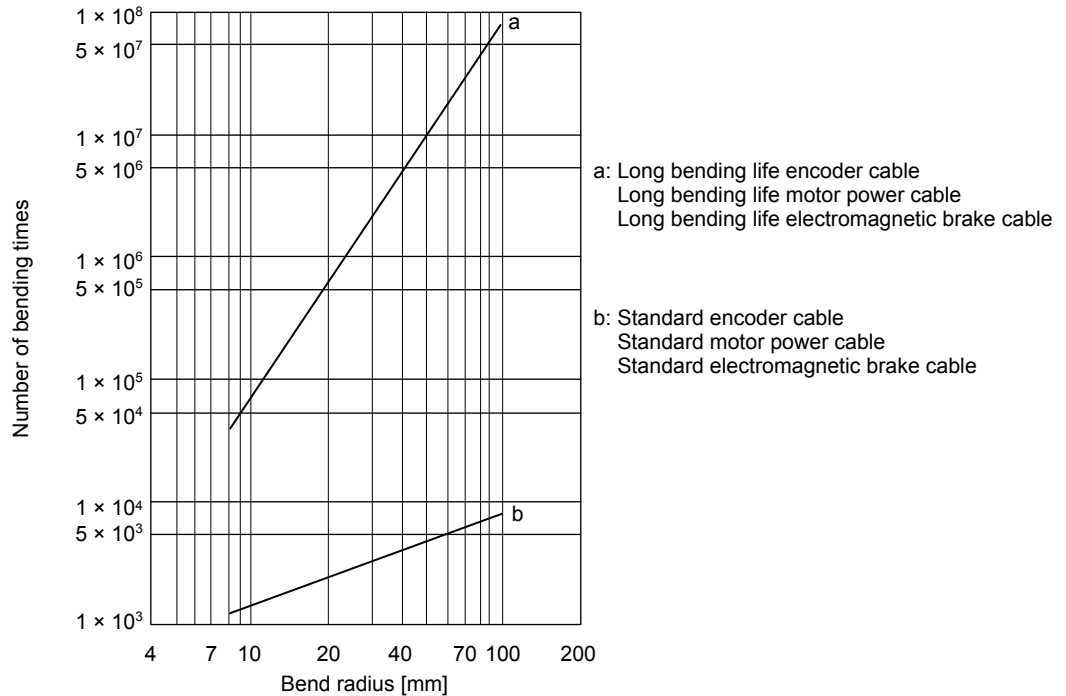
The values of the permissible load to motor inertia ratio in the table are the values at the maximum rotation speed of the servo motor.

Servo motor	Permissible load to motor inertia ratio [multiplier]
HG-KN13_	30
HG-KN23_	
HG-KN43_	
HG-KN73_	
HG-SN52_	
HG-SN102_	
HG-SN152_	24
HG-SN202_	16
HG-SN302_	

# 10. CHARACTERISTICS

## 10.4 Cable bending life

The bending life of the cables is shown below. This graph calculated values. Since they are not guaranteed values, provide a little allowance for these values.



## 10.5 Inrush current at power-on

POINT
<p>● For a servo amplifier of 400 W or less, the inrush current values can change depending on frequency of turning on/off the power and ambient temperature.</p>

The following table indicates the inrush currents (reference data) that will flow when 240 V AC is applied at the power supply capacity of 2500 kVA and the wiring length of 1 m. Even when you use a 1-phase 200 V AC power supply with MR-JE-10A to MR-JE-200A, the inrush currents will be the same.

Servo amplifier	Inrush currents ( $A_{0-P}$ )
MR-JE-10A, MR-JE-20A, MR-JE-40A	32 A (attenuated to approx. 3 A in 20 ms)
MR-JE-70A, MR-JE-100A	36 A (attenuated to approx. 7 A in 20 ms)
MR-JE-200A, MR-JE-300A	102 A (attenuated to approx. 12 A in 20 ms)


Since large inrush currents flow in the power supplies, always use molded-case circuit breakers and magnetic contactors. (Refer to section 11.6.)


When circuit protectors are used, it is recommended that the inertia delay type, which is not tripped by an inrush current, be used.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

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## 11. OPTIONS AND PERIPHERAL EQUIPMENT

 <b>WARNING</b>	● Before connecting options and peripheral equipment, turn off the power and wait for 15 minutes or more until the charge lamp turns off. Otherwise, an electric shock may occur. In addition, when confirming whether the charge lamp is off or not, always confirm it from the front of the servo amplifier.
--	--

 <b>CAUTION</b>	● Use the specified peripheral equipment and options to prevent a malfunction or a fire.
--	--

<b>POINT</b>	● We recommend using HIV wires to wire the servo amplifiers, options, and peripheral equipment. Therefore, the recommended wire sizes may differ from those used for the previous servo amplifiers.
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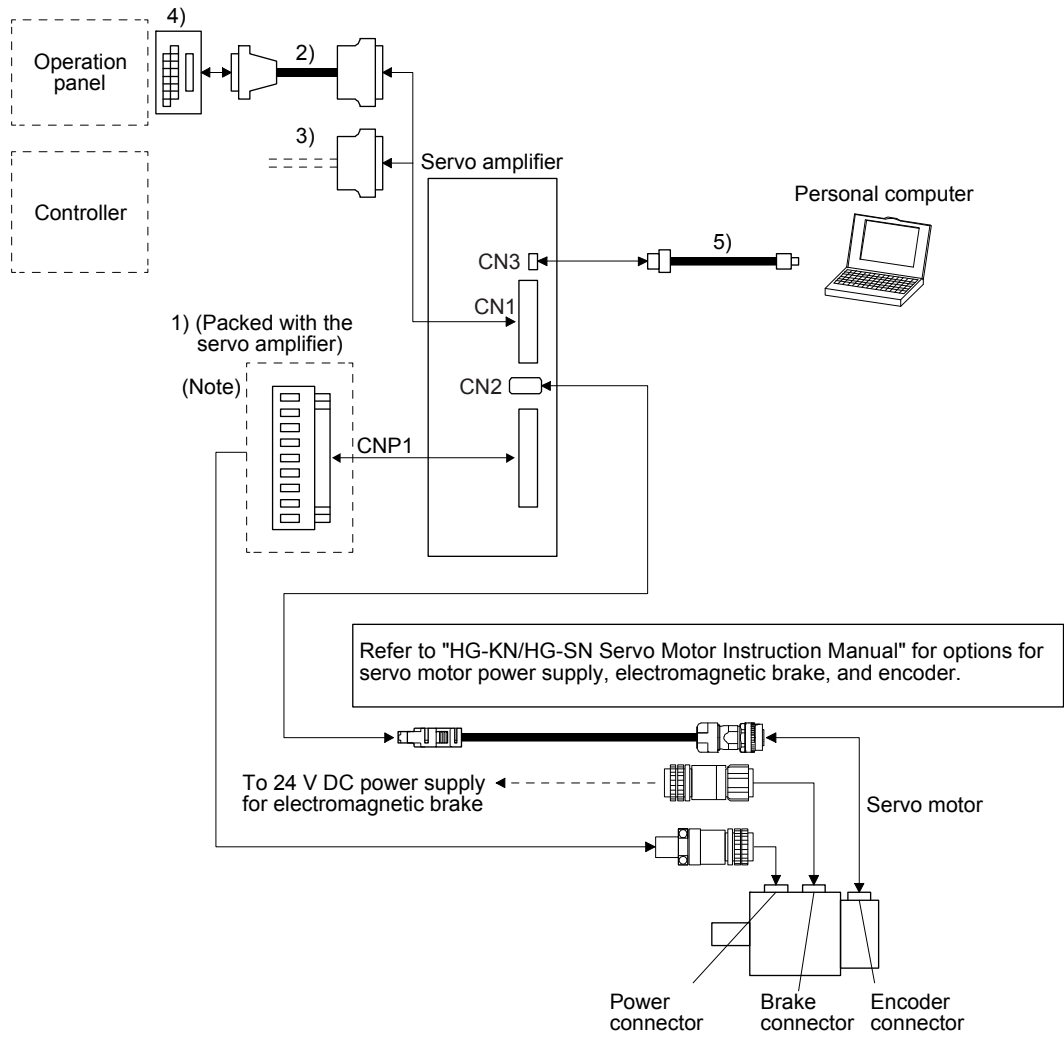
### 11.1 Cable/connector sets

<b>POINT</b>	● The IP rating indicated for cables and connectors is their protection against ingress of dust and raindrops when they are connected to a servo amplifier or servo motor. If the IP rating of the cable, connector, servo amplifier and servo motor vary, the overall IP rating depends on the lowest IP rating of all components.
--------------	---

Please purchase the cable and connector options indicated in this section.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.1.1 Combinations of cable/connector sets




Note. Connectors for 1 kW or less. Refer to section 3.3.3 (1) (b) for 2 kW or more.



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.2 Regenerative option

 <b>CAUTION</b>	● Do not use servo amplifiers with regenerative options other than the combinations specified below. Otherwise, it may cause a fire.
--	--

### 11.2.1 Combination and regenerative power

The power values in the table are resistor-generated powers and not rated powers.

Servo amplifier	Regenerative power [W]					
	Built-in regenerative resistor	MR-RB032 [40 Ω]	MR-RB12 [40 Ω]	MR-RB30 [13 Ω]	MR-RB32 [40 Ω]	(Note) MR-RB50 [13 Ω]
MR-JE-10A		30				
MR-JE-20A		30	100			
MR-JE-40A	10	30	100			
MR-JE-70A	20	30	100		300	
MR-JE-100A	20	30	100		300	
MR-JE-200A	100			300		500
MR-JE-300A	100			300		500

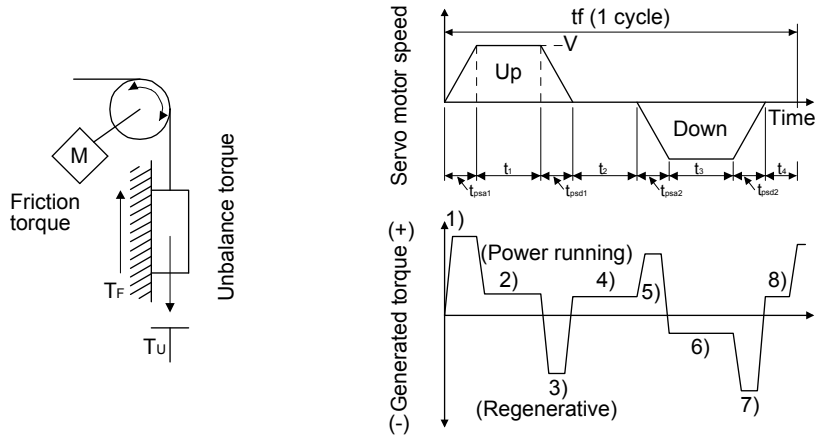
Note. Always install a cooling fan.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.2.2 Selection of regenerative option

Use the following method when regeneration occurs continuously in vertical motion applications or when selecting the regenerative option in details.

### (1) Regenerative energy calculation



Formulas for calculating torque and energy in operation

Regenerative power	Torque applied to servo motor [N•m] (Note)	Energy E [J]
1)	$T_1 = \frac{(J_L/\eta + J_M) \cdot V}{9.55 \cdot 10^4} \cdot \frac{1}{t_{psa1}} + T_U + T_F$	$E_1 = \frac{0.1047}{2} \cdot V \cdot T_1 \cdot t_{psa1}$
2)	$T_2 = T_U + T_F$	$E_2 = 0.1047 \cdot V \cdot T_2 \cdot t_1$
3)	$T_3 = \frac{-(J_L \cdot \eta + J_M) \cdot V}{9.55 \cdot 10^4} \cdot \frac{1}{t_{psd1}} + T_U + T_F$	$E_3 = \frac{0.1047}{2} \cdot V \cdot T_3 \cdot t_{psd1}$
4), 8)	$T_4, T_8 = T_U$	$E_4, E_8 \geq 0$ (No regeneration)
5)	$T_5 = \frac{(J_L/\eta + J_M) \cdot V}{9.55 \cdot 10^4} \cdot \frac{1}{t_{psa2}} - T_U + T_F$	$E_5 = \frac{0.1047}{2} \cdot V \cdot T_5 \cdot t_{psa2}$
6)	$T_6 = -T_U + T_F$	$E_6 = 0.1047 \cdot V \cdot T_6 \cdot t_3$
7)	$T_7 = \frac{-(J_L \cdot \eta + J_M) \cdot V}{9.55 \cdot 10^4} \cdot \frac{1}{t_{psd2}} - T_U + T_F$	$E_7 = \frac{0.1047}{2} \cdot V \cdot T_7 \cdot t_{psd2}$

Note.  $\eta$ : Drive system efficiency

From the calculation results in 1) to 8), find the absolute value (Es) of the sum total of negative energies.



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## (2) Losses of servo motor and servo amplifier in regenerative mode

The following table lists the efficiencies and other data of the servo motor and servo amplifier in the regenerative mode.

Servo amplifier	Inverse efficiency [%]	Capacitor charging [J]
MR-JE-10A	55	11
MR-JE-20A	75	11
MR-JE-40A	85	14
MR-JE-70A	85	25

Servo amplifier	Inverse efficiency [%]	Capacitor charging [J]
MR-JE-100A	85	25
MR-JE-200A	85	42
MR-JE-300A	85	42

Inverse efficiency ( $\eta_m$ ): Efficiency including some efficiencies of the servo motor and servo amplifier when rated (regenerative) torque is generated at rated speed. Since the efficiency varies with the speed and generated torque, allow for about 10%.

Capacitor charging ( $E_c$ ): Energy charged into the electrolytic capacitor in the servo amplifier

Subtract the capacitor charging from the result of multiplying the sum total of regenerative energies by the inverse efficiency to calculate the energy consumed by the regenerative option.

$$ER [J] = \eta_m \cdot E_s - E_c$$

Select a necessary regenerative option by calculating the power consumption of the regenerative option on the basis of one-cycle operation period  $t_f$  [s].

$$PR [W] = ER/t_f$$

### 11.2.3 Parameter setting

Set [Pr. PA02] according to the option to be used.

[Pr. PA02]

0	0		
---	---	--	--

Regenerative option selection

00: Regenerative option is not used.

- For servo amplifier of 200 W or less, regenerative resistor is not used.

- For servo amplifier of 0.4 kW to 3 kW, built-in regenerative resistor is used.

02: MR-RB032

03: MR-RB12

04: MR-RB32

05: MR-RB30

06: MR-RB50 (Cooling fan is required)

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

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## 11.2.4 Selection of regenerative option

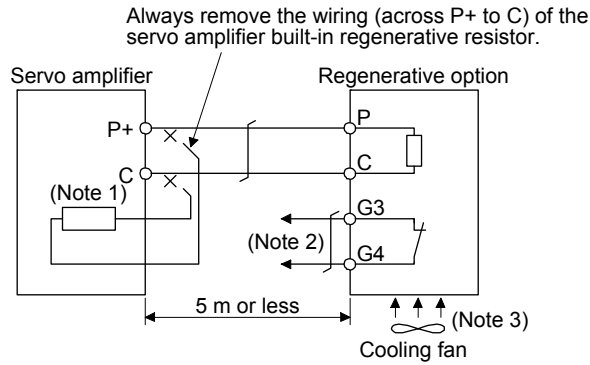
POINT
<ul style="list-style-type: none"><li>● When you use a regenerative option with an MR-JE-40A to MR-JE-100A, remove the built-in regenerative resistor and wiring from the servo amplifier.</li><li>● When MR-RB50 is used, a cooling fan is required to cool it. The cooling fan should be prepared by the customer.</li><li>● For the wire sizes used for wiring, refer to section 11.5.</li><li>● A built-in regenerative resistor should not be mounted/removed frequently.</li><li>● When you remount a built-in regenerative resistor, check the lead wires of the built-in regenerative resistor for scratches or cracks.</li></ul>

The regenerative option generates heat of 100 °C higher than the ambient temperature. Fully consider heat dissipation, installation position, wires used, etc. before installing the option. For wiring, use flame-resistant wires or make the wires flame-resistant and keep them away from the regenerative option. Use twisted wires with a maximum length of 5 m for a connection with the servo amplifier.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## (1) MR-JE-100A or less

When you use a regenerative option for MR-JE-40A to MR-JE-100A, remove wirings of P+ and C, remove the built-in regenerative resistor, and then connect the regenerative option between P+ and C. G3 and G4 are terminals for thermal sensor. Between G3 and G4 is opened when the regenerative option overheats abnormally.



Note 1. The built-in regenerative resistor is not provided for MR-JE-10A and MR-JE-20A.

2. Make up a sequence which will switch off the magnetic contactor when abnormal heating occurs.

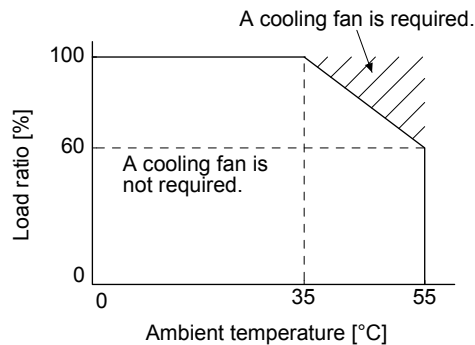
G3-G4 contact specifications

Maximum voltage: 120 V AC/DC

Maximum current: 0.5 A/4.8 V DC

Maximum capacity: 2.4 VA

3. When the ambient temperature is more than 55 °C and the regenerative load ratio is more than 60% in MR-RB32, forcefully cool the air with a cooling fan (1.0 m<sup>3</sup>/min or more, 92 mm × 92 mm). A cooling fan is not required if the ambient temperature is 35 °C or less. (A cooling fan is required for the shaded area in the following graph.)

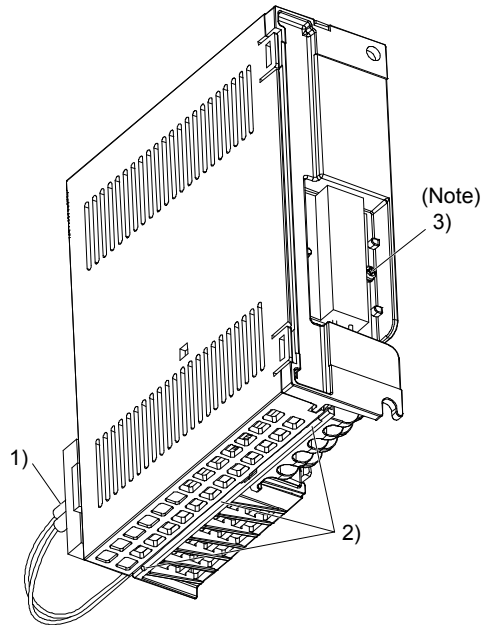


## 11. OPTIONS AND PERIPHERAL EQUIPMENT

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To remove the built-in regenerative resistor mounted on the back of MR-JE-40A to MR-JE-100A, follow the procedures 1) to 3) with referring to the illustration.

- 1) Disconnect the wirings of the built-in regenerative resistor from the power connector (CNP1).  
(Refer to (3) (b) of 3.3.2.)
- 2) Remove the wirings of the built-in regenerative resistor from the closest position to the power connector (CNP1) in order. Please pay full attention not to break the wirings.
- 3) Remove the screw fixing the built-in regenerative resistor and dismount the built-in regenerative resistor.

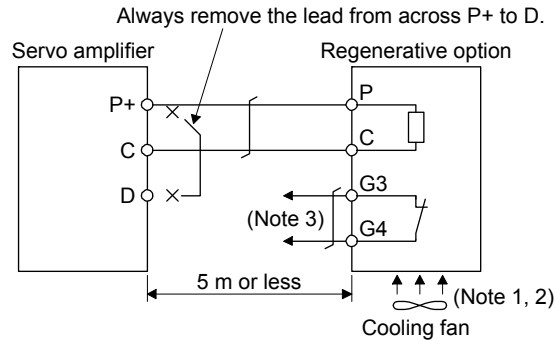


Note. Screw size: M3  
Tightening torque: 0.72 [N•m]

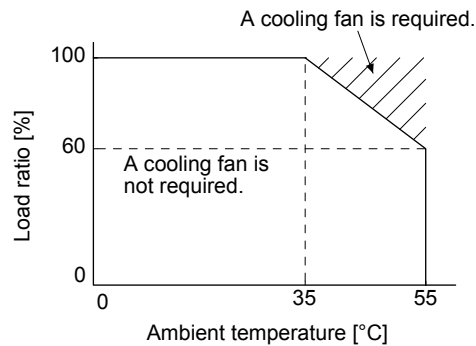
# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## (2) MR-JE-200A or more

Always remove the wiring from across P+ to D and fit the regenerative option across P+ to C. G3 and G4 are terminals for thermal sensor. Between G3 and G4 is opened when the regenerative option overheats abnormally.



- Note 1. When using the MR-RB50, forcibly cool it with a cooling fan (1.0 m<sup>3</sup>/min or more, 92 mm × 92 mm).
2. When the ambient temperature is more than 55 °C and the regenerative load ratio is more than 60% in MR-RB30, forcibly cool the air with a cooling fan (1.0 m<sup>3</sup>/min or more, 92 mm × 92 mm). A cooling fan is not required if the ambient temperature is 35 °C or less. (A cooling fan is required for the shaded area in the following graph.)



3. Make up a sequence which will switch off the magnetic contactor when abnormal heating occurs.

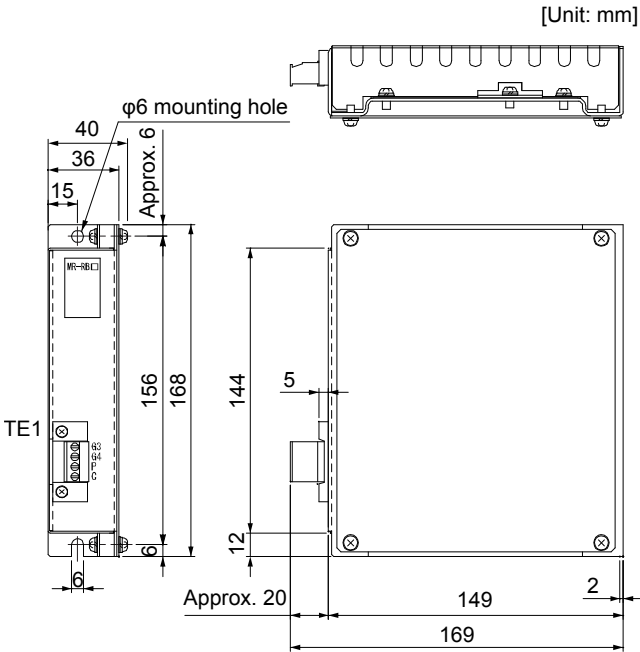
G3-G4 contact specifications

- Maximum voltage: 120 V AC/DC
- Maximum current: 0.5 A/4.8 V DC
- Maximum capacity: 2.4 VA

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.2.5 Dimensions

### (1) MR-RB12



• TE1 terminal

G3
G4
P
C

Applicable wire size: 0.2 mm<sup>2</sup> to 2.5 mm<sup>2</sup> (AWG 24 to 12)

Tightening torque: 0.5 to 0.6 [N•m]

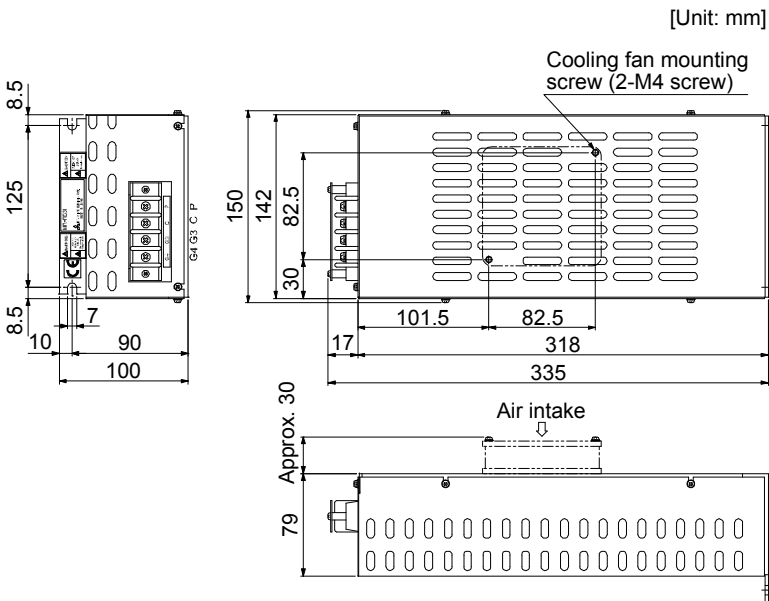
• Mounting screw

Screw size: M5

Tightening torque: 3.24 [N•m]

Mass: 1.1 [kg]

### (2) MR-RB30/MR-RB32



• Terminal

P
C
G3
G4

Terminal screw size: M4

Tightening torque: 1.2 [N•m]

• Mounting screw

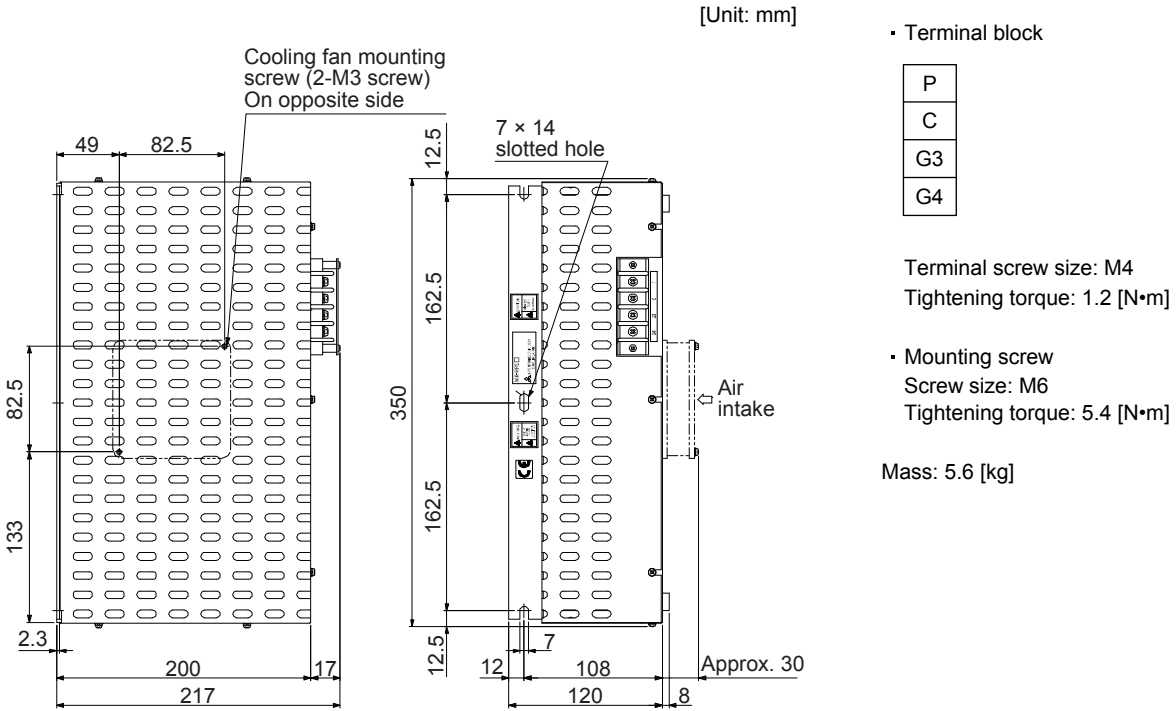
Screw size: M6

Tightening torque: 5.4 [N•m]

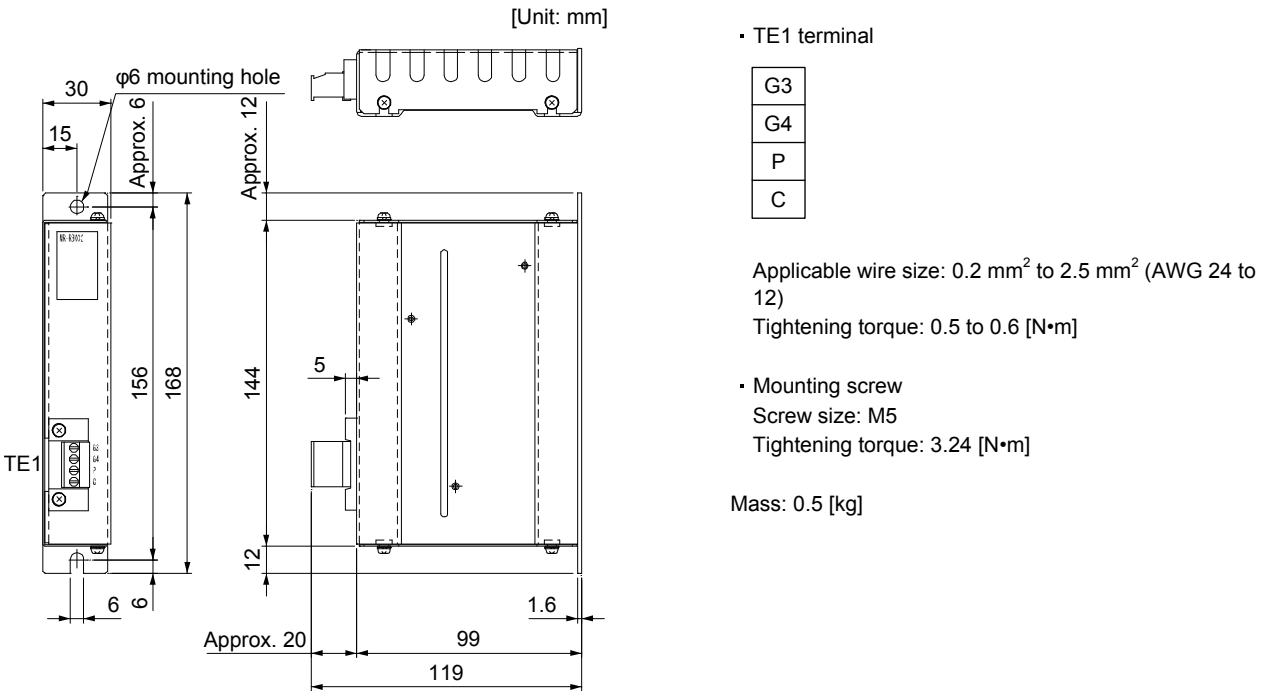
Mass: 2.9 [kg]

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## (3) MR-RB50



## (4) MR-RB032

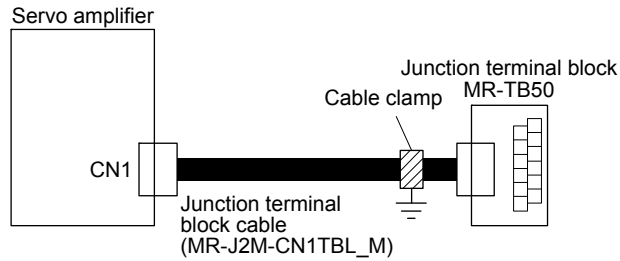


# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.3 Junction terminal block MR-TB50

### (1) Usage

Always use the junction terminal block (MR-TB50) with the option cable (MR-J2M-CN1TBL\_M) as a set.



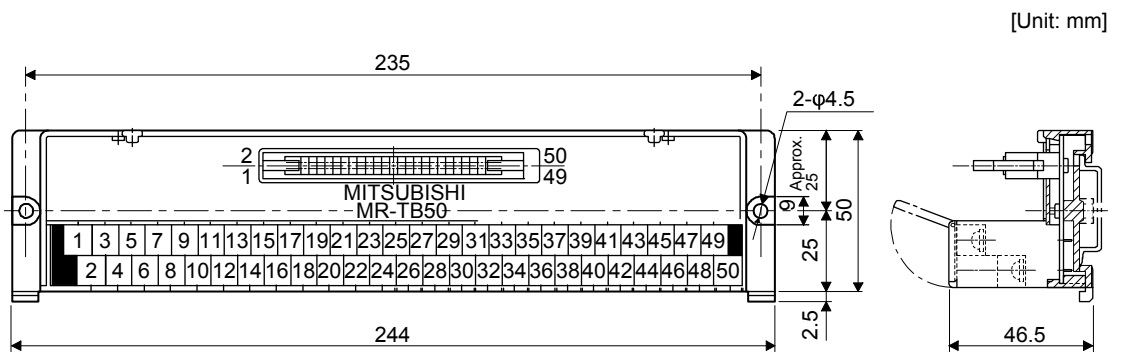
Ground the junction terminal block cable on the junction terminal block side with the supplied cable clamp fitting (AERSBAN-ESET). For the use of the cable clamp fitting, refer to section 11.9, (2) (c).

### (2) Terminal block label

Use the following for the terminal label. For the input/output pin assignment in the control mode, refer to (4) (b) of this section.

1	3	5	7	9	11	13	15	17	19	21	23	25	27	29	31	33	35	37	39	41	43	45	47	49
2	4	6	8	10	12	14	16	18	20	22	24	26	28	30	32	34	36	38	40	42	44	46	48	50

### (3) Dimensions



Terminal screw: M3.5  
 Applicable wire: 2 mm<sup>2</sup>  
 Crimp terminal width: 7.2 mm or shorter



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

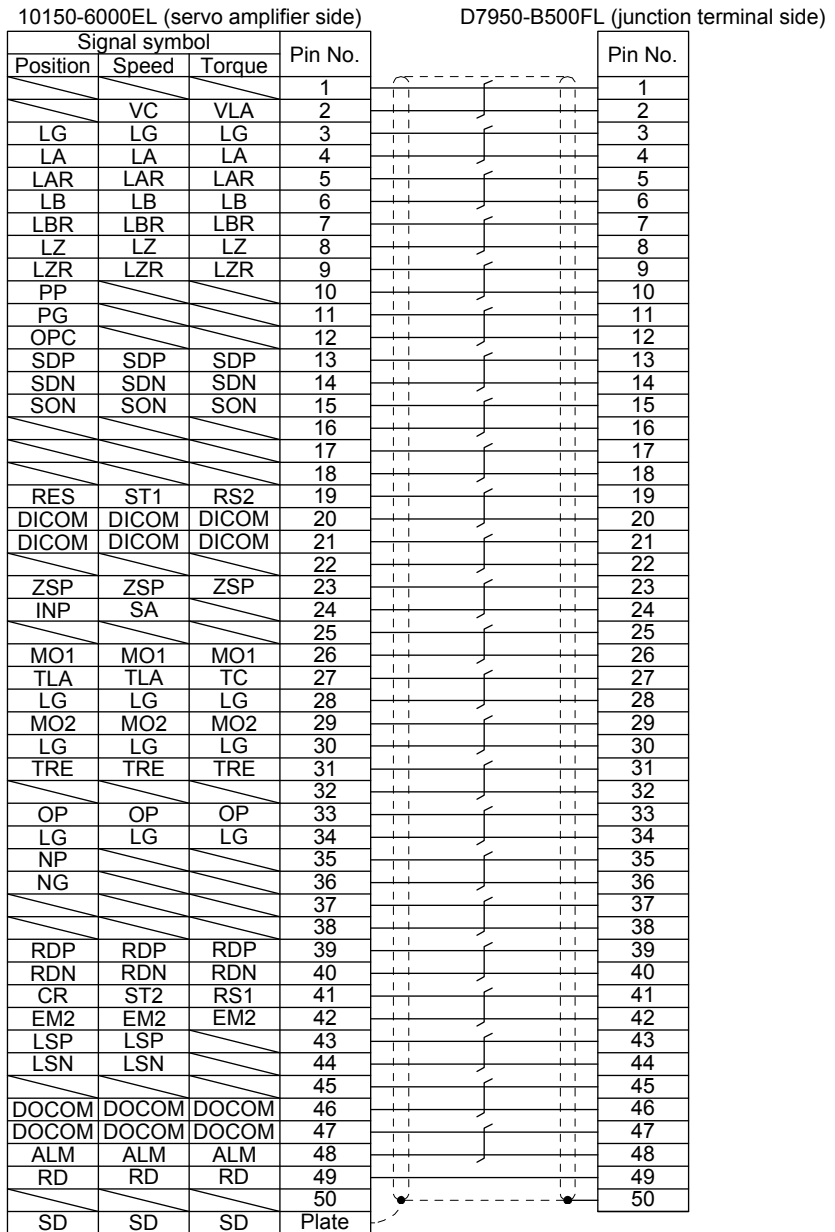
## (4) Junction terminal block cable MR-J2M-CN1TBL\_M

### (a) Model explanations

Model: MR - J 2 M - C N 1 T B L \_ M

Symbol	Cable length [m]
05	0.5
1	1

### (b) Connection diagram



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.4 MR Configurator2

POINT	
	● For the MR-JE servo amplifier, use MR Configurator2 with software version 1.19V or later.

MR Configurator2 (SW1DNC-MRC2-\_) uses the communication function of the servo amplifier to perform parameter setting changes, graph display, test operation, etc. on a personal computer.

### 11.4.1 Specifications

Item	Description
Project	Create/read/save/delete project, system setting, and print
Parameter	Parameter setting, axis name setting
Monitor	Display all, I/O monitor, and graph
Diagnosis	Alarm display, alarm onset data, drive recorder, no motor rotation, system configuration, life diagnosis, machine diagnosis
Test operation	Jog operation, positioning operation, motor-less operation, DO forced output, and program operation, test mode information
Adjustment	One-touch tuning, tuning, and machine analyzer
Others	Servo assistant, parameter setting range update, machine unit conversion setting, and help display

### 11.4.2 System requirements

#### (1) Configuration diagram

To use this software, the following components are required in addition to the servo amplifier and servo motor.

Equipment	Description
(Note 1, 2, 3, 4, 5) Personal computer	OS Microsoft® Windows® 8.1 Enterprise Operating System/Pro Operating System/Operating System Microsoft® Windows® 8 Enterprise Operating System/Pro Operating System/Operating System Microsoft® Windows® 7 Enterprise Operating System/Ultimate Operating System/Professional Operating System/Home Premium Operating System/Starter Operating System Microsoft® Windows Vista® Enterprise Operating System/Ultimate Operating System/Business Operating System/Home Premium Operating System/Home Basic Operating System Microsoft® Windows® XP Professional Operating System, Service Pack3/Home Edition Operating System, Service Pack3
	CPU (recommended) Desktop personal computer: Intel® Celeron® processor 2.8 GHz or more Laptop personal computer: Intel® Pentium® M processor 1.7 GHz or more
	Memory (recommended) 512 MB or more (for 32-bit OS), 1 GB or more (for 64-bit OS)
	Free space on the hard disk: 1 GB or more
	Communication interface USB port
Browser	Windows® Internet Explorer® 4.0 or more
Display	One whose resolution is 1024 × 768 or more and that can provide a high color (16 bit) display. Connectable with the above personal computer.
Keyboard	Connectable with the above personal computer.
Mouse	Connectable with the above personal computer.
Printer	Connectable with the above personal computer.
USB cable	MR-J3USBCBL3M

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

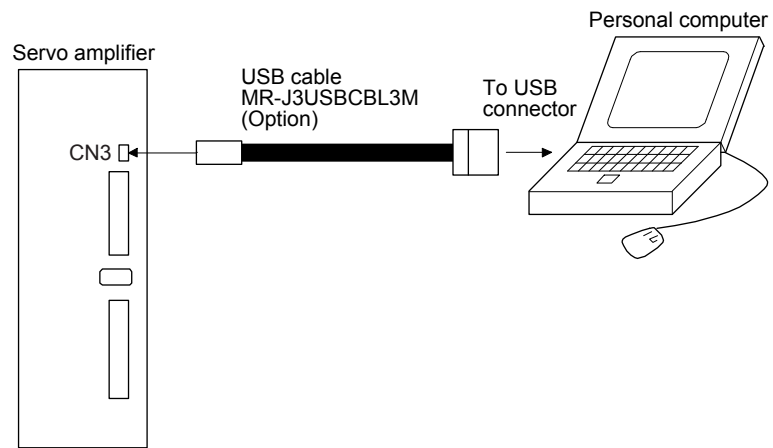
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- Note
1. On some personal computers, MR Configurator2 may not run properly.
  2. When Windows® XP or later is used, the following functions cannot be used.
    - Windows Program Compatibility mode
    - Fast User Switching
    - Remote Desktop
    - Large Fonts Mode (Display property)
    - DPI settings other than 96 DPI (Display property)

For 64-bit operating system, this software is compatible with Windows® 7 and Windows® 8.

3. When Windows® 7 or later is used, the following functions cannot be used.
  - Windows XP Mode
  - Windows touch
4. When using this software with Windows Vista® or later, log in as a user having USER authority or higher.
5. When Windows® 8 or later is used, the following functions cannot be used.
  - Hyper-V
  - Modern UI style

## (2) Connection with servo amplifier



## 11. OPTIONS AND PERIPHERAL EQUIPMENT

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### 11.4.3 Precautions for using USB communication function

Note the following to prevent an electric shock and malfunction of the servo amplifier.

(1) Power connection of personal computers

Connect your personal computer with the following procedures.

(a) When you use a personal computer with AC power supply

- 1) When using a personal computer with a three-core power plug or power plug with grounding wire, use a three-pin socket or ground the grounding wire.
- 2) When your personal computer has two-core plug and has no grounding wire, connect the personal computer to the servo amplifier with the following procedures.
  - a) Disconnect the power plug of the personal computer from an AC power socket.
  - b) Check that the power plug was disconnected and connect the device to the servo amplifier.
  - c) Connect the power plug of the personal computer to the AC power socket.

(b) When you use a personal computer with battery

You can use as it is.

(2) Connection with other devices using servo amplifier communication function

When the servo amplifier is charged with electricity due to connection with a personal computer and the charged servo amplifier is connected with other devices, the servo amplifier or the connected devices may malfunction. Connect the servo amplifier and other devices with the following procedures.

- (a) Shut off the power of the device for connecting with the servo amplifier.
- (b) Shut off the power of the servo amplifier which was connected with the personal computer and check the charge lamp is off.
- (c) Connect the device with the servo amplifier.
- (d) Turn on the power of the servo amplifier and the device.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.5 Selection example of wires

POINT
<ul style="list-style-type: none"> <li>● To comply with the IEC/EN/UL/CSA standard, use the wires shown in app. 2 for wiring. To comply with other standards, use a wire that is complied with each standard.</li> <li>● Selection conditions of wire size are as follows.            Construction condition: Single wire set in midair            Wiring length: 30 m or shorter</li> </ul>

The following diagram shows the wires used for wiring. Use the wires given in this section or equivalent.

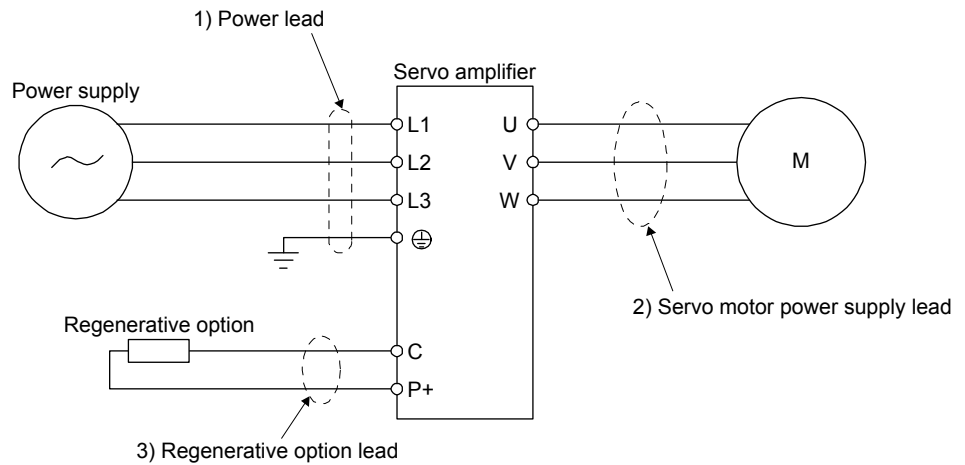


Table 11.1 shows examples for using the 600 V Grade heat-resistant polyvinyl chloride insulated wire (HIV wire).

Table 11.1 Wire size selection example (HIV wire)


Servo amplifier	Wire [mm <sup>2</sup> ]		
	1) L1/L2/L3/⊕	3) P+/C	2) U/V/W/⊕ (Note 1)
MR-JE-10A	2 (AWG 14)	2 (AWG 14)	AWG 18 to 14 (Note 2)
MR-JE-20A			
MR-JE-40A			
MR-JE-70A			
MR-JE-100A			
MR-JE-200A (3-phase power supply input)			3.5 (AWG 12)
MR-JE-200A (1-phase power supply input)			
MR-JE-300A	2 (AWG 14)		

Note 1. The wire size shows applicable size of the servo amplifier connector. For wires connecting to the servo motor, refer to "HG-KN/HG-SN Servo Motor Instruction Manual".

2. Be sure to use the size of 2 mm<sup>2</sup> when corresponding to IEC/EN/UL/CSA standard.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.6 Molded-case circuit breakers, fuses, magnetic contactors


**CAUTION**

- To prevent the servo amplifier from smoke and a fire, select a molded-case circuit breaker which shuts off with high speed.
- Always use one molded-case circuit breaker and one magnetic contactor with one servo amplifier.

When using a fuse instead of the molded-case circuit breaker, use the one having the specifications given in this section.

Servo amplifier	Molded-case circuit breaker (Note 1, 4)		Fuse			Magnetic contactor (Note 2)	
	Frame, rated current		Voltage AC [V]	Class	Current [A]		Voltage AC [V]
	Power factor improving reactor is not used	Power factor improving reactor is used					
MR-JE-10A	30 A frame 5 A	30 A frame 5 A	240	T	300	S-N10 S-T10	
MR-JE-20A							
MR-JE-40A	30 A frame 10 A	30 A frame 5 A					15
MR-JE-70A	30 A frame 15 A	30 A frame 10 A					20
MR-JE-100A (3-phase power supply input)							
MR-JE-100A (1-phase power supply input)	30 A frame 15 A	30 A frame 15 A				30	
MR-JE-200A	30 A frame 20 A	30 A frame 20 A				40	S-N20 (Note 3) S-T21
MR-JE-300A	30 A frame 30 A	30 A frame 30 A	70	S-N20 S-T21			

- Note
1. When having the servo amplifier comply with the IEC/EN/UL/CSA standard, refer to app. 2.
  2. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less.
  3. S-N18 can be used when auxiliary contact is not required.
  4. Use a molded-case circuit breaker which has the same or more operation characteristics than our lineup.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.7 Power factor improving AC reactor

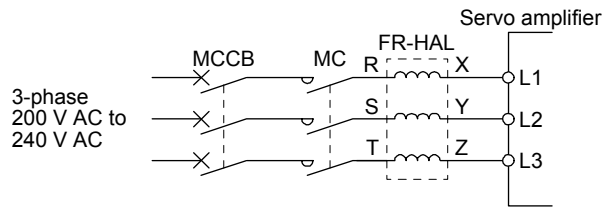
The following shows the advantages of using power factor improving AC reactor.

- It improves the power factor by increasing the form factor of the servo amplifier's input current.
- It decreases the power supply capacity.
- The input power factor is improved to about 80%.

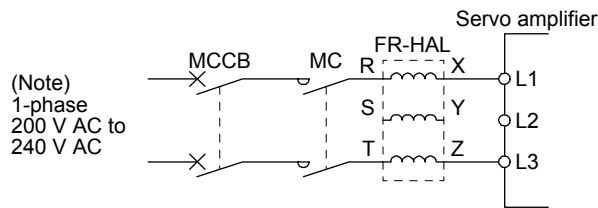
When using power factor improving reactors for two servo amplifiers or more, be sure to connect a power factor improving reactor to each servo amplifier. If using only one power factor improving reactor, enough improvement effect of phase factor cannot be obtained unless all servo amplifiers are operated.

### (1) Connection example

(a) When using 3-phase 200 V AC to 240 V AC power supply

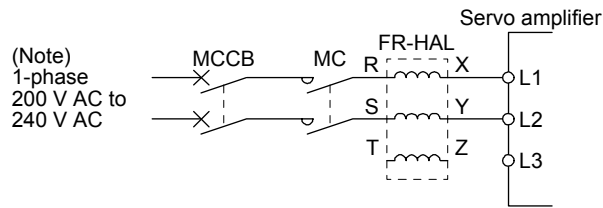


(b) When using 1-phase 200 V AC to 240 V AC power supply for MR-JE-10A to MR-JE-100A



Note. Connect the power supply to L1 and L3. Leave L2 open.

(c) When using 1-phase 200 V AC to 240 V AC power supply for MR-JE-200A



Note. Connect the power supply to L1 and L2. Leave L3 open.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## (2) Dimensions

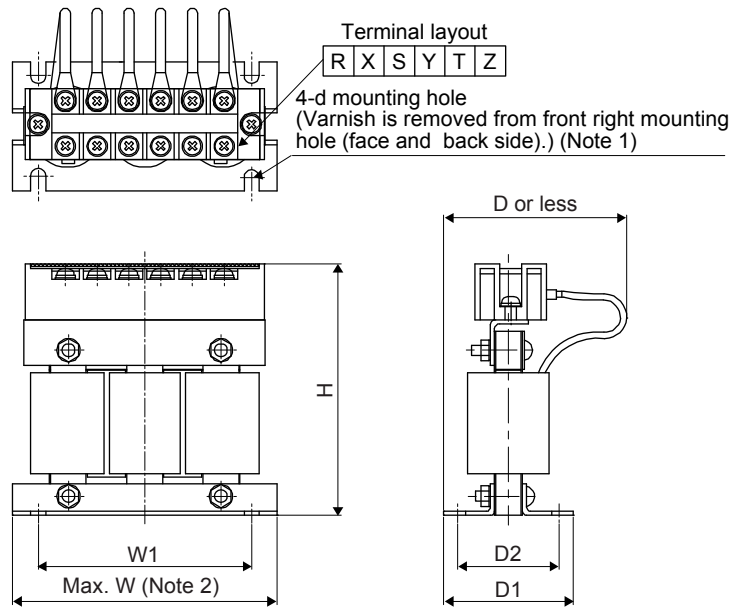


Fig. 11.1

Servo amplifier	Power factor improving AC reactor	Dimensions	Dimensions [mm]							Terminal size	Mass [kg]
			W	W1	H	D (Note 3)	D1	D2	d		
MR-JE-10A, MR-JE-20A	FR-HAL-0.4K	Fig. 11.1	104	84	99	72	51	40	M5	M4	0.6
MR-JE-40A	FR-HAL-0.75K		104	84	99	74	56	44	M5	M4	0.8
MR-JE-70A	FR-HAL-1.5K		104	84	99	77	61	50	M5	M4	1.1
MR-JE-100A (3-phase power supply input)	FR-HAL-2.2K		115 (Note 3)	40	115	77	71	57	M6	M4	1.5
MR-JE-100A (1-phase power supply input) MR-JE-200A (3-phase power supply input)	FR-HAL-3.7K		115 (Note 3)	40	115	83	81	67	M6	M4	2.2
MR-JE-200A (1-phase power supply input) MR-JE-300A	FR-HAL-5.5K		115 (Note 3)	40	115	83	81	67	M6	M4	2.3

Note 1. Use this for grounding.

2.  $W \pm 2$  is applicable for FR-HAL-0.4K to FR-HAL-1.5K.

3. Maximum dimensions. The dimension varies depending on the input/output lines.

## 11.8 Relay (recommended)

The following relays should be used with the interfaces.

Interface	Selection example
Digital input (interface DI-1) Relay used for digital input command signals	To prevent defective contacts, use a relay for small signal (twin contacts). (Ex.) Omron: type G2A, type MY
Digital output (interface DO-1) Relay used for digital output signals	Small relay with 12 V DC or 24 V DC of rated current 40 mA or less (Ex.) Omron: type MY



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.9 Noise reduction techniques

Noises are classified into external noises which enter the servo amplifier to cause it to malfunction and those radiated by the servo amplifier to cause peripheral equipment to malfunction. Since the servo amplifier is an electronic device which handles small signals, the following general noise reduction techniques are required. Also, the servo amplifier can be a source of noise as its outputs are chopped by high carrier frequencies. If peripheral equipment malfunctions due to noises produced by the servo amplifier, take measures to suppress the noises. The measures will vary slightly with the routes of noise transmission.

### (1) Noise reduction techniques

#### (a) General reduction techniques

- Avoid bundling power lines (input/output) and signal cables together or running them in parallel to each other. Separate the power lines from the signal cables.
- Use a shielded twisted pair cable for connection with the encoder and for control signal transmission, and connect the external conductor of the cable to the SD terminal.
- Ground the servo amplifier, servo motor, etc. together at one point. (Refer to section 3.11.)

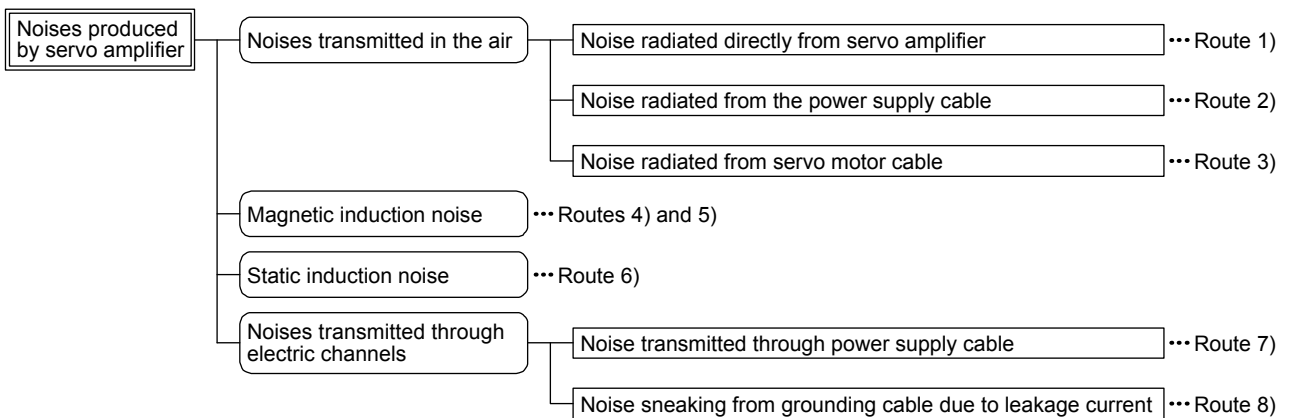
#### (b) Reduction techniques for external noises that cause the servo amplifier to malfunction

If there are noise sources (such as a magnetic contactor, an electromagnetic brake, and many relays which make a large amount of noise) near the servo amplifier and the servo amplifier may malfunction, the following countermeasures are required.

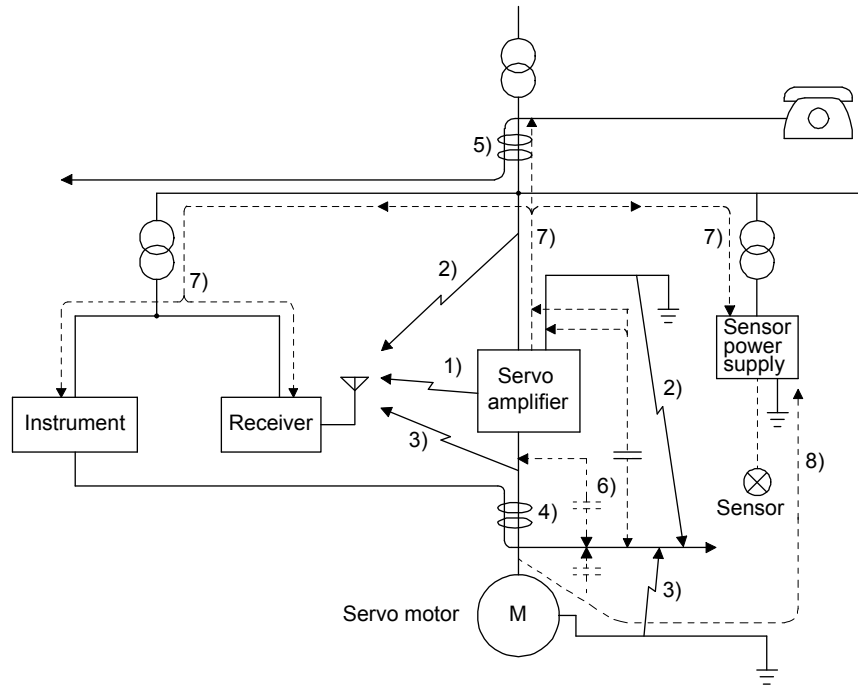
- Provide surge absorbers on the noise sources to suppress noises.
- Attach data line filters to the signal cables.
- Ground the shields of the encoder connecting cable and the control signal cables with cable clamp fittings.
- Although a surge absorber is built into the servo amplifier, to protect the servo amplifier and other equipment against large exogenous noise and lightning surge, attaching a varistor to the power input section of the equipment is recommended.

#### (c) Techniques for noises radiated by the servo amplifier that cause peripheral equipment to malfunction

Noises produced by the servo amplifier are classified into those radiated from the cables connected to the servo amplifier and its main circuits (input and output circuits), those induced electromagnetically or statically by the signal cables of the peripheral equipment located near the main circuit cables, and those transmitted through the power supply cables.



# 11. OPTIONS AND PERIPHERAL EQUIPMENT



Noise transmission route	Suppression techniques
1) 2) 3)	<p>When measuring instruments, receivers, sensors, etc. which handle weak signals and may malfunction due to noise and/or their signal cables are contained in a cabinet together with the servo amplifier or run near the servo amplifier, such devices may malfunction due to noises transmitted through the air. The following techniques are required.</p> <ol style="list-style-type: none"> <li>1. Provide maximum clearance between easily affected devices and the servo amplifier.</li> <li>2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier.</li> <li>3. Avoid wiring the power lines (input/output lines of the servo amplifier) and signal lines side by side or bundling them together.</li> <li>4. Insert a line noise filter to the I/O cables or a radio noise filter on the input line.</li> <li>5. Use shielded wires for the signal and power lines, or put the lines in separate metal conduits.</li> </ol>
4) 5) 6)	<p>When the power lines and the signal lines are laid side by side or bundled together, magnetic induction noise and static induction noise will be transmitted through the signal cables and malfunction may occur. The following techniques are required.</p> <ol style="list-style-type: none"> <li>1. Provide maximum clearance between easily affected devices and the servo amplifier.</li> <li>2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier.</li> <li>3. Avoid wiring the power lines (input/output lines of the servo amplifier) and signal lines side by side or bundling them together.</li> <li>4. Use shielded wires for the signal and power lines, or put the lines in separate metal conduits.</li> </ol>
7)	<p>When the power supply of peripheral equipment is connected to the power supply of the servo amplifier system, noises produced by the servo amplifier may be transmitted back through the power supply cable and the devices may malfunction. The following techniques are required.</p> <ol style="list-style-type: none"> <li>1. Install the radio noise filter (FR-BIF) on the power lines (Input lines) of the servo amplifier.</li> <li>2. Install the line noise filter (FR-BSF01) on the power lines of the servo amplifier.</li> </ol>
8)	<p>If the grounding wires of the peripheral equipment and the servo amplifier make a closed loop circuit, leakage current may flow through, causing the equipment to malfunction. In this case, the malfunction may be prevented by the grounding wires disconnected from the equipment.</p>

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## (2) Noise reduction techniques

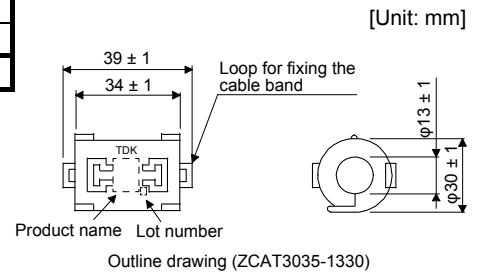
### (a) Data line filter (recommended)

Noise can be prevented by installing a data line filter onto the encoder cable, etc.

For example, ZCAT3035-1330 by TDK, ESD-SR-250 by NEC TOKIN, GRFC-13 by Kitagawa Industries, and E04SRM563218 by SEIWA ELECTRIC are available as data line filters.

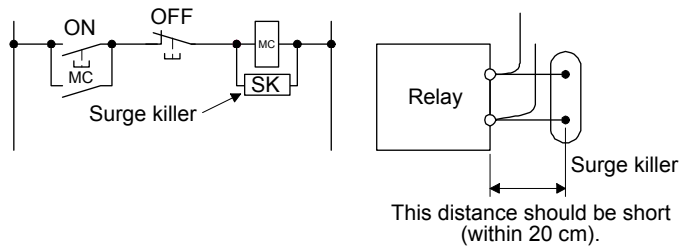
As a reference example, the impedance specifications of the ZCAT3035-1330 (TDK) are indicated below. These impedances are reference values and not guaranteed values.

Impedance [ $\Omega$ ]	
10 MHz to 100 MHz	100 MHz to 500 MHz
80	150



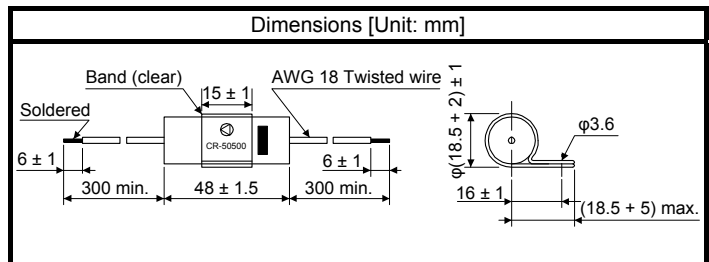
### (b) Surge killer (recommended)

Use of a surge killer is recommended for AC relay, magnetic contactor or the like near the servo amplifier. Use the following surge killer or equivalent.



(Ex.) CR-50500 Okaya Electric Industries)

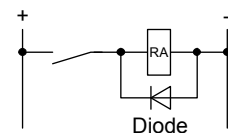
Rated voltage AC [V]	C [ $\mu\text{F} \pm 20\%$ ]	R [ $\Omega \pm 30\%$ ]	Test voltage
250	0.5	50 (1/2 W)	Between terminals: 625 V AC, 50/60 Hz 60 s Between terminal and case: 2000 V AC, 50/60 Hz 60 s



Note that a diode should be installed to a DC relay or the like.

Maximum voltage: not less than four times the drive voltage of the relay or the like

Maximum current: not less than two times the drive current of the relay or the like



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

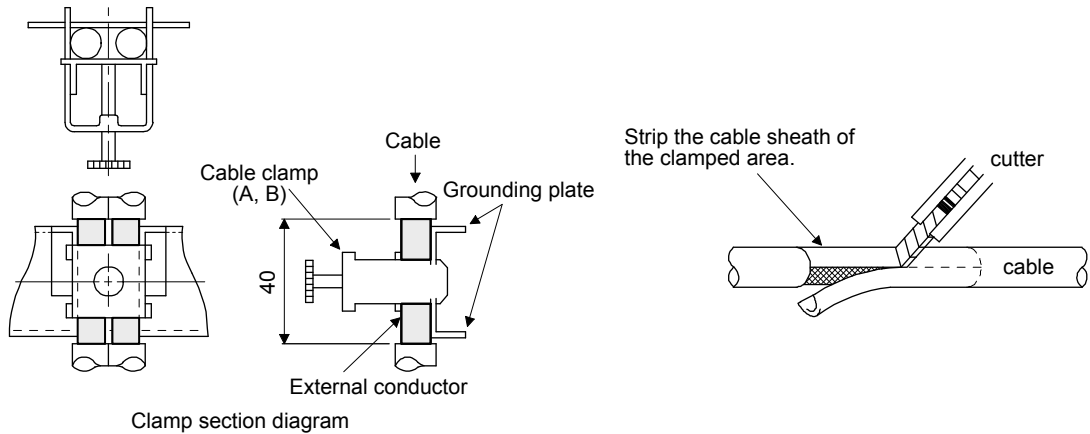
## (c) Cable clamp fitting AERSBAN-\_SET

Generally, connecting the grounding of the shielded wire to the SD terminal of the connector provides a sufficient effect. However, the effect can be increased when the shielded wire is connected directly to the grounding plate as shown below.

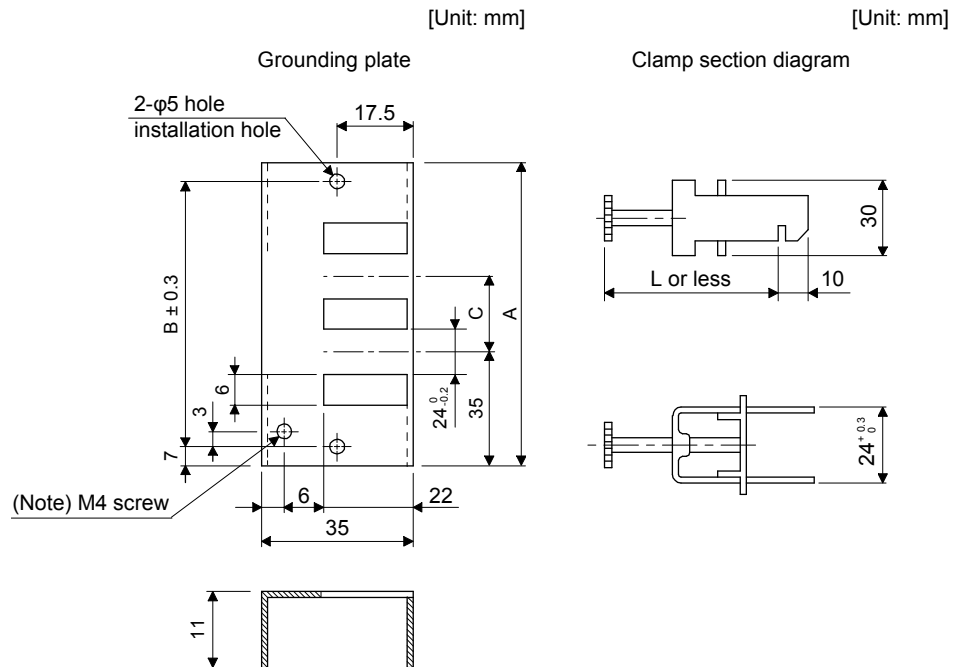
Install the grounding plate near the servo amplifier for the encoder cable. Peel part of the cable sheath to expose the external conductor, and press that part against the grounding plate with the cable clamp. If the cable is thin, clamp several cables in a bunch.

The cable clamp comes as a set with the grounding plate.

[Unit: mm]



### • Dimensions



Note. Screw hole for grounding. Connect it to the grounding plate of the cabinet.

Model	A	B	C	Accessory fittings
AERSBAN-DSET	100	86	30	Clamp A: 2pcs.
AERSBAN-ESET	70	56		Clamp B: 1pc.

Clamp fitting	L
A	70
B	45

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

(d) Line noise filter (FR-BSF01)

This filter is effective in suppressing noises radiated from the power supply side and output side of the servo amplifier and also in suppressing high-frequency leakage current (0-phase current). It especially affects the noises between 0.5 MHz and 5 MHz band.

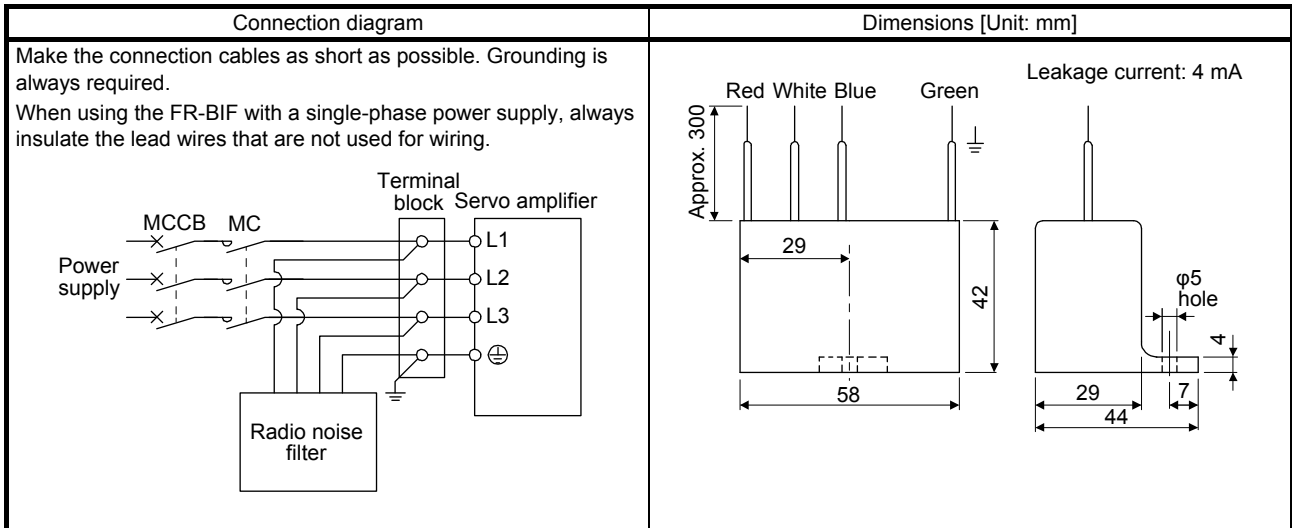
Connection diagram	Dimensions [Unit: mm]
<p>The line noise filters can be installed on lines of the power supply (L1/L2/L3) and of the servo motor power (U/V/W). Pass each of the wires through the line noise filter an equal number of times in the same direction. For wires of the power supply, the effect of the filter rises as the number of passes increases, but generally four passes would be appropriate. For the servo motor power lines, passes must be four times or less. Do not pass the grounding wire through the filter. Otherwise, the effect of the filter will drop.</p> <p>Wind the wires by passing through the filter to satisfy the required number of passes as shown in Example 1. If the wires are too thick to wind, use two or more filters to have the required number of passes as shown in Example 2.</p> <p>Place the line noise filters as close to the servo amplifier as possible for their best performance.</p> <div data-bbox="215 840 718 1321"> <p>Example 1 (Number of passes: 4)</p> <p>Example 2 Two filters are used (Total number of passes: 4)</p> </div>	<p>FR-BSF01 (for wire size 3.5 mm<sup>2</sup> (AWG 12) or less)</p>

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

(e) Radio noise filter (FR-BIF)

This filter is effective in suppressing noises radiated from the power supply side of the servo amplifier especially in 10 MHz and lower radio frequency bands. The FR-BIF is designed for the input only.

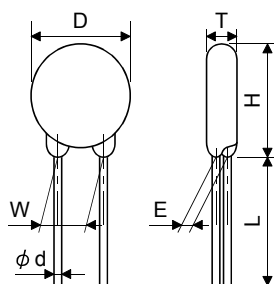
200 V class: FR-BIF



(f) Varistor for input power supply (recommended)

Varistors are effective to prevent exogenous noise and lightning surge from entering the servo amplifier. When using a varistor, connect it between each phase of the input power supply of the equipment. For varistors, the TND20V-431K and TND20V-471K, manufactured by NIPPON CHEMI-CON, are recommended. For detailed specification and usage of the varistors, refer to the manufacturer catalog.

Power supply voltage	Varistor	Maximum rating					Maximum limit voltage		Static capacity (reference value)	Varistor voltage rating (range) V1 mA
		Permissible circuit voltage		Surge current immunity	Energy immunity	Rated pulse power	[A]	[V]		
		AC [Vrms]	DC [V]	8/20 $\mu$ s [A]	2 ms [J]	[W]			[pF]	[V]
200 V class	TND20V-431K	275	350	10000/1 times	195	1.0	100	710	1300	430 (387 to 473)
	TND20V-471K	300	385	7000/2 times	215			775	1200	470 (423 to 517)



[Unit: mm]

Model	D Max.	H Max.	T Max.	E $\pm$ 1.0	(Note) L Min.	$\phi$ d $\pm$ 0.05	W $\pm$ 1.0
TND20V-431K	21.5	24.5	6.4	3.3	20	0.8	10.0
TND20V-471K			6.6	3.5			

Note. For special purpose items for lead length (L), contact the manufacturer.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.10 Earth-leakage current breaker

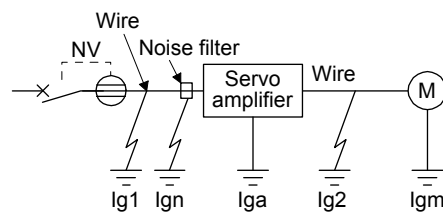
### (1) Selection method

High-frequency chopper currents controlled by pulse width modulation flow in the AC servo circuits. Leakage currents containing harmonic contents are larger than those of the motor which is run with a commercial power supply.

Select an earth-leakage current breaker according to the following formula, and ground the servo amplifier, servo motor, etc. securely.

To minimize leakage currents, make the input and output wires as short as possible, and keep a distance of 30 cm or longer between the wires and ground.

$$\text{Rated sensitivity current} \geq 10 \cdot \{I_{g1} + I_{gn} + I_{ga} + K \cdot (I_{g2} + I_{gm})\} \text{ [mA]} \dots\dots\dots (11.1)$$



Earth-leakage current breaker		K
Type	Mitsubishi products	
Models provided with harmonic and surge reduction techniques	NV-SP NV-SW NV-CP NV-CW NV-HW	1
General models	BV-C1 NFB NV-L	3

I<sub>g1</sub>: Leakage current on the electric channel from the earth-leakage current breaker to the input terminals of the servo amplifier (Found from Fig. 11.2.)

I<sub>g2</sub>: Leakage current on the electric channel from the output terminals of the servo amplifier to the servo motor (found from Fig. 11.2.)

I<sub>gn</sub>: Leakage current when a filter is connected to the input side (4.4 mA per one FR-BIF)

I<sub>ga</sub>: Leakage current of the servo amplifier (Found from table 11.3.)

I<sub>gm</sub>: Leakage current of the servo motor (Found from table 11.2.)

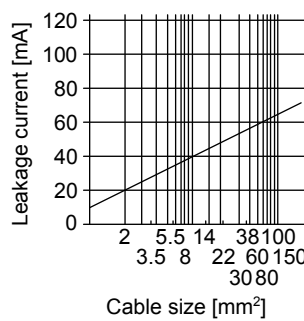


Fig. 11.2 Example of leakage current per km (I<sub>g1</sub>, I<sub>g2</sub>) for CV cable run in metal conduit

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

Table 11.2 Servo motor leakage current example (Igm)

Servo motor power [kW]	Leakage current [mA]
0.1 to 1	0.1
1.5 to 2	0.2
3	0.3

Table 11.3 Servo amplifier leakage current example (Iga)

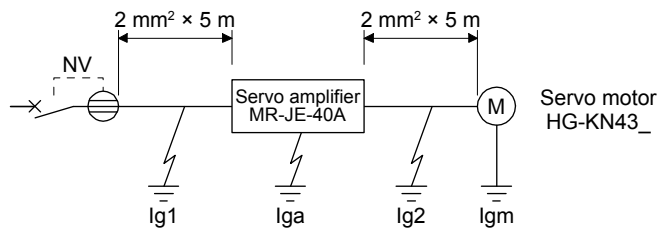
Servo amplifier capacity [kW]	Leakage current [mA]
0.1 to 0.4	0.1
0.75 to 3	0.15

Table 11.4 Earth-leakage current breaker selection example

Servo amplifier capacity [kW]	Rated sensitivity current of earth-leakage current breaker [mA]
MR-JE-10A to MR-JE-300A	15

(2) Selection example

Indicated below is an example of selecting an earth-leakage current breaker under the following conditions.



Use an earth-leakage current breaker designed for suppressing harmonics/surges. Find the terms of equation (11.1) from the diagram.

$$I_{g1} = 20 \cdot \frac{5}{1000} = 0.1 \text{ [mA]}$$

$$I_{g2} = 20 \cdot \frac{5}{1000} = 0.1 \text{ [mA]}$$

$$I_{gn} = 0 \text{ (not used)}$$

$$I_{ga} = 0.1 \text{ [mA]}$$

$$I_{gm} = 0.1 \text{ [mA]}$$

Insert these values in equation (11.1).

$$I_g \geq 10 \cdot \{0.1 + 0 + 0.1 + 1 \cdot (0.1 + 0.1)\} \\ \geq 4 \text{ [mA]}$$

According to the result of calculation, use an earth-leakage current breaker having the rated sensitivity current (I<sub>g</sub>) of 4.0 mA or more.

Use an earth-leakage current breaker having I<sub>g</sub> of 15 mA with the NV-SP/SW/CP/CW/HW series.



# 11. OPTIONS AND PERIPHERAL EQUIPMENT

## 11.11 EMC filter (recommended)

POINT
<p>● For when multiple servo amplifiers are connected to one EMC filter, refer to section 6.4 of "EMC Installation Guidelines".</p>

It is recommended that one of the following filters be used to comply with EN EMC directive. Some EMC filters have large in leakage current.

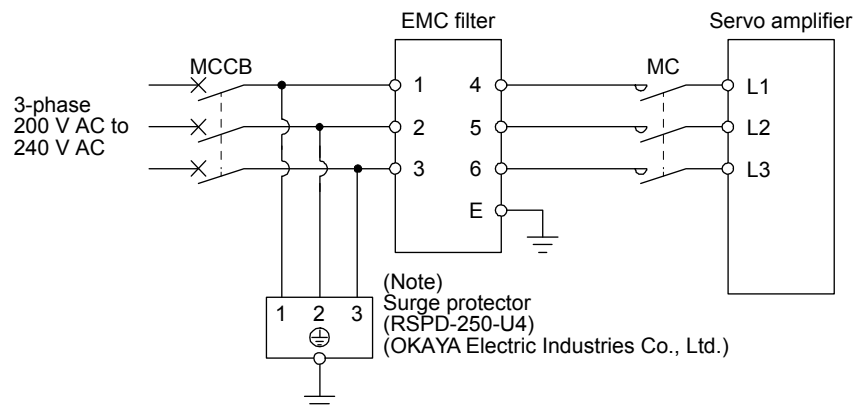
### (1) Combination with the servo amplifier

Servo amplifier	Recommended filter (Soshin Electric)				Mass [kg]
	Model	Rated current [A]	Rated voltage [V AC]	Leakage current [mA]	
MR-JE-10A to MR-JE-100A	HF3010A-UN (Note)	10	250	5	3.5
MR-JE-200A, MR-JE-300A	HF3030A-UN (Note)	30			5.5

Note. A surge protector is separately required to use any of these EMC filters.

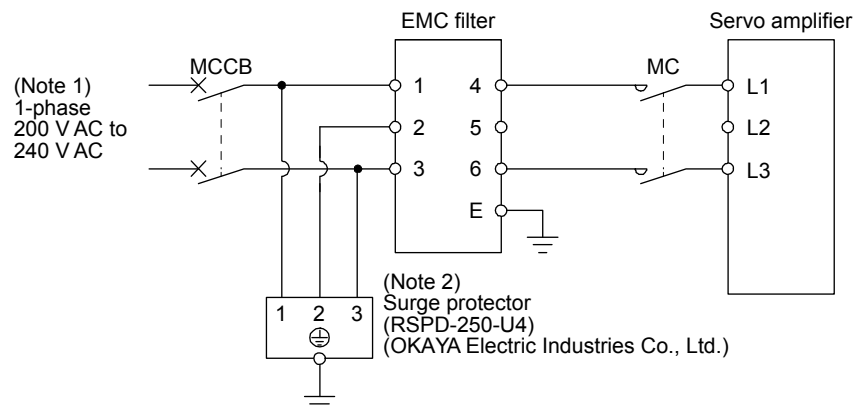
### (2) Connection example

#### (a) When using 3-phase 200 V AC to 240 V AC power supply



Note. The example is when a surge protector is connected.

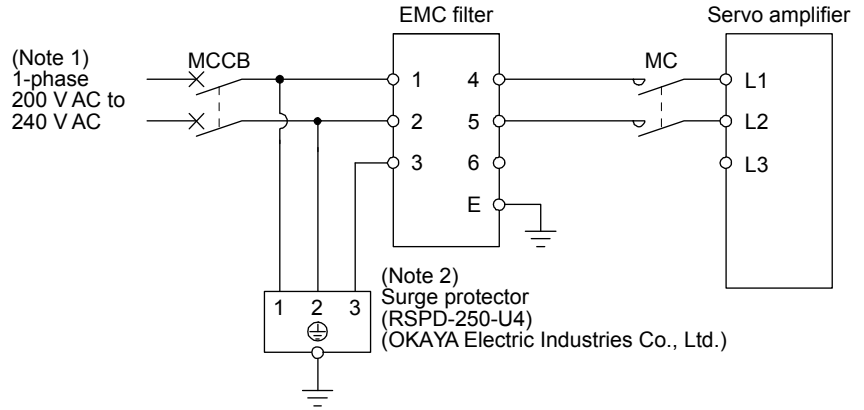
#### (b) When using 1-phase 200 V AC to 240 V AC power supply for MR-JE-10A to MR-JE-100A



Note 1. Connect the power supply to L1 and L3. Leave L2 open.  
Note 2. The example is when a surge protector is connected.

# 11. OPTIONS AND PERIPHERAL EQUIPMENT

(c) When using 1-phase 200 V AC to 240 V AC power supply for MR-JE-200A

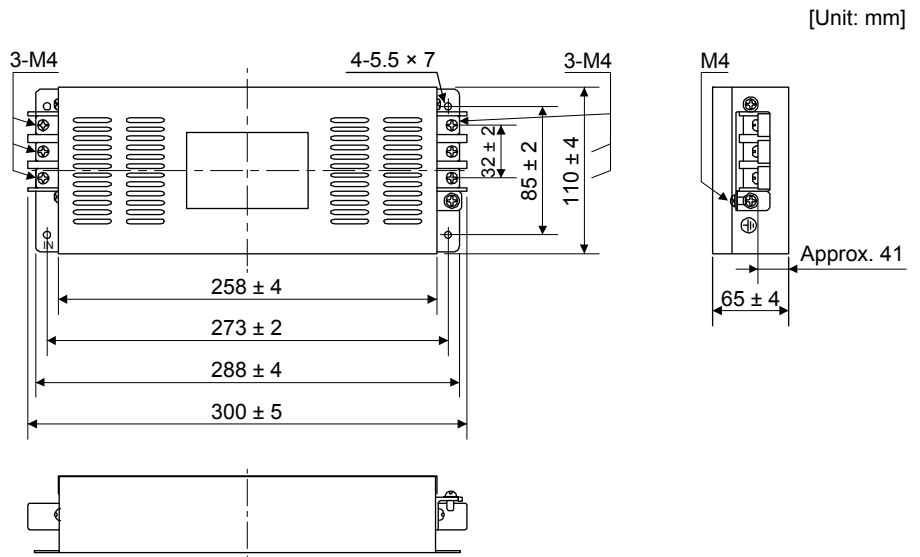


- Note 1. Connect the power supply to L1 and L2. Leave L3 open.  
 Note 2. The example is when a surge protector is connected.

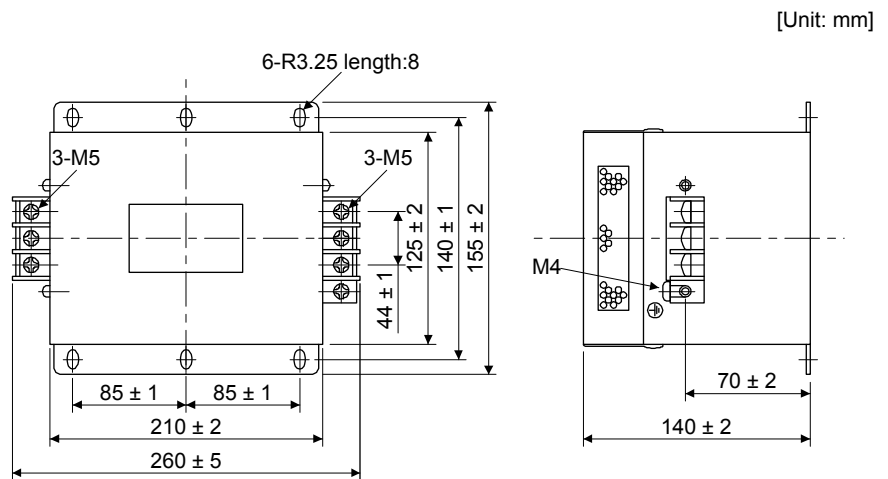
## (3) Dimensions

(a) EMC filter

HF3010A-UN



HF3030A-UN

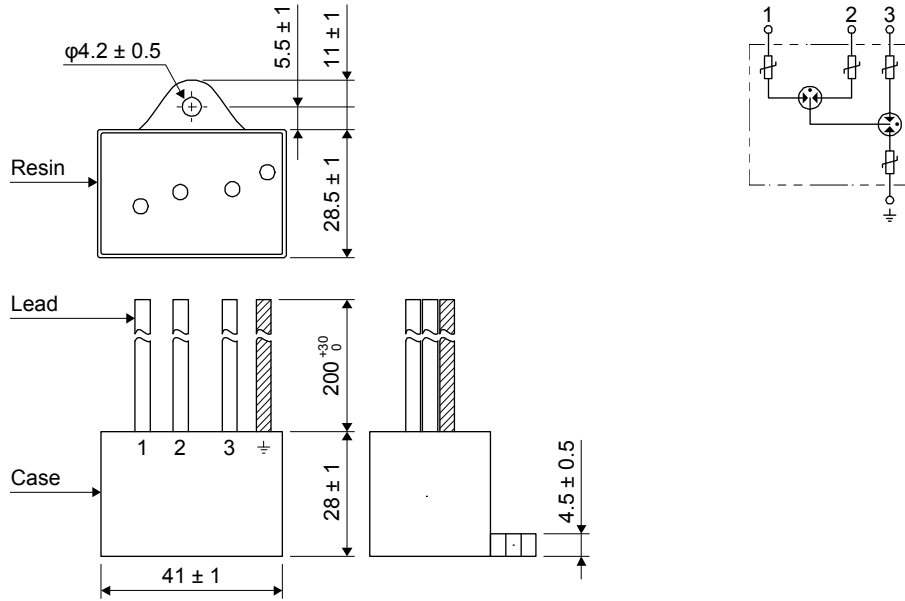


# 11. OPTIONS AND PERIPHERAL EQUIPMENT

(b) Surge protector

RSPD-250-U4

[Unit: mm]



12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

POINT
<ul style="list-style-type: none"> <li>● The RS-422 serial communication function is supported by servo amplifier manufactured in December 2013 or later. Refer to section 1.6 (1) for the year and month of manufacture.</li> <li>● The USB communication function and RS-422 communication function are mutually exclusive. They cannot be used together.</li> </ul>

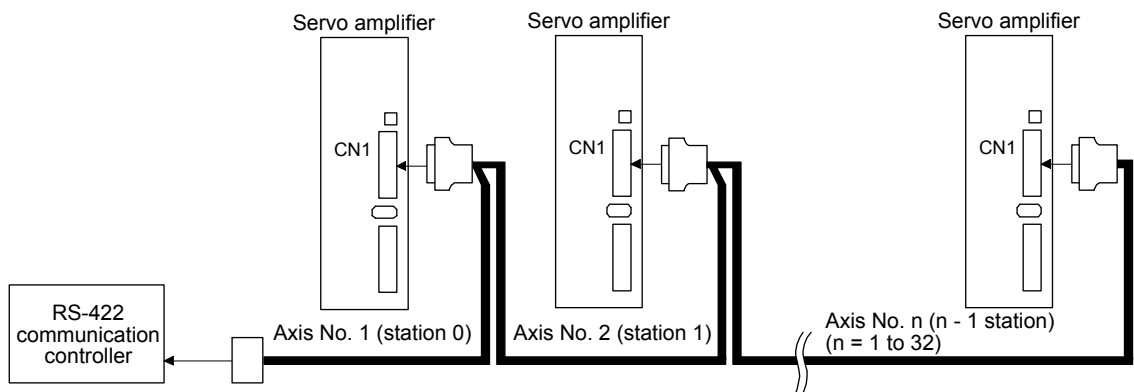
You can operate servo driving, parameter change, monitor function, etc. using Mitsubishi general-purpose AC servo protocol (RS-422 communication) with the servo amplifier.

12.1 Structure

12.1.1 Configuration diagram

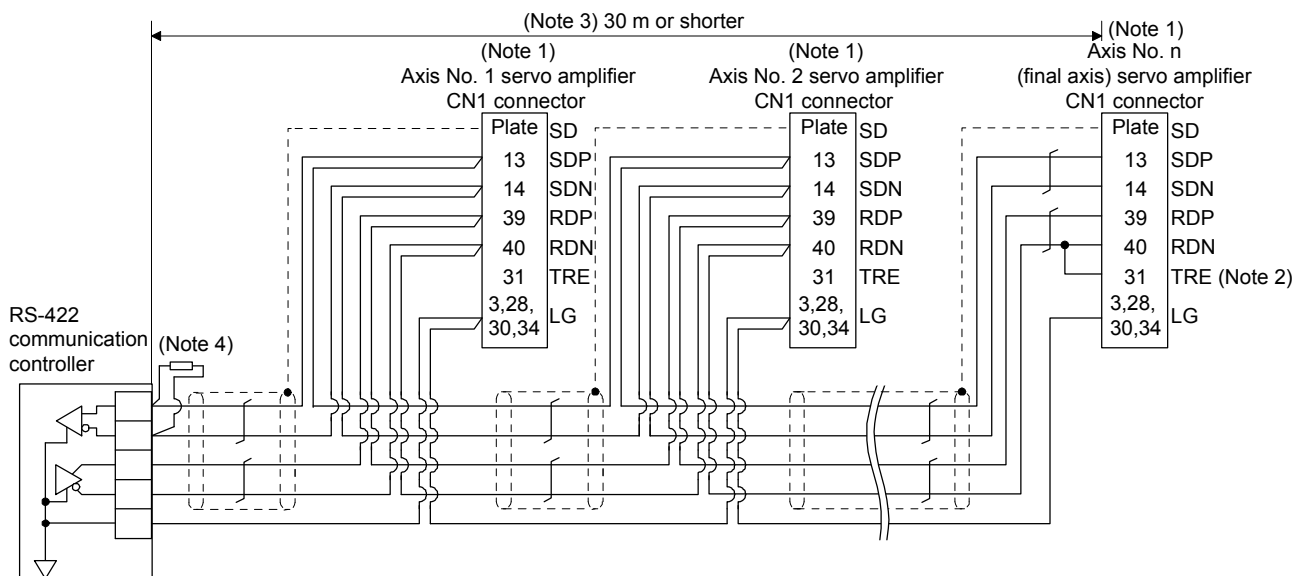
(1) Diagrammatic sketch

Up to 32 axes of servo amplifiers from stations 0 to 31 can be operated on the same bus.



(2) Cable connection diagram

Wire the cables as follows.



## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

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- Note
1. Connector set MR-J3CN1 (3M or equivalent)  
Connector: 10150-3000PE  
Shell kit: 10350-52F0-008
  2. Connect between TRE and RDN of the final axis servo amplifier.
  3. The overall length is 30 m or less in low-noise environment.
  4. If the RS-422 communication controller does not have a termination resistor, terminate it with a 150  $\Omega$  resistor.

### 12.1.2 Precautions for using RS422/USB communication function

Note the following to prevent an electric shock and malfunction of the servo amplifier.

#### (1) Power connection of personal computers

Connect your personal computer with the following procedures.

##### (a) When you use a personal computer with AC power supply

- 1) When using a personal computer with a three-core power plug or power plug with grounding wire, use a three-pin socket or ground the grounding wire.
- 2) When your personal computer has two-core plug and has no grounding wire, connect the personal computer to the servo amplifier with the following procedures.
  - a) Disconnect the power plug of the personal computer from an AC power socket.
  - b) Check that the power plug was disconnected and connect the device to the servo amplifier.
  - c) Connect the power plug of the personal computer to the AC power socket.

##### (b) When you use a personal computer with battery

You can use as it is.

#### (2) Connection with other devices using servo amplifier communication function

When the servo amplifier is charged with electricity due to connection with a personal computer and the charged servo amplifier is connected with other devices, the servo amplifier or the connected devices may malfunction. Connect the servo amplifier and other devices with the following procedures.

- (a) Shut off the power of the device for connecting with the servo amplifier.
- (b) Shut off the power of the servo amplifier which was connected with the personal computer and check the charge lamp is off.
- (c) Connect the device with the servo amplifier.
- (d) Turn on the power of the servo amplifier and the device.

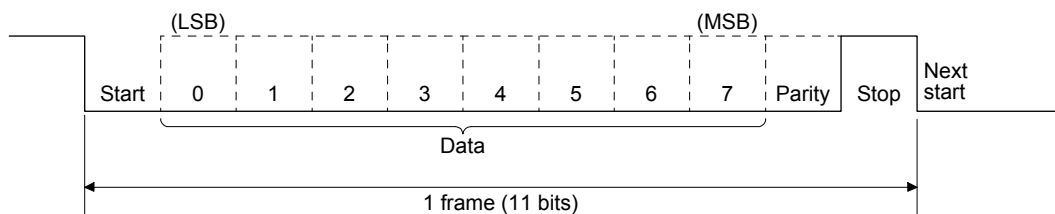
## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.2 Communication specifications

#### 12.2.1 Outline of communication

Receiving a command, this servo amplifier returns data. The device which gives the command (e.g. personal computer) is called a master station and the device (servo amplifier) which returns data in response to the command is called a slave station. When fetching data successively, the master station repeatedly commands the slave station to send data.

Item	Description	
Baud rate [bps]	4800/9600/19200/38400/57600/115200 asynchronous system	
Transfer code	Start bit	1 bit
	Data bit	8 bits
	Parity bit	1 bit (even)
	Stop bit	1 bit
Transfer method	Character method	Half-duplex communication method



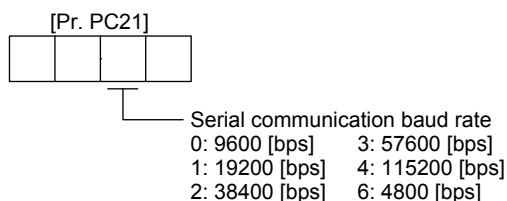
#### 12.2.2 Parameter setting

When the RS-422 communication function is used to operate the servo, set the communication specifications of the servo amplifier with the parameters.

To enable the parameter values, cycle the power after setting.

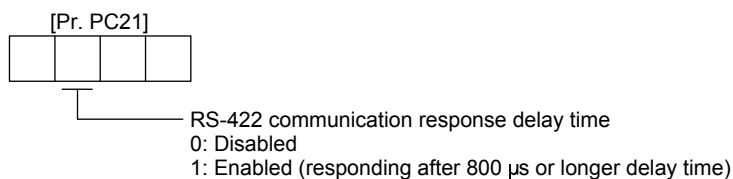
##### (1) Serial communication baud rate

Select the communication speed. Match this value to the communication speed of the sending end (master station).



##### (2) RS-422 communication response delay time

Set the time from when the servo amplifier (slave station) receives communication data to when it returns data. Set "0" to return data in less than 800 μs or "1" to return data in 800 μs or longer.



##### (3) Station No. setting

Set the station No. of the servo amplifier to [Pr. PC20]. The setting range is station No. 0 to 31.

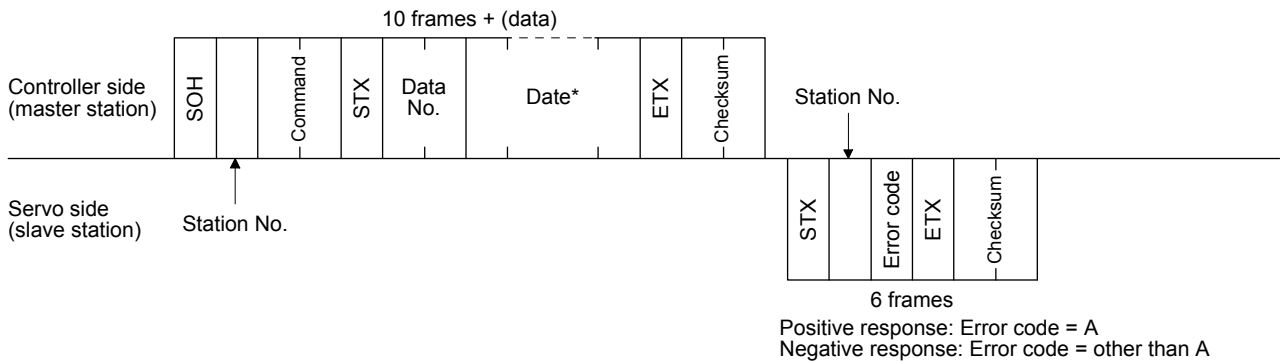
## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.3 Protocol

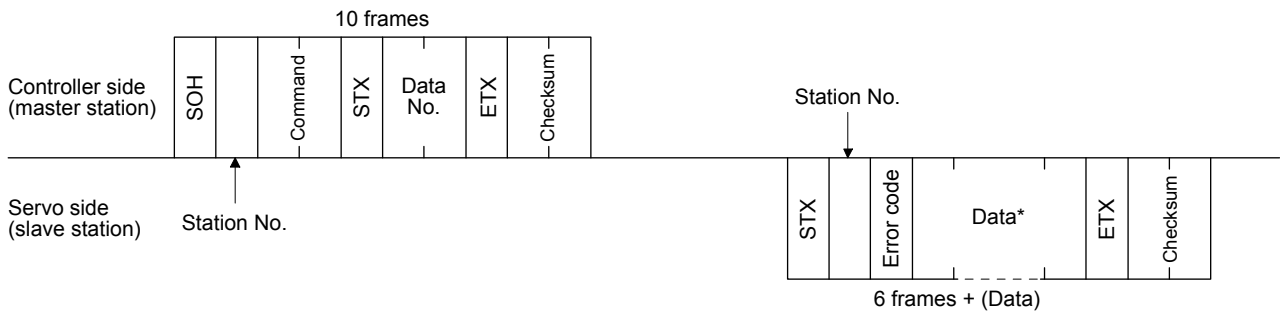
#### 12.3.1 Transmission data configuration

Since up to 32 axes may be connected to the bus, add a station No. to the command, data No., etc. to determine the destination servo amplifier of data communication. Set the station No. to each servo amplifier using the parameters. Transmission data is enabled for the servo amplifier of the specified station No. When "\*" is set as the station No. added to the transmission data, the transmission data is enabled for all servo amplifiers connected. However, when return data is required from the servo amplifier in response to the transmission data, set "0" to the station No. of the servo amplifier which must provide the return data.

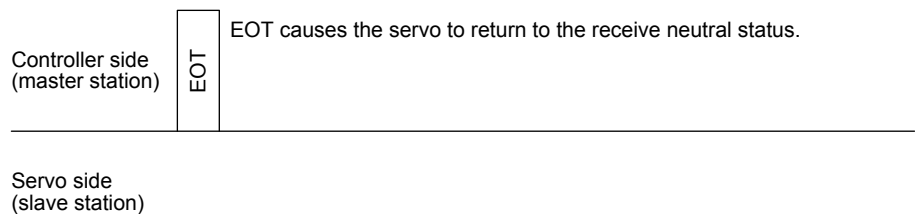
##### (1) Transmission of data from the controller to the servo



##### (2) Transmission of data request from the controller to the servo

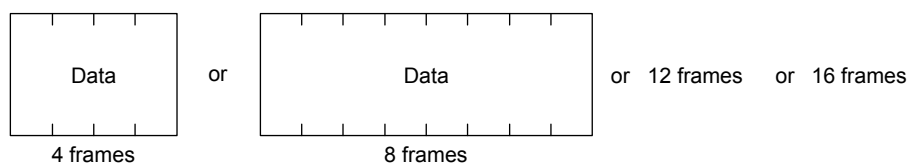


##### (3) Recovery of communication status by time-out



##### (4) Data frames

The data length depends on the command.



## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.3.2 Character codes

#### (1) Control codes

Code name	Hexadecimal (ASCII code)	Description	Personal computer terminal key operation (general)
SOH	01H	start of head	ctrl + A
STX	02H	start of text	ctrl + B
ETX	03H	end of text	ctrl + C
EOT	04H	end of transmission	ctrl + D

#### (2) Codes for data

Use ASCII unit codes.

	b8	0	0	0	0	0	0	0	0
	b7	0	0	0	0	1	1	1	1
	b6	0	0	1	1	0	0	1	1
	b5	0	1	0	1	0	1	0	1

b8 to b5	b4	b3	b2	b1
	0	0	0	0
	0	0	0	1
	0	0	1	0
	0	0	1	1
	0	1	0	0
	0	1	0	1
	0	1	1	0
	0	1	1	1
	1	0	0	0
	1	0	0	1
	1	0	1	0
	1	0	1	1
	1	1	0	0
	1	1	0	1
	1	1	1	0
	1	1	1	1

R \ C	0	1	2	3	4	5	6	7
0	NUL	DLE	Space	0	@	P	`	p
1	SOH	DC <sub>1</sub>	!	1	A	Q	a	q
2	STX	DC <sub>2</sub>	"	2	B	R	b	r
3	ETX	DC <sub>3</sub>	#	3	C	S	c	s
4			\$	4	D	T	d	t
5			%	5	E	U	e	u
6			&	6	F	V	f	v
7			'	7	G	W	g	w
8			(	8	H	X	h	x
9			)	9	I	Y	i	y
10			*	:	J	Z	j	z
11			+	;	K	[	k	{
12			,	<	L	¥	l	
13			-	=	M	]	m	}
14			.	>	N	^	n	~
15			/	?	O	_	o	DEL

#### (3) Station numbers

Set the station Nos. from station 0 to 31 in total of 32 stations, and use the ASCII unit codes to specify the stations.

Station No.	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
ASCII code	0	1	2	3	4	5	6	7	8	9	A	B	C	D	E	F

Station No.	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31
ASCII code	G	H	I	J	K	L	M	N	O	P	Q	R	S	T	U	V

For example, "30H" is transmitted in hexadecimal for the station No. "0" (axis 1).



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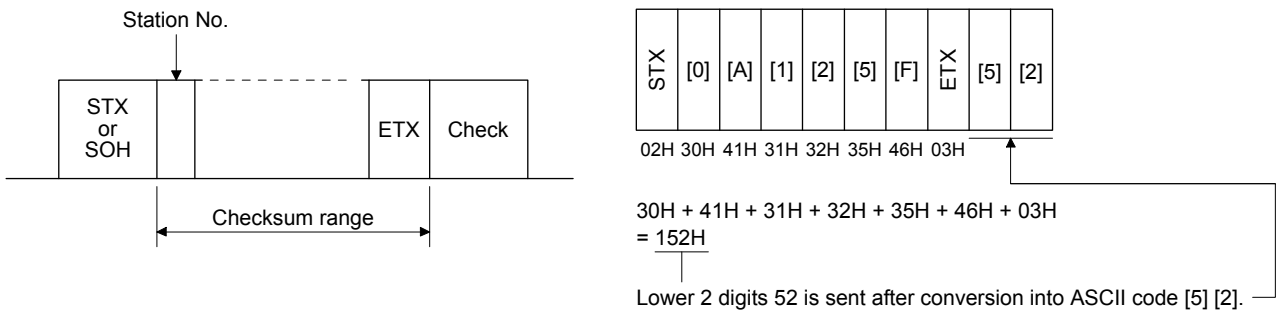
### 12.3.3 Error codes

Error codes are used in the following cases and an error code of single-code length is transmitted. Receiving data from the master station, the slave station sends the error code corresponding to that data to the master station. The error code sent in upper case indicates that the servo is normal and the one in lower case indicates that an alarm occurred.

Error code		Error name	Explanation	Remark
Servo: normal	Servo: alarm			
[A]	[a]	Normal	Data transmitted was processed normally.	Positive response
[B]	[b]	Parity error	Parity error occurred in the transmitted data.	Negative response
[C]	[c]	Checksum error	Checksum error occurred in the transmitted data.	
[D]	[d]	Character error	The transmitted character is out of specifications.	
[E]	[e]	Command error	The transmitted command is out of specifications.	
[F]	[f]	Data No. error	The transmitted data No. is out of specifications.	

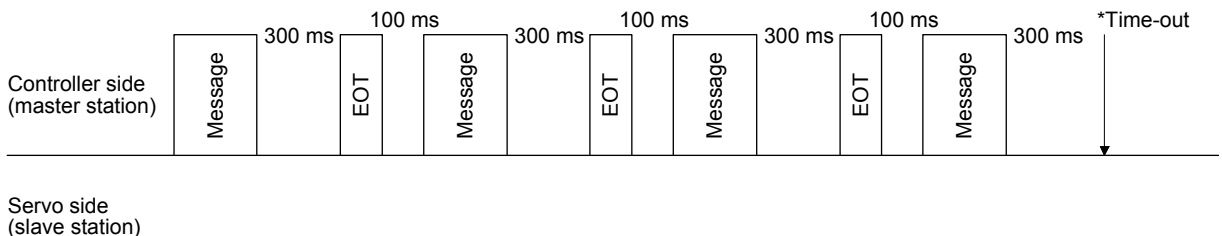
### 12.3.4 Checksum

The checksum is an ASCII-coded hexadecimal representing the lower two digits of the sum of ASCII-coded hexadecimal numbers up to ETX, with the exception of the first control code (STX or SOH).



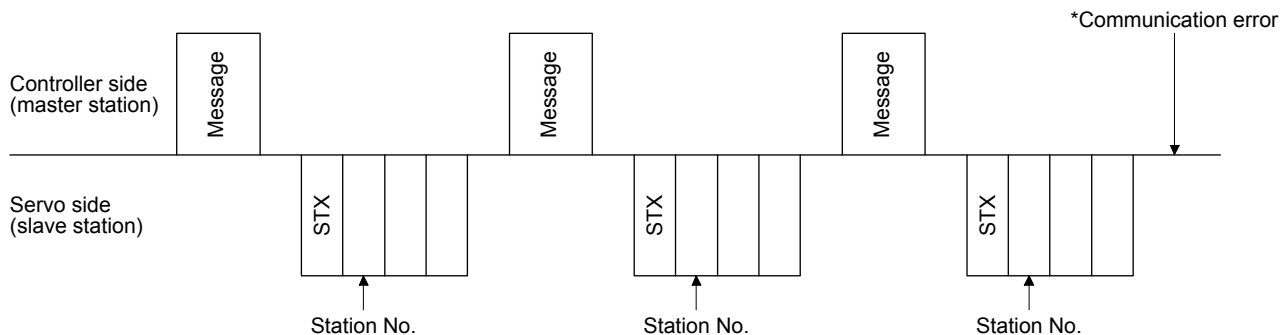
### 12.3.5 Time-out processing

The master station transmits EOT when the slave station does not start return processing (STX is not received) 300 [ms] after the master station has ended communication processing. 100 ms after that, the master station retransmits the message. Time-out occurs if the slave station does not answer after the master station has performed the above communication processing three times. (communication error)



12.3.6 Retry processing

When a fault occurs in communication between the master and slave stations, the error code in the response data from the slave station is a negative response code ([B] to [F], [b] to [f]). In this case, the master station retransmits the message which was sent at the occurrence of the fault (retry processing). A communication error occurs if the above processing is repeated and results in the error three or more consecutive times.



Similarly, when the master station detects a fault (e.g. checksum, parity) in the response data from the slave station, the master station retransmits the message which was sent at the occurrence of the fault. A communication error occurs if the retry processing is performed three times.

12.3.7 Initialization

After the slave station is switched on, it cannot return to communication until the internal initialization processing terminates. Hence, at power-on, ordinary communication should be started after.

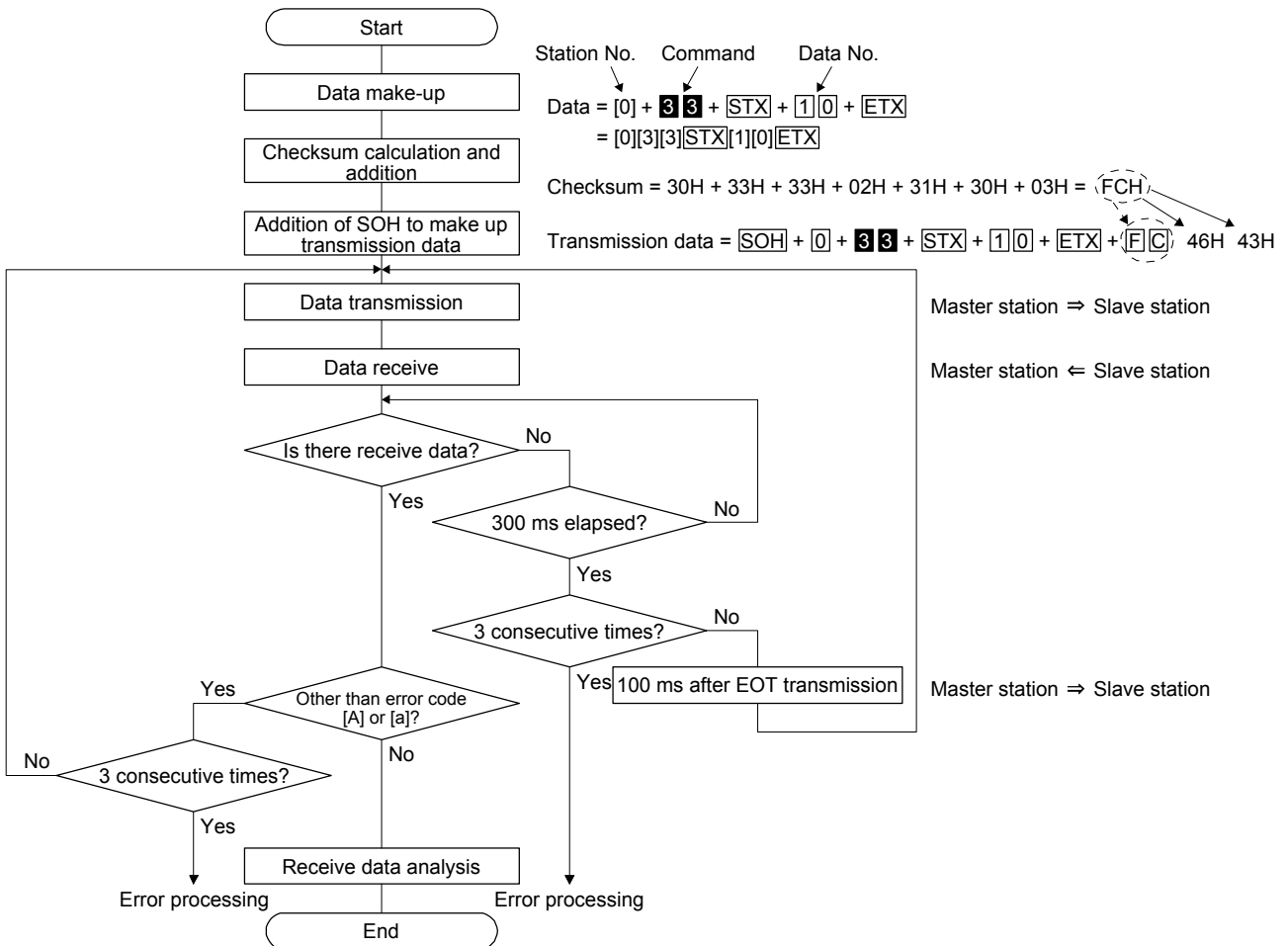
- (1) Wait for 3.5 s or longer after the slave station is switched on.
- (2) Check that normal communication can be made by reading the parameter or other data which does not pose any safety problems.

## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.3.8 Communication procedure example

The following example reads the set value of alarm history (last alarm) from the servo amplifier of station 0.

Data item	Value	Description
Station No.	0	Servo amplifier station 0
Command	3 3	Reading command
Data No.	1 0	Alarm history (last alarm)



## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.4 Command and data No. list

POINT
● Even if a command or data No. is the same between different model servo amplifiers, its description may differ.

#### 12.4.1 Reading command

##### (1) Status display (command [0] [1])

Command	Data No.	Description	Status display	Frame length		
[0] [1]	[0] [0]	Status display symbol and unit	Cumulative feedback pulses	16		
	[0] [1]		Servo motor speed			
	[0] [2]		Droop pulses			
	[0] [3]		Cumulative command pulses			
	[0] [4]		Command pulse frequency			
	[0] [5]		Analog speed command voltage			
			Analog speed limit voltage			
	[0] [6]		Analog torque limit voltage			
			Analog torque command voltage			
	[0] [7]		Regenerative load ratio			
	[0] [8]		Effective load ratio			
	[0] [9]		Peak load ratio			
	[0] [A]		Instantaneous torque			
	[0] [B]		Position within one-revolution			
	[0] [C]		ABS counter (Note)			
	[0] [D]		Load to motor inertia ratio			
	[0] [E]		Bus voltage			
	[2] [0]		Internal temperature of encoder			
	[2] [1]		Settling time			
	[2] [2]		Oscillation detection frequency			
	[2] [3]		Number of tough drive operations			
	[2] [8]		Unit power consumption			
	[2] [9]		Unit total power consumption			
	[8] [0]		Status display data value and processing information		Cumulative feedback pulses	12
	[8] [1]				Servo motor speed	
	[8] [2]				Droop pulses	
	[8] [3]				Cumulative command pulses	
	[8] [4]	Command pulse frequency				
	[8] [5]	Analog speed command voltage				
		Analog speed limit voltage				
	[8] [6]	Analog torque limit voltage				
		Analog torque command voltage				
	[8] [7]	Regenerative load ratio				
[8] [8]	Effective load ratio					
[8] [9]	Peak load ratio					
[8] [A]	Instantaneous torque					
[8] [B]	Position within one-revolution					
[8] [C]	ABS counter (Note)					
[8] [D]	Load to motor inertia ratio					
[8] [E]	Bus voltage					
[A] [0]	Internal temperature of encoder					
[A] [1]	Settling time					
[A] [2]	Oscillation detection frequency					
[A] [3]	Number of tough drive operations					
[A] [8]	Unit power consumption					
[A] [9]	Unit total power consumption					

Note. Travel distance from power on is displayed by counter value.

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### (2) Parameters (command [0] [4], [1] [5], [1] [6], [1] [7], [0] [8], and [0] [9])

Command	Data No.	Description	Frame length
[0] [4]	[0] [1]	Parameter group reading 0000: Basic setting parameters ([Pr. PA_ _]) 0001: Gain/filter parameters ([Pr. PB_ _]) 0002: Extension setting parameters ([Pr. PC_ _]) 0003: I/O setting parameters ([Pr. PD_ _]) 0004: Extension setting 2 parameters ([Pr. PE_ _]) 0005: Extension setting 3 parameters ([Pr. PF_ _])	4
[1] [5]	[0] [1] to [F] [F]	Current values of parameters Reads the current values of the parameters in the parameter group specified with the command [8] [5] + data No. [0] [0]. Before reading the current values, therefore, always specify the parameter group with the command [8] [5] + data No. [0] [0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter No.	12
[1] [6]	[0] [1] to [F] [F]	Upper limit values of parameter setting ranges Reads the permissible upper limit values of the parameters in the parameter group specified with the command [8] [5] + data No. [0] [0]. Before reading the upper limit values, therefore, always specify the parameter group with the command [8] [5] + data No. [0] [0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter No.	12
[1] [7]	[0] [1] to [F] [F]	Lower limit values of parameter setting ranges Reads the permissible lower limit values of the parameters in the parameter group specified with the command [8] [5] + data No. [0] [0]. Before reading the lower limit values, therefore, always specify the parameter group with the command [8] [5] + data No. [0] [0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter No.	12
[0] [8]	[0] [1] to [F] [F]	Parameter symbols Reads the symbols of the parameters in the parameter group specified with the command [8] [5] + data No. [0] [0]. Before reading the symbols, therefore, always specify the parameter group with the command [8] [5] + data No. [0] [0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter No.	12
[0] [9]	[0] [1] to [F] [F]	Writing enable/disable of parameters Reads writing enable/disable of the parameters in the parameter group specified with the command [8] [5] + data No. [0] [0]. Before reading the lower limit values, therefore, always specify the parameter group with the command [8] [5] + data No. [0] [0]. 0000: Writing enabled 0001: Writing disabled	4

### (3) External I/O signals (command [1] [2])

Command	Data No.	Description	Frame length
[1] [2]	[0] [0]	Input device status	8
	[4] [0]	External input pin status	
	[6] [0]	Status of input device turned on by communication	
	[8] [0]	Output device status	
	[C] [0]	External output pin status	

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### (4) Alarm history (command [3] [3])

Command	Data No.	Description	Alarm occurrence sequence	Frame length
[3] [3]	[1] [0]	Alarm No. in alarm history	Most recent alarm	4
	[1] [1]		First alarm in past	
	[1] [2]		Second alarm in past	
	[1] [3]		Third alarm in past	
	[1] [4]		Fourth alarm in past	
	[1] [5]		Fifth alarm in past	
	[1] [6]		Sixth alarm in past	
	[1] [7]		Seventh alarm in past	
	[1] [8]		Eighth alarm in past	
	[1] [9]		Ninth alarm in past	
	[1] [A]		Tenth alarm in past	
	[1] [B]		Eleventh alarm in past	
	[1] [C]		Twelfth alarm in past	
	[1] [D]		Thirteenth alarm in past	
	[1] [E]		Fourteenth alarm in past	
	[1] [F]	Fifteenth alarm in past		
	[2] [0]	Alarm occurrence time in alarm history	Most recent alarm	8
	[2] [1]		First alarm in past	
	[2] [2]		Second alarm in past	
	[2] [3]		Third alarm in past	
	[2] [4]		Fourth alarm in past	
	[2] [5]		Fifth alarm in past	
	[2] [6]		Sixth alarm in past	
	[2] [7]		Seventh alarm in past	
	[2] [8]		Eighth alarm in past	
	[2] [9]		Ninth alarm in past	
	[2] [A]		Tenth alarm in past	
[2] [B]	Eleventh alarm in past			
[2] [C]	Twelfth alarm in past			
[2] [D]	Thirteenth alarm in past			
[2] [E]	Fourteenth alarm in past			
[2] [F]	Fifteenth alarm in past			

### (5) Current alarm (command [0] [2])

Command	Data No.	Description	Frame length
[0] [2]	[0] [0]	Current alarm No.	4

### (6) Status display at alarm occurrence (command [3] [5])

Command	Data No.	Description	Status display	Frame length
[3] [5]	[0] [0]	Status display symbol and unit	Cumulative feedback pulses	16
	[0] [1]		Servo motor speed	
	[0] [2]		Droop pulses	
	[0] [3]		Cumulative command pulses	
	[0] [4]		Command pulse frequency	
	[0] [5]		Analog speed command voltage	
	[0] [6]		Analog speed limit voltage	
	[0] [7]		Analog torque limit voltage	
	[0] [8]		Analog torque command voltage	
	[0] [9]		Regenerative load ratio	
		Effective load ratio		
		Peak load ratio		

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Command	Data No.	Description	Status display	Frame length		
[3] [5]	[0] [A]	Status display symbol and unit	Instantaneous torque	16		
	[0] [B]		Position within one-revolution			
	[0] [C]		ABS counter (Note)			
	[0] [D]		Load to motor inertia ratio			
	[0] [E]		Bus voltage			
	[2] [0]		Internal temperature of encoder			
	[2] [1]		Settling time			
	[2] [2]		Oscillation detection frequency			
	[2] [3]		Number of tough drive operations			
	[2] [8]		Unit power consumption			
	[2] [9]		Unit total power consumption			
	[8] [0]		Status display data value and processing information		Cumulative feedback pulses	12
	[8] [1]				Servo motor speed	
	[8] [2]	Droop pulses				
	[8] [3]	Cumulative command pulses				
	[8] [4]	Command pulse frequency				
	[8] [5]	Analog speed command voltage				
	[8] [6]	Analog speed limit voltage				
	[8] [6]	Analog torque limit voltage				
	[8] [6]	Analog torque command voltage				
	[8] [7]	Regenerative load ratio				
	[8] [8]	Effective load ratio				
	[8] [9]	Peak load ratio				
	[8] [A]	Instantaneous torque				
	[8] [B]	Position within one-revolution				
	[8] [C]	ABS counter (Note)				
	[8] [D]	Load to motor inertia ratio				
[8] [E]	Bus voltage					
[A] [0]	Internal temperature of encoder					
[A] [1]	Settling time					
[A] [2]	Oscillation detection frequency					
[A] [3]	Number of tough drive operations					
[A] [8]	Unit power consumption					
[A] [9]	Unit total power consumption					

Note. Travel distance from power on is displayed by counter value.

### (7) Test operation mode (command [0] [0])

Command	Data No.	Description	Frame length
[0] [0]	[1] [2]	Test operation mode reading 0000: Normal mode (not test operation mode) 0001: JOG operation 0002: Positioning operation 0004: Output signal (DO) forced output	4

### (8) Software version (command [0] [2])

Command	Data No.	Description	Frame length
[0] [2]	[7] [0]	Software version	16

## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.4.2 Writing commands

#### (1) Status display (command [8] [1])

Command	Data No.	Description	Setting range	Frame length
[8] [1]	[0] [0]	Status display data deletion	1EA5	4

#### (2) Parameters (command [9] [4], [8] [5])

Command	Data No.	Description	Setting range	Frame length
[9] [4]	[0] [1] to [F] [F]	Writing each parameter Writes the values of the parameters in the parameter group specified with the command [8] [5] + data No. [0] [0]. Before writing the values, therefore, always specify the parameter group with the command [8] [5] + data No. [0] [0]. The decimal equivalent of the data No. value (hexadecimal) corresponds to the parameter No.	Depending on the parameter	12
[8] [5]	[0] [0]	Parameter group writing 0000: Basic setting parameters ([Pr. PA_ _]) 0001: Gain/filter parameters ([Pr. PB_ _]) 0002: Extension setting parameters ([Pr. PC_ _]) 0003: I/O setting parameters ([Pr. PD_ _]) 0004: Extension setting 2 parameters ([Pr. PE_ _]) 0005: Extension setting 3 parameters ([Pr. PF_ _])	0000 to 0005	4

#### (3) External I/O signals (command [9] [2])

Command	Data No.	Description	Setting range	Frame length
[9] [2]	[6] [0]	Communication input device signal	Refer to section 12.5.5.	8

#### (4) Alarm history (command [8] [2])

Command	Data No.	Description	Setting range	Frame length
[8] [2]	[2] [0]	Alarm history clear	1EA5	4

#### (5) Current alarm (command [8] [2])

Command	Data No.	Description	Setting range	Frame length
[8] [2]	[0] [0]	Alarm clear	1EA5	4

#### (6) I/O device prohibition (command [9] [0])

Command	Data No.	Description	Setting range	Frame length
[9] [0]	[0] [0]	Turns off the input device, external analog input signal or pulse train input, except EM2, LSP and LSN, independently of the external on/off status.	1EA5	4
	[0] [3]	Disables all output devices (DO).	1EA5	4
	[1] [0]	Cancels the prohibition of the input device, external analog input signal or pulse train input, except EM2, LSP and LSN.	1EA5	4
	[1] [3]	Cancels the prohibition of the output device.	1EA5	4

#### (7) Operation mode selection (command [8] [B])

Command	Data No.	Description	Setting range	Frame length
[8] [B]	[0] [0]	Selection of test operation mode 0000: Test operation mode cancel 0001: JOG operation 0002: Positioning operation 0004: Output signal (DO) forced output	0000 to 0002, 0004	4



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(8) Test operation mode data (command [9] [2], [A] [0])

Command	Data No.	Description	Setting range	Frame length				
[9] [2]	[0] [0]	Input signal for test operation	Refer to section 12.5.7.	8				
	[A] [0]	Forced output of signal pin	Refer to section 12.5.9.	8				
[A] [0]	[1] [0]	Write the servo motor speed in the test operation mode (JOG operation and positioning operation).	0000 to 7FFF	4				
	[1] [1]	Write the acceleration/deceleration time constant in the test operation mode (JOG operation and positioning operation).	00000000 to 7FFFFFFF	8				
	[2] [0]	Set the travel distance in the test operation mode (positioning operation).	00000000 to 7FFFFFFF	8				
	[2] [1]	Select the positioning direction of test operation (positioning operation).  <div style="text-align: center;"> <table border="1" style="display: inline-table; border-collapse: collapse;"> <tr> <td style="padding: 2px 10px;">0</td> <td style="padding: 2px 10px;"></td> <td style="padding: 2px 10px;">0</td> <td style="padding: 2px 10px;"></td> </tr> </table> <p style="margin-left: 40px;">└─ 0: Forward rotation direction    1: Reverse rotation direction</p> <p style="margin-left: 40px;">└─ 0: Command pulse unit    1: Encoder pulse unit</p> </div>	0		0		0000 to 0101	4
	0		0					
[4] [0]	This is a start command for test operation (positioning operation).	1EA5	4					
[4] [1]	Use this to make a temporary stop during test operation (positioning operation). "□" in the data indicates a blank. STOP: Temporary stop GO□□: Restart for remaining distance CLR□: Remaining distance clear	STOP GO□□ CLR□	4					

12.5 Detailed explanations of commands

12.5.1 Data processing

When the master station transmits a command data No. or a command + data No. + data to a slave station, the servo amplifier returns a response or data in accordance with the purpose.

When numerical values are represented in these send data and receive data, they are represented in decimal, hexadecimal, etc.

Therefore, data must be processed in accordance with the application.

Since whether data must be processed or not and how to process data depend on the monitoring, parameters, etc., follow the detailed explanation of the corresponding command.

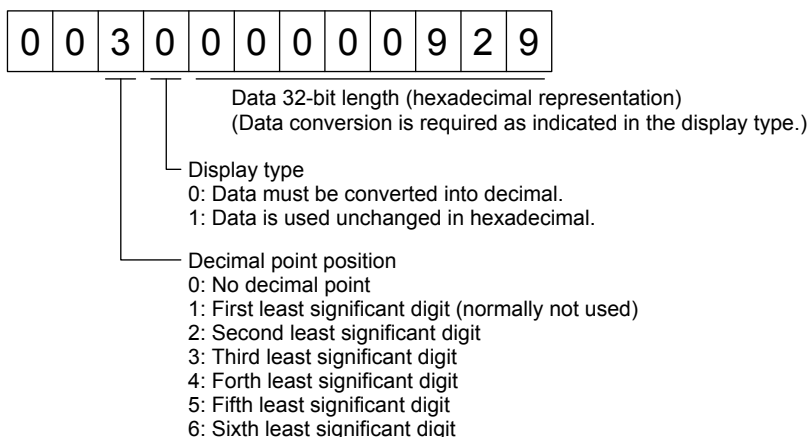
The following methods are how to process send and receive data when reading and writing data.

(1) Processing a read data

When the display type is 0, convert the eight-character data from hexadecimal to decimal, and place a decimal point according to the decimal point information.

When the display type is 1, use the eight-character data unchanged.

The following example indicates how to process the receive data "00300000929" given to show. The receive data is as follows.



Since the display type is "0" in this case, convert the hexadecimal data to decimal.

00000929H → 2345

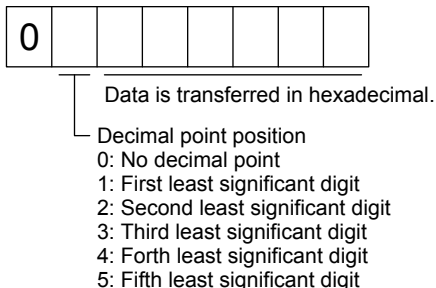
As the decimal point position is "3", place a decimal point in the lower third digit.

Hence, "23.45" is displayed.

(2) Writing processed data

When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, the data cannot be written. When the data is handled as hexadecimal, specify "0" as the decimal point position.

The data to be sent is the following value.



For example, here is described how to process the set data when a value of "15.5" is sent. Since the decimal point position is the second least significant digit, the decimal point position data is "2".

As the data to be sent is hexadecimal, convert the decimal data into hexadecimal.

155 → 9B

Hence, "0200009B" is transmitted.

12.5.2 Status display mode

(1) Reading the status display name and unit

The following shows how to read the status display name and unit.

(a) Transmission

Transmit the command [0] [1] and the data No. corresponding to the status display item to be read, [0] [0] to [0] [E] and [2] [0] to [2] [9]. (Refer to section 12.4.1.)

(b) Return

The slave station returns the status display name and unit requested.



(2) Status display data reading

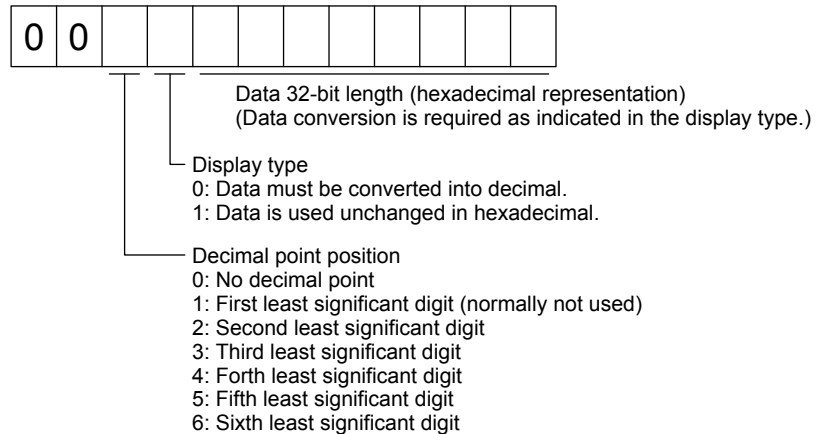
The following shows how to read the status display data and processing information.

(a) Transmission

Transmit the command [0] [1] and the data No. corresponding to the status display item to be read, [8] [0] to [8] [E] and [A] [0] to [A] [9]. (Refer to section 12.4.1.)

(b) Return

The slave station returns the status display data requested.



(3) Status display data clear

To clear the cumulative feedback pulse data of the status display, send this command immediately after reading the status display item. The data of the status display item transmitted is cleared to "0".

Command	Data No.	Data
[8] [1]	[0] [0]	1EA5

For example, after sending command [0] [1] and data No. [8] [0] and receiving the status display data, send command [8] [1], data No. [0] [0] and data [1EA5] to clear the cumulative feedback pulse value to "0".

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### 12.5.3 Parameter

#### (1) Specification of the parameter group

To read or write the parameter settings, etc., the group of the parameters to be operated must be specified in advance. Write data to the servo amplifier as follows to specify the parameter group.

Command	Data No.	Transmission data	Parameter group
[8] [5]	[0] [0]	0000	Basic setting parameters ([Pr. PA__])
		0001	Gain/filter parameters ([Pr. PB__])
		0002	Extension setting parameters ([Pr. PC__])
		0003	I/O setting parameters ([Pr. PD__])
		0004	Extension setting 2 parameters ([Pr. PE__])
		0005	Extension setting 3 parameters ([Pr. PF__])

#### (2) Parameter group reading

The following shows how to read the parameter group set with slave station.

##### (a) Transmission

Transmit command [0] [4] and data No. [0] [1].

Command	Data No.
[0] [4]	[0] [1]

##### (b) Return

The slave station returns the preset parameter group.

0	0	0	
---	---	---	--

Parameter group  
 0: Basic setting parameters ([Pr. PA\_\_])  
 1: Gain/filter parameters ([Pr. PB\_\_])  
 2: Extension setting parameters ([Pr. PC\_\_])  
 3: I/O setting parameters ([Pr. PD\_\_])  
 4: Extension setting 2 parameters ([Pr. PE\_\_])  
 5: Extension setting 3 parameters ([Pr. PF\_\_])

#### (3) Reading symbols

The following shows how to read symbols of parameters. Specify a parameter group in advance. (Refer to (1) of this section.)

##### (a) Transmission

Transmit the command [0] [8] and the data No. [0] [1] to [F] [F] corresponding to the parameter No. (Refer to section 12.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter No.

##### (b) Return

The slave station returns the symbol of the parameter requested.

0	0	0								
---	---	---	--	--	--	--	--	--	--	--

Symbol characters (9 digits)

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### (4) Reading the setting

The following shows how to read the parameter setting. Specify a parameter group in advance. (Refer to (1) of this section.)

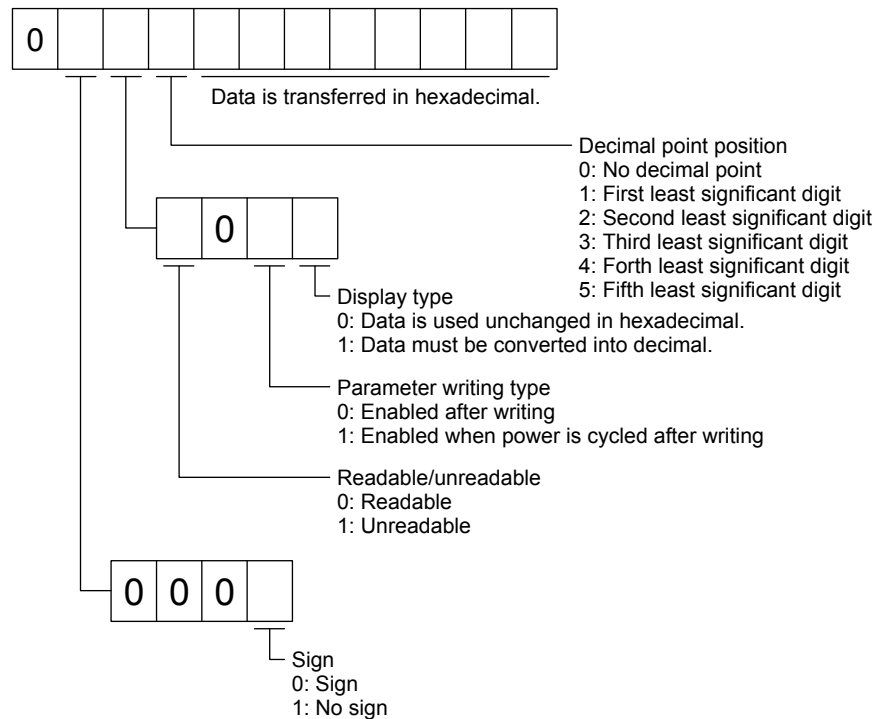
#### (a) Transmission

Transmit the command [1] [5] and the data No. corresponding to the parameter No [0] [1] to [F] [F]. (Refer to section 12.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter No.

#### (b) Return

The slave station returns the data and processing information of the parameter No. requested.



For example, data "00120000270F" means 999.9 (decimal display format) and data "000000003ABC" means 3ABC (hexadecimal display format).

When the display type is "0" (hexadecimal) and the decimal point position is other than 0, the display type is a special hexadecimal display format and "F" of the data value is handled as a blank. Data "0001FFFFFF053" means 053 (special hexadecimal display format).

"008000000000" is transferred when the parameter that was read is the one inaccessible for reference in the parameter writing inhibit setting of [Pr. PA19].

(5) Reading the setting range

The following shows how to read the parameter setting range. Specify a parameter group in advance. (Refer to (1) of this section.)

(a) Transmission

When reading an upper limit value, transmit the command [1] [6] and the data No. [0] [1] to [F] [F] corresponding to the parameter No. When reading an lower limit value, transmit the command [1] [7] and the data No. [0] [1] to [F] [F] corresponding to the parameter No. (Refer to section 12.4.1.)  
The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter No.

(b) Return

The slave station returns the data and processing information of the parameter No. requested.



Data is transferred in hexadecimal.

For example, data "FFFFFFEC" means "-20".

(6) Writing setting values

POINT
<p>● If setting values need to be changed with a high frequency (i.e. one time or more per one hour), write the setting values to the RAM, not to the EEP-ROM. The EEPROM has a limitation in the number of write times and exceeding this limitation causes the servo amplifier to malfunction. Note that the number of write times to the EEP-ROM is limited to approximately 100, 000.</p>

Write the parameter setting into EEP-ROM of the servo amplifier. Specify a parameter group in advance. (Refer to (1) of this section.)

Write any value within the setting enabled range. For the setting enabled range, refer to chapter 5 or read the setting range by performing operation in (4) of this section.

Transmit command [9] [4], the data No. , and the set data.

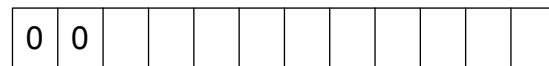
The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter No.

When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, the data cannot be written. When the data is handled as hexadecimal, specify "0" as the decimal point position.

Check the writing data is within the upper/lower limit value before writing. To prevent an error, read the parameter data to be written, confirm the decimal point position, and create transmission data.

On completion of writing, read the same parameter data to verify that data has been written correctly.

Command	Data No.	Data
[9] [4]	[0] [1] to [F] [F]	See below.



Data is transferred in hexadecimal.

Writing mode  
 0: Writing to EEP-ROM  
 3: Writing to RAM  
 When the parameter data is changed frequently through communication, set "3" to the mode to change only the RAM data in the servo amplifier.  
 When changing data frequently (once or more within one hour), do not write it to the EEP-ROM.

Decimal point position  
 0: No decimal point  
 1: First least significant digit  
 2: Second least significant digit  
 3: Third least significant digit  
 4: Forth least significant digit  
 5: Fifth least significant digit



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### 12.5.4 External I/O signal status (DIO diagnosis)

#### (1) Reading input device status

The following shows how to read the status of the input devices.

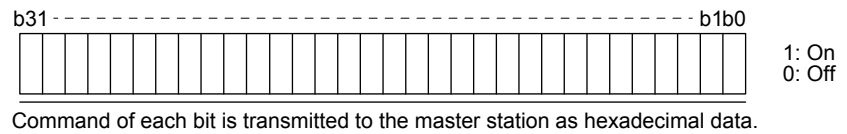
##### (a) Transmission

Transmit command [1] [2] and data No. [0] [0].

Command	Data No.
[1] [2]	[0] [0]

##### (b) Return

The slave station returns the status of the input devices.



Bit	Symbol
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

Bit	Symbol
8	SP1
9	SP2
10	SP3
11	ST1/RS2
12	ST2/RS1
13	CM1
14	CM2
15	LOP

Bit	Symbol
16	
17	
18	
19	
20	STAB2
21	
22	
23	

Bit	Symbol
24	
25	
26	
27	CDP
28	
29	
30	
31	

#### (2) Reading external input pin status

The following shows how to read the on/off status of the external input pins.

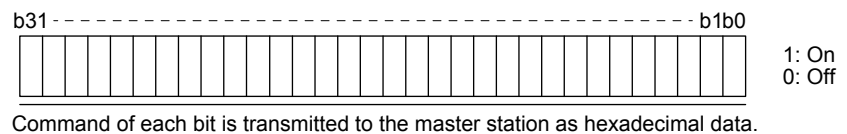
##### (a) Transmission

Transmit command [1] [2] and data No. [4] [0].

Command	Data No.
[1] [2]	[4] [0]

##### (b) Return

The on/off status of the input pins are returned.



Bit	CN1 connector pin
0	43
1	44
2	42
3	15
4	19
5	41
6	
7	

Bit	CN1 connector pin
8	
9	
10	
11	
12	
13	
14	
15	

Bit	CN1 connector pin
16	
17	
18	
19	
20	
21	
22	
23	

Bit	CN1 connector pin
24	
25	
26	
27	
28	
29	
30	
31	

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### (3) Reading the status of input devices switched on with communication

The following shows how to read the on/off status of the input devices switched on with communication.

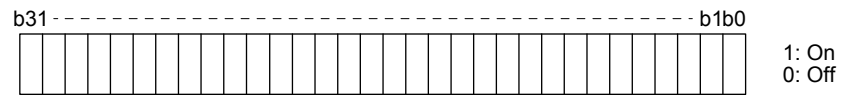
#### (a) Transmission

Transmit command [1] [2] and data No. [6] [0].

Command	Data No.
[1] [2]	[6] [0]

#### (b) Return

The slave station returns the status of the input devices.



Command of each bit is transmitted to the master station as hexadecimal data.

Bit	Symbol
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

Bit	Symbol
8	SP1
9	SP2
10	SP3
11	ST1/RS2
12	ST2/RS1
13	CM1
14	CM2
15	LOP

Bit	Symbol
16	
17	
18	
19	
20	STAB2
21	
22	
23	

Bit	Symbol
24	
25	
26	
27	CDP
28	
29	
30	
31	

### (4) Reading output device status

The following shows how to read the on/off status of the output devices.

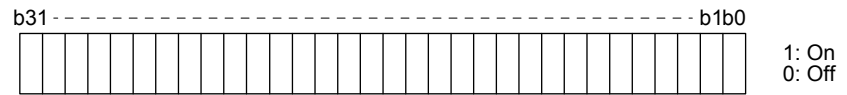
#### (a) Transmission

Transmit command [1] [2] and data No. [8] [0].

Command	Data No.
[1] [2]	[8] [0]

#### (b) Return

The slave station returns the status of the input/output devices.



Command of each bit is transmitted to the master station as hexadecimal data.

Bit	Symbol
0	RD
1	SA
2	ZSP
3	TLC
4	VLC
5	INP
6	
7	WNG

Bit	Symbol
8	ALM
9	OP
10	MBR
11	
12	ACD0
13	ACD1
14	ACD2
15	

Bit	Symbol
16	
17	
18	
19	
20	
21	
22	
23	

Bit	Symbol
24	
25	CDPS
26	
27	
28	
29	
30	
31	MTTR

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(5) Reading external output pin status

The following shows how to read the on/off status of the external output pins.

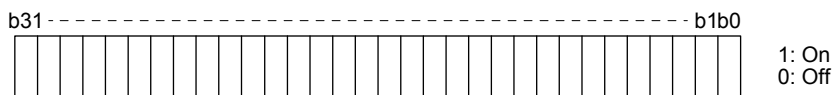
(a) Transmission

Transmit command [1] [2] and data No. [C] [0].

Command	Data No.
[1] [2]	[C] [0]

(b) Return

The slave station returns the status of the output devices.



Command of each bit is transmitted to the master station as hexadecimal data.

Bit	CN1 connector pin
0	49
1	24
2	23
3	
4	
5	48
6	33
7	

Bit	CN1 connector pin
8	
9	
10	
11	
12	
13	
14	
15	

Bit	CN1 connector pin
16	
17	
18	
19	
20	
21	
22	
23	

Bit	CN1 connector pin
24	
25	
26	
27	
28	
29	
30	
31	

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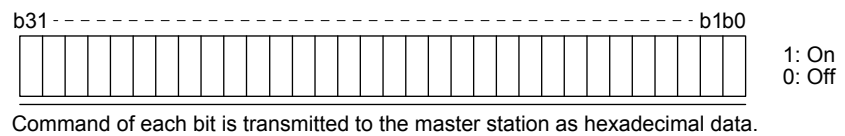
### 12.5.5 Input device on/off

POINT
<p>● The on/off status of all devices in the servo amplifier are the status of the data received at last. Therefore, when there is a device which must be kept on, transmit data which turns the device on every time.</p>

Each input device can be switched on/off. However, when the device to be switched off is in the external input signal, also switch off the input signal.

Transmit command [9] [2], data No. [6] [0], and data.

Command	Data No.	Set data
[9] [2]	[6] [0]	See below.



Bit	Symbol
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

Bit	Symbol
8	SP1
9	SP2
10	SP3
11	ST1/RS2
12	ST2/RS1
13	CM1
14	CM2
15	LOP

Bit	Symbol
16	
17	
18	
19	
20	STAB2
21	
22	
23	

Bit	Symbol
24	
25	
26	
27	CDP
28	
29	
30	
31	

### 12.5.6 Disabling/enabling I/O devices (DIO)

You can disable inputs regardless of the I/O device status. When inputs are disabled, the input signals (devices) are recognized as follows. However, EM2 (Forced stop 2), LSP (Forward rotation stroke end), and LSN (Reverse rotation stroke end) cannot be disabled.

Signal	Status
Input device (DI)	Off
External analog input signal	0 V
Pulse train input	None

- (1) Disabling/enabling the input devices (DI), external analog input signals and pulse train inputs except EM2 (Forced stop 2), LSP (Forward rotation stroke end), and LSN (Reverse rotation stroke end).  
Transmit the following communication commands.

(a) Disabling

Command	Data No.	Data
[9] [0]	[0] [0]	1EA5

(b) Enabling

Command	Data No.	Data
[9] [0]	[1] [0]	1EA5

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### (2) Disabling/enabling the output devices (DO)

Transmit the following communication commands.

#### (a) Disabling

Command	Data No.	Data
[9] [0]	[0] [3]	1EA5

#### (b) Enabling

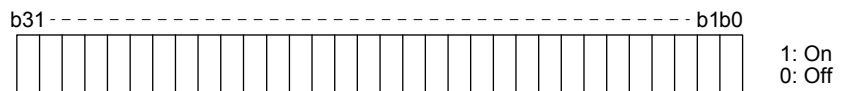
Command	Data No.	Data
[9] [0]	[1] [3]	1EA5

### 12.5.7 Input devices on/off (test operation)

Each input devices can be turned on/off for test operation. However, when the device to be switched off is in the external input signal, also switch off the input signal.

Transmit command [9] [2], data No. [0] [0], and data.

Command	Data No.	Set data
[9] [2]	[0] [0]	See below.



Command of each bit is transmitted to the master station as hexadecimal data.

Bit	Symbol
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

Bit	Symbol
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

Bit	Symbol
16	
17	
18	
19	
20	STAB2
21	
22	
23	

Bit	Symbol
24	
25	
26	
27	CDP
28	
29	
30	
31	

12.5.8 Test operation mode

POINT
<ul style="list-style-type: none"> <li>● The test operation mode is used to check operation. Do not use it for actual operation.</li> <li>● If communication stops for longer than 0.5 s during test operation, the servo amplifier decelerates to a stop, resulting in servo-lock. To prevent this, continue communication all the time by monitoring the status display, etc.</li> <li>● Even during operation, you can switch the servo amplifier to the test operation mode. In this case, switching to the test operation mode will shut off the base circuit to coast the motor.</li> </ul>

(1) How to prepare and cancel the test operation mode

(a) Preparing the test operation mode

Set the test operation mode type with the following procedure.

1) Selection of test operation mode

Send the command [8] [B] + data No. [0] [0] + data to select the test operation mode.

Command	Data No.	Transmission data	Selection of test operation mode
[8] [B]	[0] [0]	0001	JOG operation
		0002	Positioning operation
		0004	Output signal (DO) forced output (Note)

Note. Refer to section 12.5.9 for the output signal (DO) forced output.

2) Check of test operation mode

Read the test operation mode set for the slave station, and check that it is set correctly.

a) Transmission

Transmit command [0] [0] and data No. [1] [2].

Command	Data No.
[0] [0]	[1] [2]

b) Reply

The slave station returns the preset operation mode.

0	0	0	
---	---	---	--

└ Test operation mode reading  
 0: Normal mode (not test operation mode)  
 1: JOG operation  
 2: Positioning operation  
 4: Output signal (DO) forced output

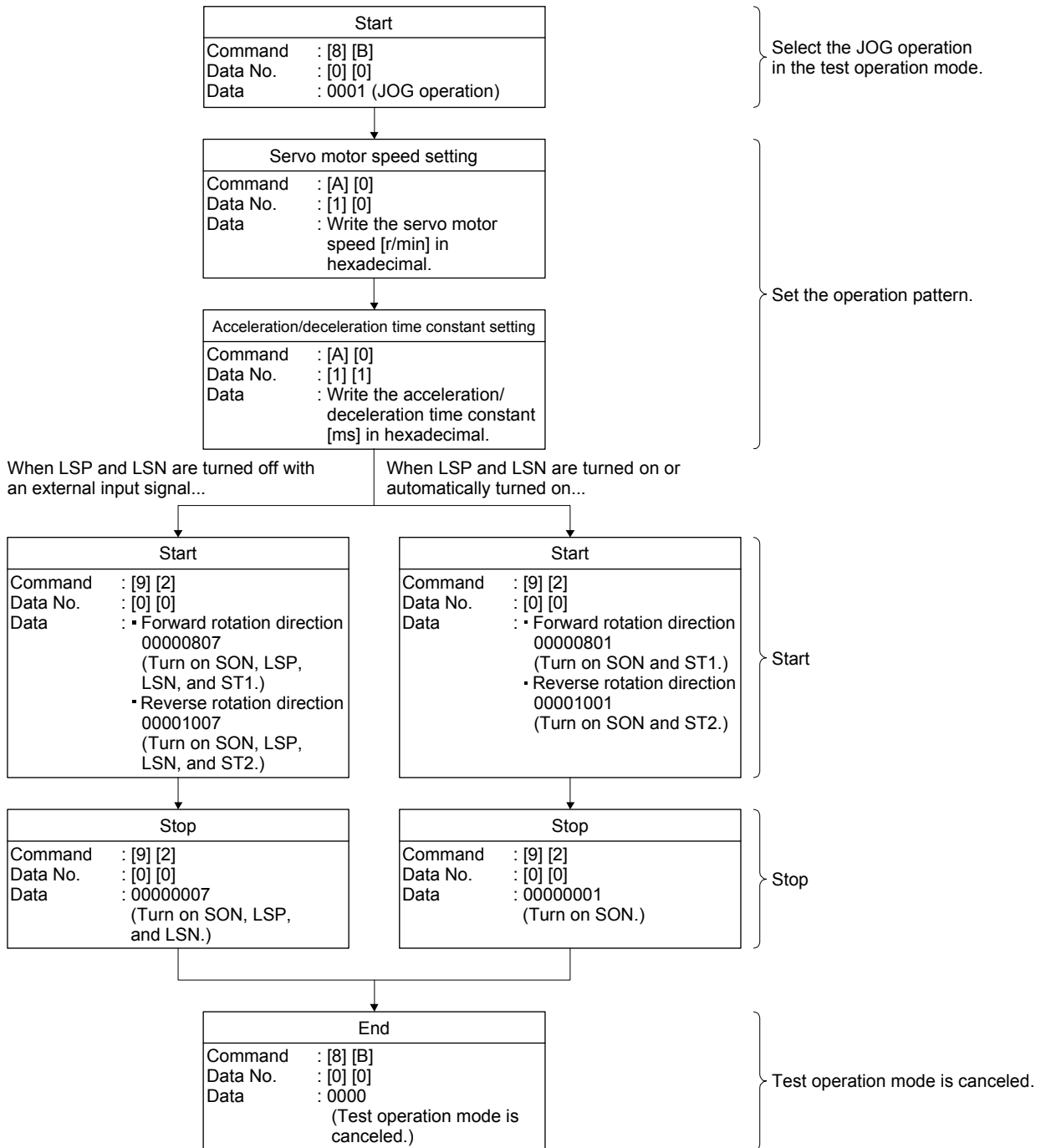
(b) Cancel of test operation mode

To terminate the test operation mode, send the command [8] [B] + data No. [0] [0] + data.

Command	Data No.	Transmission data	Selection of test operation mode
[8] [B]	[0] [0]	0000	Test operation mode cancel

(2) JOG operation

Transmit the command, data No., and data as follows to execute JOG operation.

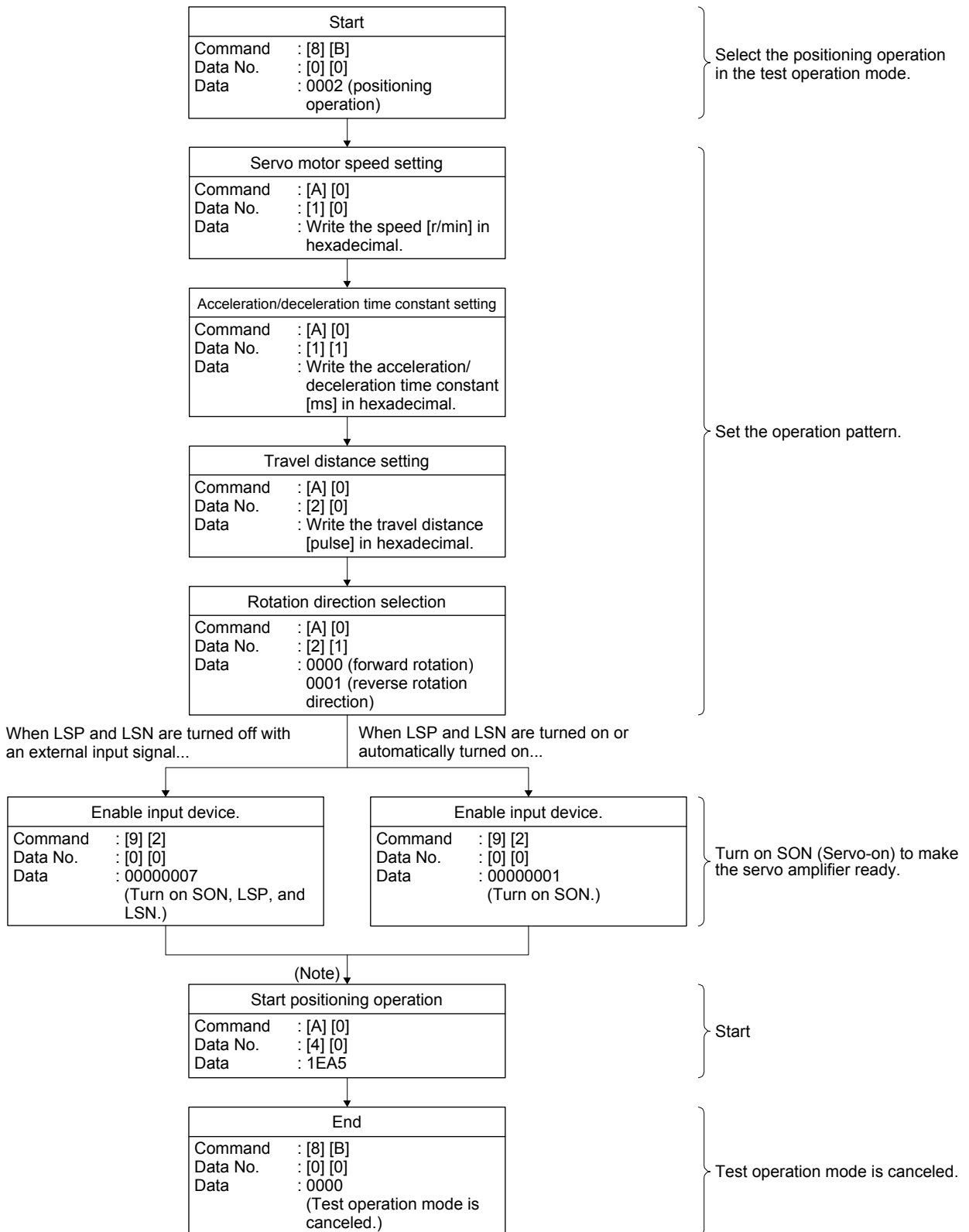


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### (3) Positioning operation

#### (a) Operation procedure

Transmit the command, data No., and data as follows to execute positioning operation.





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### (b) Temporary stop/restart/remaining distance clear

Transmit the following command, data No., and data during positioning operation to make deceleration to a stop.

Command	Data No.	Data
[A] [0]	[4] [1]	STOP

Transmit the following command, data No., and data during a temporary stop to restart.

Command	Data No.	(Note) Data
[A] [0]	[4] [1]	GO□□

Note. "□" indicates a blank.

Transmit the following command, data No., and data during a temporary stop to stop positioning operation and erase the remaining travel distance.

Command	Data No.	(Note) Data
[A] [0]	[4] [1]	CLR□

Note. "□" indicates a blank.

### 12.5.9 Output signal pin on/off (output signal (DO) forced output)

In the test operation mode, the output signal pins can be turned on/off regardless of the servo status. Using command [9] [0], disable the external input signals in advance.

#### (1) Selecting the output signal (DO) forced output in the test operation mode

Transmit command + [8] [B] + data No. [0] [0] + data "0004" to select the output signal (DO) forced output.

0	0	0	4
---	---	---	---

Selection of test operation mode  
4: Output signal (DO) forced output

#### (2) External output signal on/off

Transmit the following communication commands.

Command	Data No.	Set data
[9] [2]	[A] [0]	See below.

b31 ----- b1b0



1: On  
0: Off

Command of each bit is transmitted to the master station as hexadecimal data.

Bit	CN1 connector pin
0	49
1	24
2	23
3	
4	
5	48
6	33
7	

Bit	CN1 connector pin
8	
9	
10	
11	
12	
13	
14	
15	

Bit	CN1 connector pin
16	
17	
18	
19	
20	
21	
22	
23	

Bit	CN1 connector pin
24	
25	
26	
27	
28	
29	
30	
31	

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### (3) Output signal (DO) forced output

Transmit command [8] [B] + data No. [0] [0] + data to stop the output signal (DO) forced output.

Command	Data No.	Transmission data	Selection of test operation mode
[8] [B]	[0] [0]	0000	Test operation mode cancel

### 12.5.10 Alarm history

#### (1) Alarm No. reading

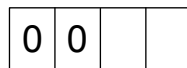
The following shows how to read alarm Nos. which occurred in the past. Alarm Nos. and occurrence times of No. 0 (last alarm) to No. 15 (sixteenth alarm in the past) are read.

##### (a) Transmission

Transmit command [3] [3] + data No. [1] [0] to [1] [F]. Refer to section 12.4.1.

##### (b) Return

Alarm Nos. corresponding to the data No. is provided.



Alarm No. is transferred in hexadecimal.

For example, "0032" means [AL. 32] and "00FF" means [AL. \_\_ ] (no alarm).

#### (2) Alarm occurrence time reading

The following shows how to read alarm occurrence times which occurred in the past.

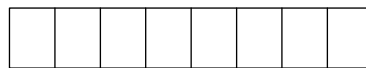
Alarm occurrence time corresponding to the data No. is provided in terms of the total time beginning with operation start, with the minute unit omitted.

##### (a) Transmission

Transmit command [3] [3] + data No. [2] [0] to [2] [F].

Refer to section 12.4.1.

##### (b) Return



The alarm occurrence time is transferred in hexadecimal. Hexadecimal must be converted into decimal.

For example, data "01F5" means that the alarm occurred in 501 hours after starting operation.

#### (3) Clearing the alarm history

Alarm history is cleared.

Transmit command [8] [2] and data No. [2] [0].

Command	Data No.	Data
[8] [2]	[2] [0]	1EA5

## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

### 12.5.11 Current alarm

#### (1) Current alarm reading

The following shows how to read the alarm No. which is occurring currently.

##### (a) Transmission

Transmit command [0] [2] and data No. [0] [0].

Command	Data No.
[0] [2]	[0] [0]

##### (b) Return

The slave station returns the alarm currently occurring.

0	0		
---	---	--	--

Alarm No. is transferred in hexadecimal.

For example, "0032" means [AL. 32] and "00FF" means [AL. \_\_ ] (no alarm).

#### (2) Reading status display at alarm occurrence

The following shows how to read the status display data at alarm occurrence. When the data No. corresponding to the status display item is transmitted, the data value and data processing information will be returned.

##### (a) Transmission

Transmit the command [3] [5] + the data No. corresponding to the status display item to read, [8] [0] to [8] [E] and [A] [0] to [A] [9]. Refer to section 12.4.1.

##### (b) Return

The slave station returns the status display data of requested alarm at occurrence.

0	0																		
---	---	--	--	--	--	--	--	--	--	--	--	--	--	--	--	--	--	--	--

Data 32-bit length (hexadecimal representation)  
(Data conversion is required as indicated in the display type.)

Display type

0: Data must be converted into decimal.

1: Data is used unchanged in hexadecimal.

Decimal point position

0: No decimal point

1: First least significant digit (normally not used)

2: Second least significant digit

3: Third least significant digit

4: Forth least significant digit

5: Fifth least significant digit

6: Sixth least significant digit

#### (3) Current alarm reset

As by the reset (RES) on, reset the servo amplifier alarm to make the servo amplifier ready to operate. After removing the cause of the alarm, reset the alarm with no command entered.

Command	Data No.	Data
[8] [2]	[0] [0]	1EA5

## 12. COMMUNICATION FUNCTION (MITSUBISHI GENERAL-PURPOSE AC SERVO PROTOCOL)

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### 12.5.12 Software version

The following shows how to read the software version of the servo amplifier.

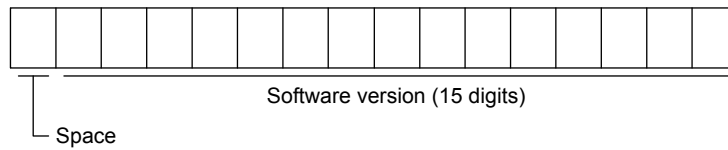
(a) Transmission

Transmit command [0] [2] and data No. [7] [0].

Command	Data No.
[0] [2]	[7] [0]

(b) Return

The slave station returns the requested software version.



# MEMO

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# APPENDIX

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## APPENDIX

### App. 1 Peripheral equipment manufacturer (for reference)

Names given in the table are as of December 2016.

Manufacturer	Contact information
JST	J.S.T. Mfg. Co., Ltd.
3M	3M
Soshin Electric	Soshin Electric Co., Ltd.

### App. 2 Compliance with global standards

#### App. 2.1 About safety

This section explains safety of users and machine operators. Please read the section carefully before mounting the equipment.

##### App. 2.1.1 Professional engineer

Only professional engineers should mount MR-JE servo amplifiers. Here, professional engineers should meet all the conditions below.

- (1) Persons who took a proper training of related work of electrical equipment or persons who can avoid risk based on past experience.
- (2) Persons who have read and familiarized himself/herself with this installation guide and operating manuals for the protective devices (e.g. light curtain) connected to the safety control system.


##### App. 2.1.2 Applications of the devices

MR-JE servo amplifiers comply with the following standards.  
IEC/EN 61800-5-1, IEC/EN 61800-3

# APPENDIX

## App. 2.1.3 Correct use

Use the MR-JE servo amplifiers within specifications. Refer to each instruction manual for specifications such as voltage, temperature, etc. Mitsubishi Electric Co. accepts no claims for liability if the equipment is used in any other way or if modifications are made to the device, even in the context of mounting and installation.

 <b>WARNING</b>	<ul style="list-style-type: none"> <li>● If you need to get close to the moving parts of the machine for inspection or others, ensure safety by confirming the power off, etc. Otherwise, it may cause an accident.</li> </ul>
	<ul style="list-style-type: none"> <li>● It takes 15 minutes maximum for capacitor discharging. Do not touch the unit and terminals immediately after power off.</li> </ul>

### (1) Peripheral device and power wiring

The followings are selected based on IEC/EN 61800-5-1, UL 508C, and CSA C22.2 No. 14.

#### (a) Local wiring

The following table shows the stranded wire sizes [AWG] symbols rated at 75 °C/60 °C.

Servo amplifier (Note 3)	75 °C/60 °C stranded wire [AWG]		
	L1/L2/L3/⊕ (Note 2)	P+/C	U/V/W/⊕ (Note 1, 2)
MR-JE-10_/MR-JE-20_/MR-JE-40_/MR-JE-70_/MR-JE-100_ (T)/ MR-JE-200_/MR-JE-300_	14/14	14/14	14/14
MR-JE-200_ (S)	12/12		

- Note
1. Select wire sizes depending on the rated output of the servo motors. The values in the table are sizes based on rated output of the servo amplifiers.
  2. The following shows the PE terminal specifications of the servo amplifier.  
Screw size: M4  
Tightening torque: 1.2 [N·m]  
Recommended crimp terminals: R2-4 (Manufactured by JST)  
Crimping tool: YPT-60-21 (Manufactured by JST)
  3. "(S)" means 1-phase 200 V AC power input and "(T)" means 3-phase 200 V AC power input in the table.

#### (b) Selection example of MCCB and fuse

Use T class fuses or molded-case circuit breaker (UL 489 Listed MCCB) as the following table. The T class fuses and molded-case circuit breakers in the table are selected examples based on rated I/O of the servo amplifiers. When you select a smaller capacity servo motor to connect it to the servo amplifier, you can also use smaller capacity T class fuses or molded-case circuit breaker than ones in the table. For selecting ones other than Class T fuses and molded-case circuit breakers below, refer to section 11.6.

Servo amplifier (Note)	Molded-case circuit breaker (240 V AC)	Fuse (300 V)
MR-JE-10_/MR-JE-20_/MR-JE-40_/MR-JE-70_ (T)	NF50-SWU-5A (50 A frame 5 A)	10 A
MR-JE-70_ (S)/MR-JE-100_ (T)	NF50-SWU-10A (50 A frame 10 A)	15 A
MR-JE-200_ (T)/MR-JE-300_	NF50-SWU-15A (50 A frame 15 A)	30 A
MR-JE-100_ (S)	NF50-SVFU-15A (50 A frame 15 A)	30 A
MR-JE-200_ (S)	NF50-SVFU-20A (50 A frame 20 A)	40 A

Note. "(S)" means 1-phase 200 V AC power input and "(T)" means 3-phase 200 V AC power input in the table.

## APPENDIX

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### (c) Power supply

This servo amplifier can be supplied from star-connected supply with grounded neutral point of overvoltage category III (overvoltage category II for 1-phase servo amplifiers) set forth in IEC/EN 60664-1. For the interface power supply, use an external 24 V DC power supply with reinforced insulation on I/O terminals.

### (d) Grounding

To prevent an electric shock, always connect the protective earth (PE) terminal (marked ⊕) of the servo amplifier to the protective earth (PE) of the cabinet. Do not connect two grounding cables to the same protective earth (PE) terminal. Always connect cables to the terminals one-to-one. This product can cause a DC current in the protective earthing conductor. To protect direct/indirect contact using an earth-leakage current breaker (RCD), only an RCD of type B can be used for the power supply side of the product.



## (2) EU compliance

The MR-JE servo amplifiers are designed to comply with the following directions to meet requirements for mounting, using, and periodic technical inspections: EMC directive (2014/30/EU), and Low-voltage directive (2014/35/EU).

### (a) EMC requirement

MR-JE servo amplifiers comply with category C3 in accordance with IEC/EN 61800-3. Install an EMC filter and surge protector on the primary side of the servo amplifier. As for I/O signal wires (max. length 10 m) and encoder cables (max. length 50 m), use shielded wires and ground the shields. However, when the encoder cable length is longer than 30 m for MR-JE-70\_ and MR-JE-100\_, set a radio noise filter (FR-BIF) to the input power supply side of the servo amplifier. The following shows recommended products.

EMC filter: Soshin Electric HF3000A-UN series

Surge protector: Okaya Electric Industries RSPD series

Radio noise filter: Mitsubishi Electric FR-BIF

MR-JE Series are not intended to be used on a low-voltage public network which supplies domestic premises; radio frequency interference is expected if used on such a network. The installer shall provide a guide for Installation and use, including recommended mitigation devices. To avoid the risk of crosstalk to signal cables, the installation instructions shall either recommend that the power interface cable be segregated from signal cables.

Use the DC power supply installed with the amplifiers in the same cabinet. Do not connect the other electric devices to the DC power supply.

### (b) For Declaration of Conformity (DoC)

Hereby, MITSUBISHI ELECTRIC EUROPE B.V., declares that the servo amplifiers are in compliance with the necessary requirements and standards (2014/30/EU and 2014/35/EU). For the copy of Declaration of Conformity, contact your local sales office.



## APPENDIX

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### (3) USA/Canada compliance

This servo amplifier is designed in compliance with UL 508C and CSA C22.2 No. 14.

#### (a) Installation

The minimum cabinet size is 150% of MR-JE servo amplifier's volume. Also, design the cabinet so that the ambient temperature in the cabinet is 55 °C or less. The servo amplifier must be installed in the metal cabinet. Additionally, mount the servo amplifier on a cabinet that the protective earth based on the standard of IEC/EN 60204-1 is correctly connected. For environment, the units should be used in open type (UL 50) and overvoltage category shown in table in app. 2.7.1. The servo amplifier needs to be installed at or below of pollution degree 2. For connection, use copper wires.

#### (b) Short-circuit current rating (SCCR)

Suitable For Use On A Circuit Capable Of Delivering Not More Than 100 kA rms Symmetrical Amperes, 500 Volts Maximum.

#### (c) Overload protection characteristics

The MR-JE servo amplifiers have solid-state servo motor overload protection. (It is set on the basis (full load current) of 120% rated current of the servo amplifier.)

#### (d) Over-temperature protection for motor

Motor Over temperature sensing is not provided by the drive.

Integral thermal protection(s) is necessary for motor and refer to app. 2.3 for the proper connection.

#### (e) Branch circuit protection

For installation in United States, branch circuit protection must be provided, in accordance with the National Electrical Code and any applicable local codes.

For installation in Canada, branch circuit protection must be provided, in accordance with the Canada Electrical Code and any applicable provincial codes.

### (4) South Korea compliance

This product complies with the Radio Wave Law (KC mark). Please note the following to use the product.

이 기기는 업무용 (A급) 전자파적합기기로서 판매자 또는 사용자는 이 점을 주의하시기 바라며, 가정외의 지역에서 사용하는 것을 목적으로 합니다.

(The product is for business use (Class A) and meets the electromagnetic compatibility requirements.

The seller and the user must note the above point, and use the product in a place except for home.)

#### App. 2.1.4 General cautions for safety protection and protective measures

Observe the following items to ensure proper use of the MR-JE servo amplifiers.

- (1) For installing systems, only qualified personnel and professional engineers should perform.
- (2) When mounting, installing, and using the MR-JE servo amplifier, always observe standards and directives applicable in the country.

#### App. 2.1.5 Disposal

Disposal of unusable or irreparable devices should always occur in accordance with the applicable country-specific waste disposal regulations. (Example: European Waste 16 02 14)

# APPENDIX


## App. 2.1.6 Lithium battery transportation

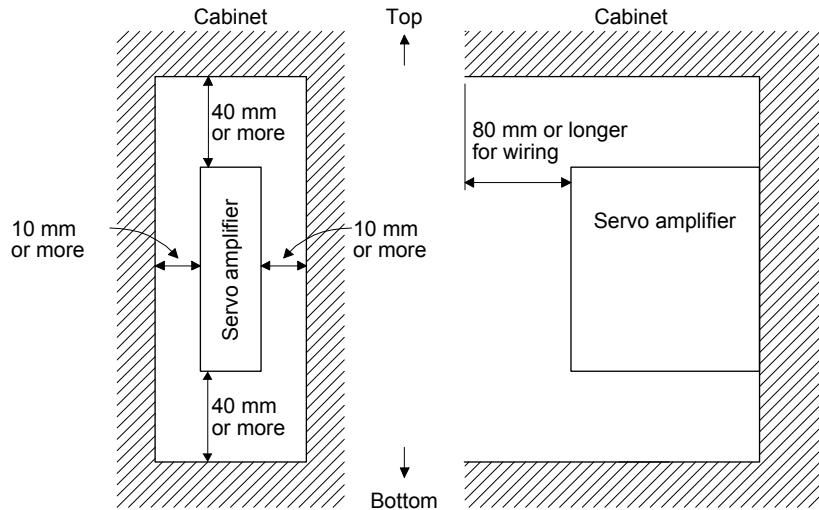
To transport lithium batteries, take actions to comply with the instructions and regulations such as the United Nations (UN), the International Civil Aviation Organization (ICAO), and the International Maritime Organization (IMO).

The batteries (MR-BAT6V1SET-A and MR-BAT6V1) are assembled batteries from two batteries (lithium metal battery CR17335A) which are not subject to the dangerous goods (Class 9) of the UN Recommendations.

## App. 2.2 Mounting/dismounting

### Installation direction and clearances

 <b>CAUTION</b>	● The devices must be installed in the specified direction. Not doing so may cause a malfunction.
	● Mount the servo amplifier on a cabinet which meets IP54 in the correct vertical direction to maintain pollution degree 2.



# APPENDIX

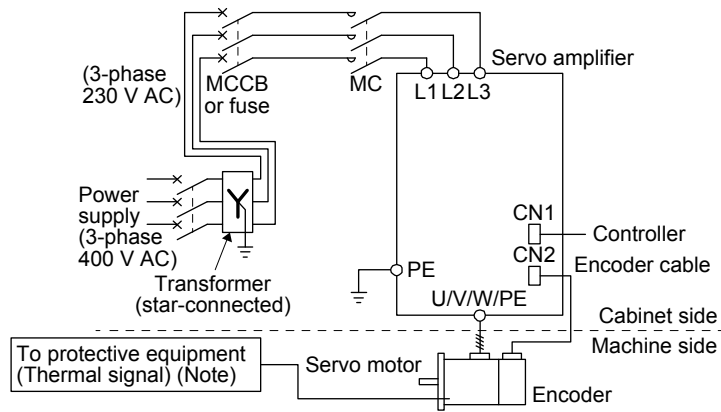
## App. 2.3 Electrical Installation and configuration diagram

**⚠ WARNING** ● Turn off the molded-case circuit breaker (MCCB) to avoid electrical shocks or damages to the product before starting the installation or wiring.

**⚠ CAUTION** ● Connecting a servo motor for different axis to U, V, W, or CN2 of the servo amplifier may cause a malfunction.  
● Securely connect the cables in the specified method and tighten them with the specified torque. Otherwise, the servo motor may operate unexpectedly.

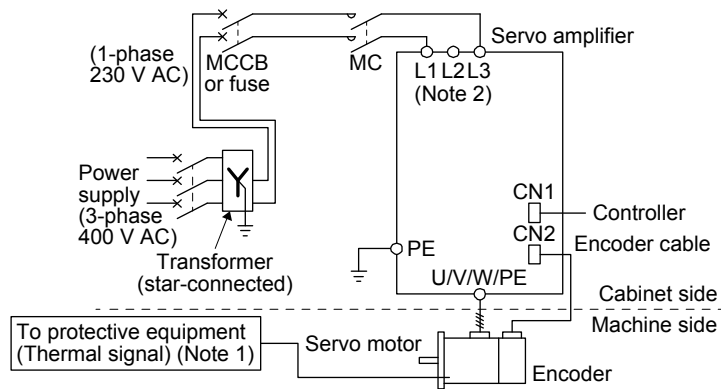
The following shows representative configuration examples to conform to the IEC/EN/UL/CSA standards.

### (1) 3-phase input



Note. Please use a thermal sensor, etc. for thermal protection of the servo motor.

### (2) 1-phase input



- Note 1. Please use a thermal sensor, etc. for thermal protection of the servo motor.  
2. For the MR-JE-200\_ servo amplifiers, connect the power supply to L1 and L2. Leave L3 open.

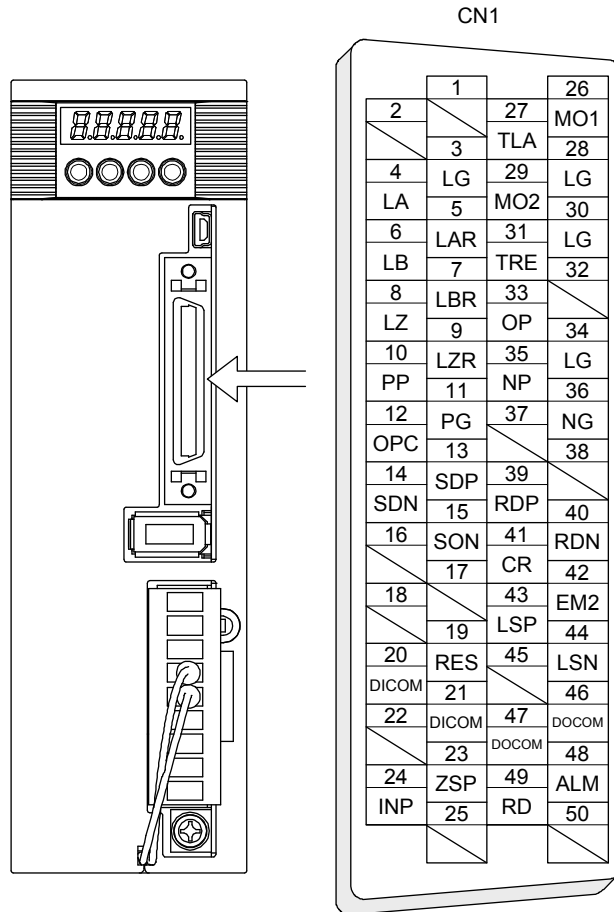
The connectors described by rectangles are safely separated from the main circuits described by circles. Use MR-JE servo amplifiers in combination with HG series or HJ series servo motors.

# APPENDIX

## App. 2.4 Signals

### App. 2.4.1 Signal

The following shows CN1 connector signals of MR-JE-10A as a typical example.



This is in position control mode.

# APPENDIX

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## App. 2.4.2 I/O device

The following shows typical I/O devices of MR-JE-\_A. For the other devices, refer to each servo amplifier instruction manual.

### Input device

Symbol	Device	Connector	Pin No.
SON	Servo-on	CN1	15
RES	Reset		19
CR	Clear		41
EM2	Forced stop 2		42
LSP	Forward rotation stroke end		43
LSN	Reverse rotation stroke end		44

### Output device


Symbol	Device	Connector	Pin No.
ZSP	Zero speed detection	CN1	23
INP	In-position		24
ALM	Malfunction		48
RD	Ready		49

### Power supply

Symbol	Device	Connector	Pin No.
DICOM	Digital I/F power supply input	CN1	20, 21
DOCOM	Digital I/F common		46, 47
SD	Shield		Plate

# APPENDIX

## App. 2.5 Maintenance and service

 **WARNING** ● To avoid an electric shock, only qualified personnel should attempt inspections. For repair and parts replacement, contact your local sales office.

### App. 2.5.1 Inspection items

It is recommended that the following points periodically be checked.

- (1) Check for loose screws on the protective earth (PE) terminal. Retighten any loose screws. (tightening torque: 1.2 N•m)
- (2) Servo motor bearings, brake section, etc. for unusual noise.
- (3) Check the cables and the like for scratches or cracks. Perform periodic inspection according to operating conditions.
- (4) Check that the connectors are securely connected to the servo motor.
- (5) Check that the wires are not coming out from the connector.
- (6) Check for dust accumulation on the servo amplifier.
- (7) Check for unusual noise generated from the servo amplifier.
- (8) Check the servo motor shaft and coupling for connection.
- (9) Make sure that the emergency stop circuit operates properly such that an operation can be stopped immediately and a power is shut off by the emergency stop switch.

### App. 2.5.2 Parts having service lives


Service lives of the following parts are listed below. However, the service lives vary depending on operation and environment. If any fault is found in the parts, they must be replaced immediately regardless of their service lives. For parts replacement, please contact your local sales office.

Part name	Life guideline
Smoothing capacitor	(Note 3) 10 years
Relay	Number of power-on, forced stop, and controller forced stop times: 100,000 times
Cooling fan	50,000 hours to 70,000 hours (7 years to 8 years)
(Note 1) Battery backup time	Approximately 20,000 hours (equipment power supply: off, ambient temperature: 20 °C)
(Note 2) Battery life	5 years from date of manufacture

- Note
1. The time is for using MR-BAT6V1SET-A. For details and other battery backup time, refer to each servo amplifier instruction manual.
  2. Quality of the batteries degrades by the storage condition. The battery life is 5 years from the production date regardless of the connection status.
  3. The characteristic of smoothing capacitor is deteriorated due to ripple currents, etc. The life of the capacitor greatly depends on ambient temperature and operating conditions. The capacitor will reach the end of its life in 10 years of continuous operation in normal air-conditioned environment (Ambient temperature of 40 °C or less).

# APPENDIX

## App. 2.6 Transportation and storage

 <b>CAUTION</b>	<ul style="list-style-type: none"> <li>● Transport the products correctly according to their mass.</li> <li>● Stacking in excess of the limited number of product packages is not allowed.</li> <li>● For detailed information on the battery's transportation and handing refer to each servo amplifier instruction manual.</li> <li>● Install the product in a load-bearing place of servo amplifier and servo motor in accordance with instruction manual.</li> <li>● Do not get on or put heavy load on the equipment.</li> <li>● Do not hold the lead of the built-in regenerative resistor when carrying the servo amplifier.</li> </ul>
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When you keep or use it, please fulfill the following environment.

Item		Environment
Ambient temperature	Operation [°C]	0 to 55 Class 3K3 (IEC/EN 60721-3-3)
	Transportation (Note) [°C]	-20 to 65 Class 2K4 (IEC/EN 60721-3-2)
	Storage (Note) [°C]	-20 to 65 Class 1K4 (IEC/EN 60721-3-1)
Ambient humidity	Operation, transportation, storage	5 %RH to 90 %RH
Vibration resistance	Test condition	10 Hz to 57 Hz with constant amplitude of 0.075 mm 57 Hz to 150 Hz with constant acceleration of 9.8 m/s <sup>2</sup> to IEC/EN 61800-5-1 (Test Fc of IEC 60068-2-6)
	Operation	5.9 m/s <sup>2</sup>
	Transportation (Note)	Class 2M3 (IEC/EN 60721-3-2)
	Storage	Class 1M2 (IEC/EN 60721-3-2)
Pollution degree		2
IP rating		IP20 (IEC/EN 60529)
		Open type (UL 50)
Altitude	Operation, storage	Max. 1000 m above sea level
	Transportation	Max. 10000 m above sea level

Note. In regular transport packaging

# APPENDIX

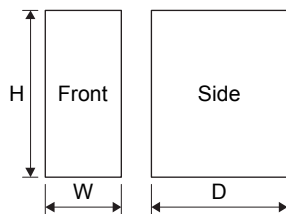
## App. 2.7 Technical data

### App. 2.7.1 MR-JE servo amplifier

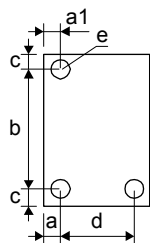
Item		MR-JE-10_/MR-JE-20_/MR-JE-40_/MR-JE-70_/MR-JE-100_/MR-JE-200_	MR-JE-300_
Power supply	Line voltage	3-phase or 1-phase 200 V AC to 240 V AC, 50 Hz /60 Hz	3-phase 200 V AC to 240 V AC, 50 Hz/60 Hz
	Interface (SELV)	24 V DC, (required current capacity: MR-JE-_A(S), 300 mA; MR-JE-_B, 300 mA; MR-JE-_C, 300 mA) (Note)	
Control method		Sine-wave PWM control, current control method	
Pollution degree		2 (IEC/EN 60664-1)	
Overvoltage category		1-phase 200 V AC: II (IEC/EN 60664-1), 3-phase 200 V AC: III (IEC/EN 60664-1)	
Protective class		I (IEC/EN 61800-5-1)	
Short-circuit current rating (SCCR)		100 kA	

Note. This will be 100 mA for the MR-JE-\_B servo amplifiers manufactured in April 2016 or before (May 2016 or before for amplifiers manufactured in China).

### App. 2.7.2 Dimensions/mounting hole process drawing



Servo amplifier	Variable dimensions [mm]			Mass [kg]
	W	H	D	
MR-JE-10_/MR-JE-20_/MR-JE-40_	50	168	135	0.8
MR-JE-70_/MR-JE-100_	70	168	185	1.5
MR-JE-200_/MR-JE-300_	90	168	195	2.1



Servo amplifier	Variable dimensions [mm]					Screw size e
	a	a1	b	c	d	
MR-JE-10_/MR-JE-20_/MR-JE-40_	6	6	156 ± 0.5	6		M5
MR-JE-70_/MR-JE-100_	22	22	156 ± 0.5	6	42 ± 0.3	M5
MR-JE-200_/MR-JE-300_	6	45	156 ± 0.5	6	78 ± 0.3	M5



# APPENDIX

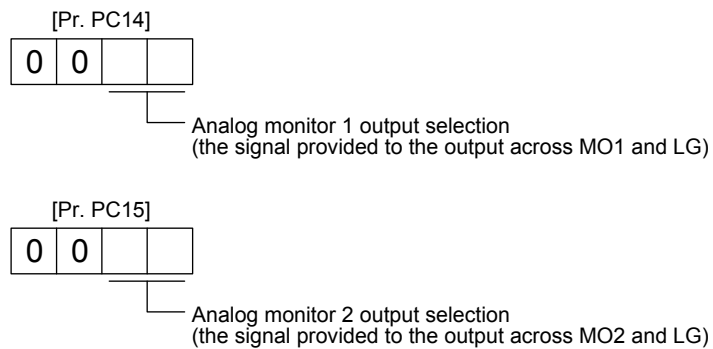
## App. 3 Analog monitor

POINT	
●A voltage of analog monitor output may be irregular at power-on.	

The servo status can be outputted to two channels in terms of voltage.

### (1) Setting

Change the following digits of [Pr. PC14] and [Pr. PC15].



[Pr. PC39] and [Pr. PC40] can be used to set the offset voltages to the analog output voltages. Setting value is -9999 mV to 9999 mV.

Parameter	Description	Setting range [mV]
PC39	Set the offset voltage of MO1 (Analog monitor 1).	-9999 to 9999
PC40	Set the offset voltage of MO2 (Analog monitor 2).	

# APPENDIX

## Setting

The servo amplifier is factory-set to output the servo motor speed to MO1 (Analog monitor 1) and the torque to MO2 (Analog monitor 2). The setting can be changed as listed below by setting the [Pr. PC14] and [Pr. PC15] value.

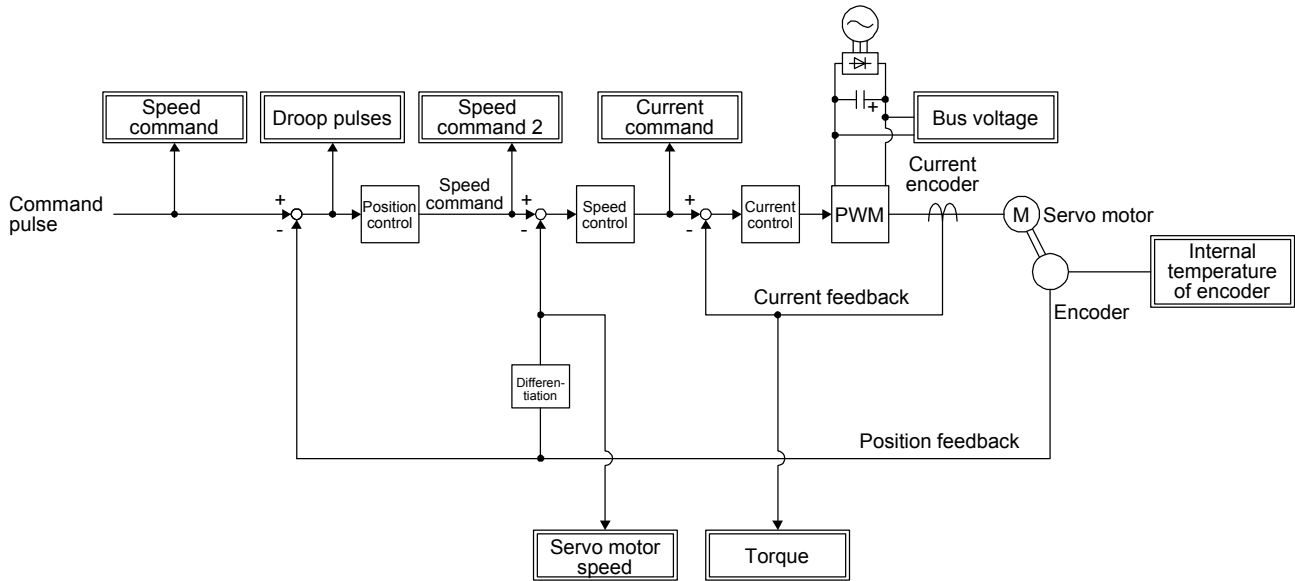
Refer to (3) for the detection point.

Setting value	Output item	Description	Setting value	Output item	Description
00	Servo motor speed (Note 4)		01	Torque	
02	Servo motor speed (Note 4)		03	Torque	
04	Current command		05	The command pulse frequency ( $\pm 10$ V/ $\pm 4$ Mpulses/s)	
06	Servo motor-side droop pulses (Note 1, 2, 3) ( $\pm 10$ V/100 pulses)		07	Servo motor-side droop pulses (Note 1, 2, 3) ( $\pm 10$ V/1000 pulses)	
08	Servo motor-side droop pulses (Note 1, 2, 3) ( $\pm 10$ V/10000 pulses)		09	Servo motor-side droop pulses (Note 1, 2, 3) ( $\pm 10$ V/100000 pulses)	
0D	Bus voltage		0E	Speed command 2 (Note 2, 4)	
17	Internal temperature of encoder ( $\pm 10$ V/ $\pm 128$ °C)				

# APPENDIX

- Note
1. Encoder pulse unit
  2. This cannot be used in the torque control mode.
  3. This cannot be used in the speed control mode.
  4. The maximum speed of the HF-KN series servo motor is 4500 r/min and that of the HG-KN series is 5000 r/min. Please watch out when using an HG-KN series servo motor as a replacement for the HF-KN series servo motor because HG-KN series output 8 V at 5000 r/min.  
HG-KN series servo motors output 8 V at 6000 r/min when you set "\_\_\_1" in [Pr. PA28] to change the maximum speed to 6000 r/min.

## (3) Analog monitor block diagram



# APPENDIX

## App. 4 Low-voltage directive

MR-JE series servo amplifiers are certificated in compliance with Low-voltage directive. The following shows a certificate by the Certification Body.

<b>Zertifikat</b>		<b>Certificate</b>			
<b>Zertifikat Nr. Certificate No.</b>	<b>Blatt Page</b>				
R 50244051	0001				
<b>Ihr Zeichen Client Reference</b>	<b>Unser Zeichen Our Reference</b>	<b>Ausstellungsdatum</b>	<b>Date of Issue (day/mo/yr)</b>		
T.E.	ZO-HIM- 12311510 001	11.01.2013			
<b>Genehmigungsinhaber License Holder</b>		<b>Fertigungsstätte Manufacturing Plant</b>			
Mitsubishi Electric Corp. Nagoya Works 1-14, Yada-minami 5-chome Higashi-ku, Nagoya-shi, Aichi 461-8670 JAPAN		Mitsubishi Electric Corp. Nagoya Works 1-14, Yada-minami 5-chome Higashi-ku, Nagoya-shi, Aichi 461-8670 JAPAN			
<b>Prüfzeichen Test Mark</b>		<b>Geprüft nach Tested acc. to</b>			
		EN 61800-5-1:2007 IEC 61800-5-1:2007			
<b>Zertifiziertes Produkt (Geräteidentifikation)</b>		<b>Lizenzentgelte - Einheit</b>			
<b>Certified Product (Product Identification)</b>		<b>License Fee - Unit</b>			
<b>Control Unit Servo Drive Unit</b>					
Type Designation	: MR-JE-uvw-xyz			5	
	: u, v, w, x, y, z = (see Appendix 1)			6	
Rated Voltage	: 3AC 200-240V, 50/60Hz or AC 200-240V, 50/60Hz				
Rated Current	: (see Appendix 1)				
Protection Class	: I				
Rated Output Values	: 3AC 170V 360Hz				
Ambient Temperature	: 0°C to 55°C				
Overvoltage Category	: III (3AC200-240V) or II (AC200-240V)				
Pollution Degree	: 2				
<b>Remark:</b> Power circuits and secondary control circuits provide protective separation. The unit must be installed in accordance with the manufacturer's instructions.					
				11	
<b>ANLAGE (Appendix): 1</b>					
<small>Dem Zertifikat liegt unsere Prüf- und Zertifizierungsordnung zugrunde und es bestätigt die Konformität des Produktes mit den oben genannten Standards und Prüfgrundlagen. Zusätzliche Anforderungen in Ländern, in denen das Produkt in Verkehr gebracht werden soll, müssen zusätzlich betrachtet werden. Die Herstellung des zertifizierten Produktes wird überwacht. This certificate is based on our Testing and Certification Regulation and states the conformity of the product with the standards and testing requirements as indicated above. Any additional requirements in countries where the product is going to be marketed have to be considered additionally. The manufacturing of the certified product is subject to surveillance.</small>					
<b>TÜV Rheinland LGA Products GmbH - Tillystraße 2 - 90431 Nürnberg</b>					
Tel: (+49/221)8 06 - 13 71 e-mail: cert-validity@de.tuv.com					
Fax: (+49/221)8 06 - 39 35 http://www.tuv.com/safety					
				 <b>Dipl.-Ing. (FH) M. Geiser</b>	
<small>10/2004/08 TÜV, TÜV und TUV are registered trademarks. Uniform and application require prior approval.</small>					

Supplementation: Refer to section 1.6 (2) for the models shown in "(see app. 1)".

# APPENDIX

## App. 5 Using HF-KN series and HF-SN series servo motors

**POINT**

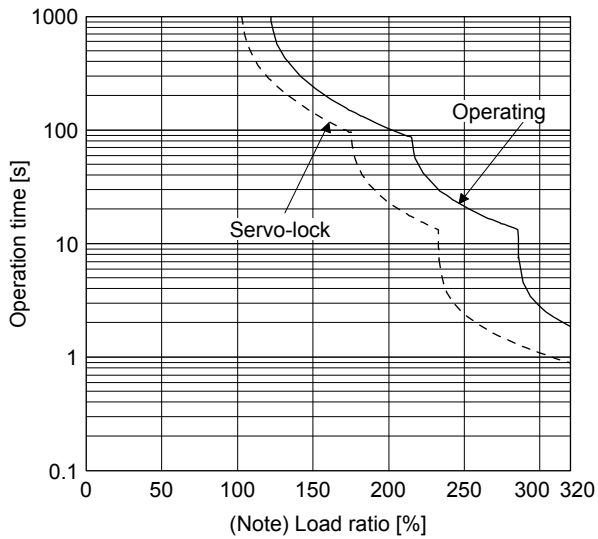
● For HF-KN series and HF-SN series servo motors, refer to "HF-KN/HF-SN Servo Motor Instruction Manual" (SH(NA)030123).

### App. 5.1 Combinations of servo amplifiers and servo motors

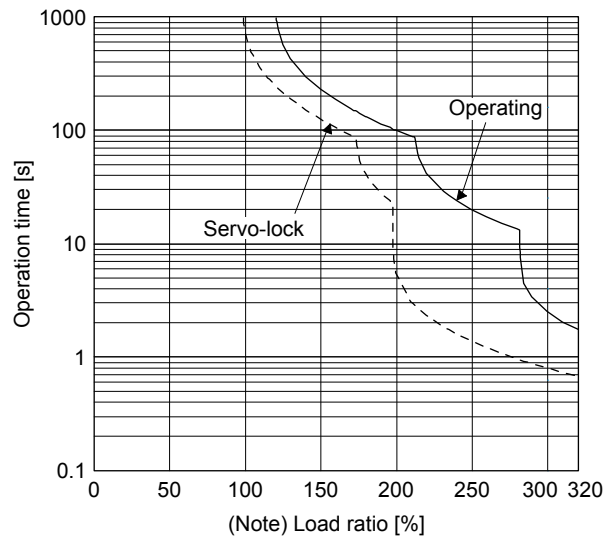
Servo amplifier	Servo motor
MR-JE-10A	HF-KN13_
MR-JE-20A	HF-KN23_
MR-JE-40A	HF-KN43_
MR-JE-70A	HF-KN73_ HF-SN52_
MR-JE-100A	HF-SN102_
MR-JE-200A	HF-SN152_ HF-SN202_
MR-JE-300A	HF-SN302_

### App. 5.2 Characteristics

#### App. 5.2.1 Overload protection characteristics



HF-KN13\_, HF-KN23\_, HF-KN43\_  
HF-KN73\_, HF-SN52\_, HF-SN102\_



HF-SN152\_, HF-SN202\_, HF-SN302\_

Note. If operation that generates torque more than 100% of the rating is performed with an abnormally high frequency in a servo motor stop status (servo-lock status) or in a 30 r/min or less low-speed operation status, the servo amplifier may malfunction regardless of the electronic thermal protection.

# APPENDIX

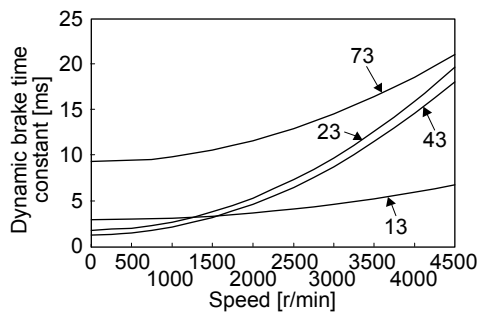
## App. 5.2.2 Power supply capacity and generated loss

Servo amplifier	Servo motor	(Note 1) Power supply capacity [kVA]	(Note 2) Servo amplifier-generated heat [W]		Area required for heat dissipation [m <sup>2</sup> ]
			At rated output	With servo-off	
MR-JE-10A	HF-KN13_	0.3	25	15	0.5
MR-JE-20A	HF-KN23_	0.5	25	15	0.5
MR-JE-40A	HF-KN43_	0.9	35	15	0.7
MR-JE-70A	HF-KN73_	1.3	50	15	1.0
	HF-SN52_	1.0	40	15	0.8
MR-JE-100A	HF-SN102_	1.7	50	15	1.0
MR-JE-200A	HF-SN152_	2.5	90	20	1.8
	HF-SN202_	3.5			
MR-JE-300A	HF-SN302_	4.8	120	20	2.4

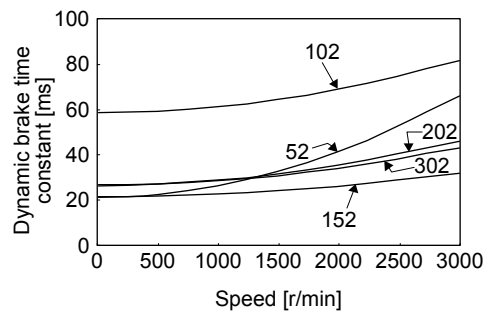
- Note 1. Note that the power supply capacity will vary according to the power supply impedance. This value is applicable when the power factor improving AC reactor is not used.
2. Heat generated during regeneration is not included in the servo amplifier-generated heat. To calculate heat generated by the regenerative option, refer to section 11.2.

## App. 5.2.3 Dynamic brake characteristics

### (1) Dynamic brake time constant



HF-KN series



HF-SN series

### (2) Permissible load to motor inertia when the dynamic brake is used

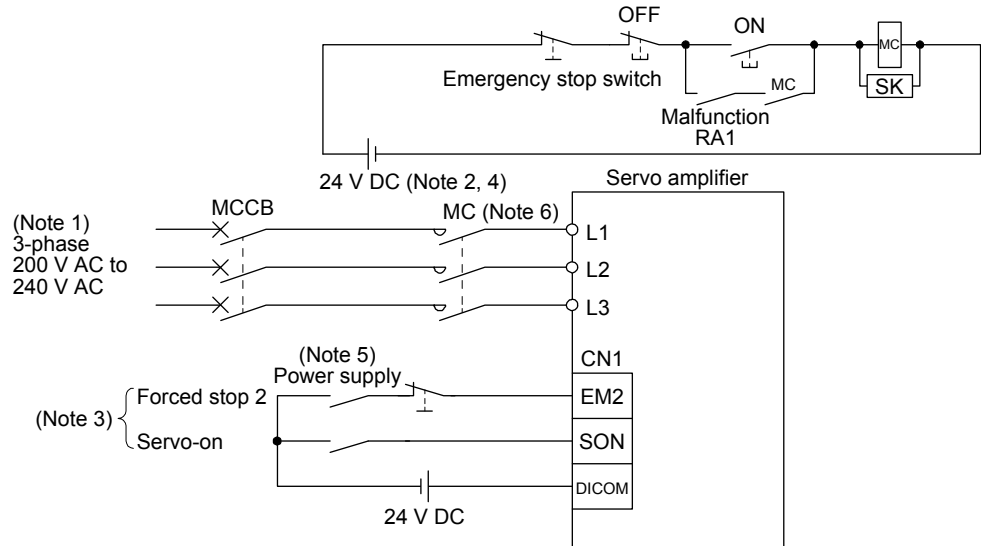
Servo motor	Permissible load to motor inertia ratio [multiplier]
HF-KN13_	30
HF-KN23_	
HF-KN43_	
HF-KN73_	
HF-SN52_	
HF-SN102_	
HF-SN152_	
HF-SN202_	16
HF-SN302_	

# APPENDIX

## App. 6 When turning on or off the input power supply with DC power supply

### App. 6.1 Connection example

For the signals or wiring that are not described in this section, refer to section 3.1.



- Note 1. When using a power supply of 1-phase 200 V AC to 240 V AC for MR-JE-10A to MR-JE-100A, connect the power supply to L1 and L3. Leave L2 open. When using a power supply of 1-phase 200 V AC to 240 V AC for MR-JE-200A, connect the power supply to L1 and L2. Leave L3 open. MR-JE-300A cannot be used with 1-phase 200 V AC to 240 V AC power supply.
- Note 2. Do not use the 24 V DC interface power supply for magnetic contactor. Always use the power supply designed exclusively for the magnetic contactor.
- Note 3. This diagram shows sink I/O interface. For source I/O interface, refer to section 3.9.3.
- Note 4. Controlling the on switch or off switch with DC power supply satisfies the requirements of IEC/EN 60204-1.
- Note 5. Configure a circuit to turn off EM2 when the power is turned off to prevent an unexpected restart of the servo amplifier.
- Note 6. Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less. Depending on the power supply voltage and operation pattern, bus voltage can decrease. This can shift the mode to the dynamic brake deceleration during forced stop deceleration. When dynamic brake deceleration is not required, delay the time to turn off the magnetic contactor.

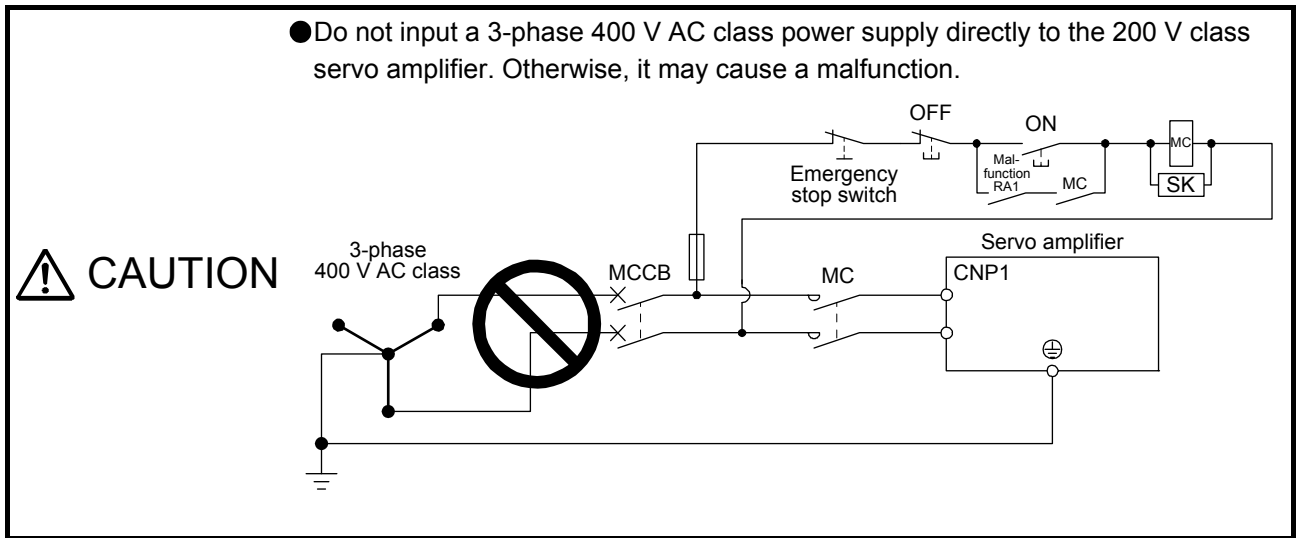
### App. 6.2 Magnetic contactor

Use a magnetic contactor with an operation delay time (interval between current being applied to the coil until closure of contacts) of 80 ms or less.

Servo amplifier	Magnetic contactor
MR-JE-10A	SD-N11
MR-JE-20A	
MR-JE-40A	
MR-JE-70A	
MR-JE-100A	
MR-JE-200A	SD-N21
MR-JE-300A	

# APPENDIX

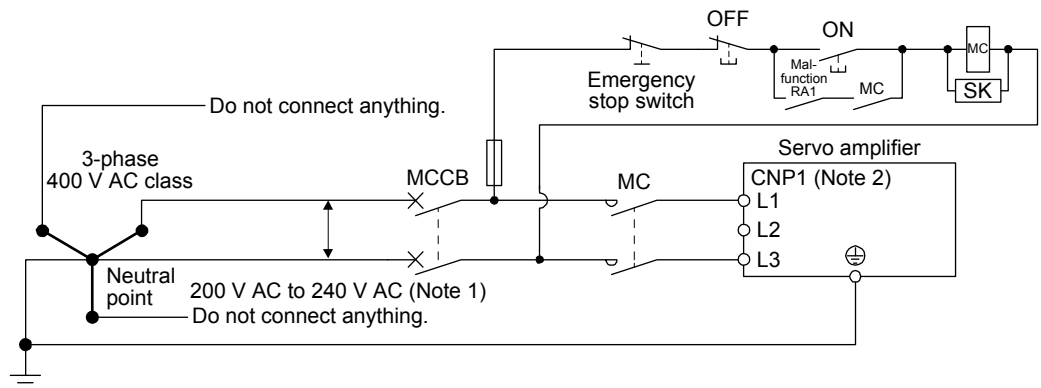
## App. 7 Using the neutral point of a 3-phase 400 V AC class power supply for inputting a 1-phase 200 V AC class power supply



You can use the neutral point of a 3-phase 400 V AC class power supply to input a 1-phase 200 V AC class power supply to the servo amplifier.

If necessary, use a step-down transformer to decrease the power supply voltage to 200 V AC to 240 V AC.

(1) For MR-JE-10A to MR-JE-100A



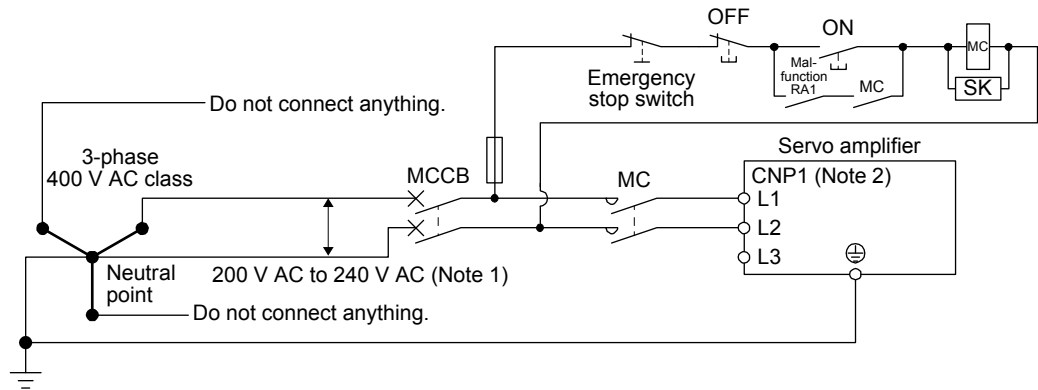
Note 1. If necessary, use a step-down transformer to decrease the power supply voltage to 200 V AC to 240 V AC.

Note 2. Connect the 1-phase 200 V AC to 240 V AC power supply to L1 and L3. One of the connecting destinations is different from MR-JE-200A servo amplifier's.



# APPENDIX

(2) For MR-JE-200A



- Note 1. If necessary, use a step-down transformer to decrease the power supply voltage to 200 V AC to 240 V AC.
- Note 2. Connect the 1-phase 200 V AC to 240 V AC power supply to L1 and L2. One of the connecting destinations is different from MR-JE-100A or less servo amplifier's.

# APPENDIX

## App. 8 Status of general-purpose AC servo products for compliance with the China RoHS directive





### (1) Summary

The China RoHS directive: 电子信息产品污染控制管理办法 (Management Methods for Controlling Pollution by Electronic Information Products) came into effect on March 1, 2007. The China RoHS directive was replaced by the following China RoHS directive: 电器电子产品有害物质限制使用管理办法 (Management Methods for the Restriction of the Use of Hazardous Substances in Electrical and Electronic Products). The succeeding China RoHS directive has been in effect since July 1, 2016. The China RoHS directive restricts the use of six hazardous substances (lead, mercury, cadmium, hexavalent chromium, polybrominated biphenyls (PBB), and polybrominated diphenyl ethers (PBDE)) and other hazardous substances specified by the State (currently no applicable substances). The EU RoHS directive (2011/65/EU) also restricts the use of the above six hazardous substances.

### (2) Status of our products for compliance with the China RoHS directive

The following tables show the content of six hazardous substances in our products and Environment-Friendly Use Period marks. Table app. 1 is created based on the standard SJ/T11364.

Table app. 1 Names and the content of hazardous substances in the products

Substance name Threshold standard		Hazardous substance (Note 1)						Environment-Friendly Use Period mark (Note 2)	Remark
		Lead (Pb)	Mercury (Hg)	Cadmium (Cd)	Hexavalent chromium (Cr(VI))	PBB	PBDE		
Part name		Threshold of cadmium: 0.01 wt% (100 ppm), Threshold of substances other than cadmium: 0.1 wt% (1000 ppm)							
Servo amplifier	Mounting board	×	○	○	○	○	○		/
	Heat sink	×	○	○	○	○	○		
	Resin cabinet	○	○	○	○	○	○		
	Plate and screw	○	○	○	○	○	○		
Servo motor	Bracket	×	○	○	○	○	○		/
	Mounting board	×	○	○	○	○	○		
	Resin cabinet	○	○	○	○	○	○		
	Core and cable	○	○	○	○	○	○		
Cable product	Cable	○	○	○	○	○	○		Including connector set
	Connector	○	○	○	○	○	○		
Optional unit	Mounting board	×	○	○	○	○	○		/
	Resin cabinet	○	○	○	○	○	○		
	Plate and screw	○	○	○	○	○	○		

Note 1. ○: Indicates that said hazardous substance contained in all of the homogeneous materials for this part is below the limit requirement of GB/T26572.

×: Indicates that said hazardous substance contained in at least one of the homogeneous materials for this part is above the limit requirement of GB/T26572.

2. Indications based on "Marking for the restriction of the use of hazardous substances in electrical and electronic product" [SJ/T11364-2014]



Indicates that a certain hazardous substance is contained in the product manufactured or sold in China. Observe safety and usage precautions for the product, and use it within a limited number of years from the production date. Thereby, any of the hazardous substances in the product does not cause environmental pollution, or seriously affect human health or property.



Indicates that no certain hazardous substance is contained in the product.

# APPENDIX

### (3) Difference between the China RoHS directive and the EU RoHS directive

The China RoHS directive allows no restriction exemption unlike the EU RoHS directive. Although a product complies with the EU RoHS directive, a hazardous substance in the product may be considered to be above the limit requirement (marked "x") in the China RoHS directive.

The following shows some restriction exemptions and their examples according to the EU RoHS directive.

- Lead as an alloying element in steel for machining purposes and in galvanized steel containing up to 0.35% lead by weight, lead as an alloying element in aluminum containing up to 0.4% lead by weight, and copper alloy containing up to 4% lead by weight, e.g. brass-made insert nuts
- Lead in high melting temperature type solders (i.e. lead-based alloys containing 85% by weight or more lead)
- Electrical and electronic components containing lead in a glass or ceramic other than dielectric ceramic in capacitors, e.g. piezoelectric devices
- Electrical and electronic components containing lead in a glass or ceramic matrix compound, e.g. chip resistors

### (4) Status of our products for compliance with the China RoHS directive (Chinese)

The following shows Table app. 1 in Chinese according to "Management Methods for the Restriction of the Use of Hazardous Substances in Electrical and Electronic Products".

表附. 2 产品中所含有害物质的名称及含量

部件名称	物质名称 阈值 基准	有害物质 (注1)						环境保护 使用期限标识 (注2)	备注
		铅 (Pb)	汞 (Hg)	镉 (Cd)	六价铬 (Cr(VI))	PBB	PBDE		
		阈值: 镉: 0.01wt%(100ppm)、 镉以外: 0.1wt%(1000ppm)、							
伺服放大器 伺服系统 控制器	电路板组件	x	○	○	○	○	○		/
	散热片	x	○	○	○	○	○		
	树脂壳体	○	○	○	○	○	○		
	金属板、螺丝	○	○	○	○	○	○		
伺服电机	托架	x	○	○	○	○	○		/
	电路板组件	x	○	○	○	○	○		
	树脂壳体	○	○	○	○	○	○		
	铁心、电线	○	○	○	○	○	○		
电缆 加工品	电线	○	○	○	○	○	○		包括连接器组件
	连接器	○	○	○	○	○	○		
选件 模块	电路板组件	x	○	○	○	○	○		/
	树脂壳体	○	○	○	○	○	○		
	金属板、螺丝	○	○	○	○	○	○		

注 1. ○: 表示该有害物质在该部件所有均质材料中的含量均在GB/T26572规定的限量要求以下。  
x: 表示该有害物质在该部件的至少一种均质材料中的含量超出GB/T26572规定的限量要求。

2. 根据“电子电气产品有害物质限制使用标识要求”、[SJ/T11364-2014]的表示



该标志表示在中国制造/销售的产品中含有特定有害物质。

只要遵守本产品的安全及使用方面的注意事项，从生产日算起的环保使用期限内不会造成环境污染或对人体、财产产生深刻的影响。



该标志表示制造的产品中不含有特定有害物质。

REVISIONS

\*The manual number is given on the bottom left of the back cover.

Revision Date	*Manual Number	Revision	
May. 2013	SH(NA)030128ENG-A	First edition	
Jul. 2013	SH(NA)030128ENG-B	4. Additional instructions (3) Transportation and installation Section 1.3 Section 1.6 Chapter 2 Chapter 3 Section 3.2.1 Section 3.4 Section 3.5 Section 3.6.1 Section 3.9.1 Section 3.9.2 Section 3.9.3 Section 5.2.1 Section 11.3 Section 11.6 App. 2	Partially changed.  Partially changed. Partially changed. CAUTION is partially changed. CAUTION is partially changed. Partially changed. Partially changed. Partially changed. Partially changed. Partially changed. Partially changed. Partially deleted. Partially added and partially changed in Pr. PA13. Partially changed. Partially changed. Partially changed.
Jan. 2014	SH(NA)030128ENG-C	RS-422 function is added. Section 1.2 Section 1.3 Section 1.5 Section 1.7.1 Section 3.2.1 Section 3.2.2 Section 3.2.3 Section 3.3.2 Section 3.4 Section 3.5 Section 3.9.1 Section 3.10.1 Section 3.10.2 Section 5.1.3 Section 5.2.1 Section 6.2 Section 7.1.1 Section 7.1.3 Section 7.1.4 Section 7.2.3 Section 7.3 Chapter 8 Section 8.1 Section 8.2 Section 8.3 Section 11.3 Section 11.4.1 Section 11.4.2 Section 11.4.3 Section 11.6 Section 11.9 Section 11.11	The diagram is partially changed. Partially changed. Added. Partially changed. Note is added. Note is added. Note is added. Partially changed. The table is partially changed. RS-422 communication is added. The diagram is partially changed. Partially changed. Partially changed. PC20 and PC21 are added. Partially changed. POINT is added. Partially changed. Partially changed. The sentence is added. Partially changed. The sentence is added. POINT is added. Partially changed. POINT is added. Partially changed. POINT is added. The diagram is partially changed. Partially changed. Partially changed. Added. The table is changed. Partially changed. Partially changed.

Revision Date	*Manual Number	Revision	
Jan. 2014	SH(NA)030128ENG-C	Chapter 12 App. 2.1.3 App. 2.1.4 App. 2.7.1	Added. Partially changed. Partially changed. Partially changed.
Oct. 2014	SH(NA)030128ENG-D	Compatible with HG-KN series/HG-SN series servo motors Safety Instructions 2.To prevent fire, note the following 4. Additional instructions (6) Maintenance, inspection and parts replacement «About the manual» Section 1.3 Section 1.4 Section 1.6 Section 3.1 Section 3.2.1 (1) Section 3.2.1 (2) Section 3.2.2 Section 3.2.3 Section 3.3.3 Section 3.10.1  Section 3.10.2 Section 4.5.4 Section 4.5.5 Section 5.2.3 Section 7.1.1 Section 7.1.3 Section 7.1.5 Section 7.2.3 Section 7.2.4 Section 7.3.1 Chapter 8 Section 8.2 Section 8.3 Section 10.3 Section 10.3.1 Section 10.3.2 Section 10.5 Section 11.1.1 Section 11.4.2 Section 11.5 Section 11.6 Section 11.10 Section 12.1.1 App. 1 App. 2 App. 3 App. 5	Partially changed.  Partially changed. Partially added.  Partially changed. Note 5 is added. Servo motor series are changed to HG-KN/HG-SN. Partially changed. Partially changed. Partially changed. Partially changed. Partially changed. Partially changed. Partially added. CAUTION is partially added. POINT is partially changed. Partially changed. Partially changed. Partially changed. [Pr. PC14] is partially changed. Partially changed. POINT is added. Partially added and partially changed. Partially changed. Partially changed. Partially changed. POINT is partially added. Partially changed. POINT is partially changed. POINT is partially added. Partially changed. Partially changed. POINT is added. Partially changed. Partially changed. Partially changed. CAUTION is newly added. Partially changed. Partially changed. Partially changed. Partially changed. Partially added. Partially changed. Partially added. Newly added.
Apr. 2015	SH(NA)030128ENG-E	1-phase 200 V AC (to 2 kW) is added. Source pulse input is added. RS-422 is changed to RS-422/RS-485. 1. To prevent electric shock, note the following.	An item is deleted.

Revision Date	*Manual Number	Revision
Apr. 2015	SH(NA)030128ENG-E	<p>2. To prevent fire, note the following. The content is changed.</p> <p>4. Additional instructions The sentences are changed.</p> <p>4. Additional instructions (6) An item is added.</p> <p>General instruction</p> <p>Relevant manuals The content is added.</p> <p>Section 1.3 The content of the table is changed and added. Note is added.</p> <p>Section 1.4 The content of the table is changed.</p> <p>Section 1.5 The content of the table is changed and added.</p> <p>Section 1.6 (1) The diagram is changed.</p> <p>Section 2.1 (2) The content of POINT is changed.</p> <p>Section 3.1 CAUTION is added. The content of POINT is changed.</p> <p>Section 3.1 (1) The diagram is changed.</p> <p>Section 3.1 (2) The content of POINT is changed.</p> <p>Section 3.1 (3) The title is changed.</p> <p>Section 3.1 (4) Newly added.</p> <p>Section 3.2.2 (1) The diagram is changed. Note is deleted.</p> <p>Section 3.2.2 (2) The diagram is changed.</p> <p>Section 3.2.3 (1) The diagram is changed. Note is deleted.</p> <p>Section 3.2.3 (2) The diagram is changed.</p> <p>Section 3.3.1 The content of the table is changed.</p> <p>Section 3.3.3 (2) (a) The sentences are changed.</p> <p>Section 3.4 The content of the table is changed. Note is added. POINT is added.</p> <p>Section 3.5 (2) The content of the table is changed.</p> <p>Section 3.5 (4) The title is changed.</p> <p>Section 3.6.1 (1) (b) 1) The diagram is changed.</p> <p>Section 3.9.1 The diagram is changed. The diagram of Note 2 is changed.</p> <p>Section 3.9.2 The diagram is added.</p> <p>Section 3.9.3 (1) The diagram is added.</p> <p>Section 3.9.3 (3) Newly added.</p> <p>Section 3.10.1 The sentences of CAUTION are changed.</p> <p>Section 4.5.4 The table is changed.</p> <p>Section 4.5.7 (2) The diagram is changed. Note is added.</p> <p>Section 4.5.7 (2) (a) The content of the table is changed.</p> <p>Section 5.1 Sentences of POINT is changed. Note is added.</p> <p>Section 5.1.3 [Pr. PC73] is added.</p> <p>Section 5.1.4 [Pr. PD43] to [Pr. PD46] are added.</p> <p>Section 5.1.6 The name of [Pr. PF25] is changed.</p> <p>Section 5.2.1 The sentences of [Pr. PA20] and [Pr. PA26] are changed.</p> <p>Section 5.2.2 The contents of [Pr. PB25] and [Pr. PB26] are changed.</p> <p>Section 5.2.3 [Pr. PC27] and [Pr. PC73] are added. Sentences of [Pr. PC43] is changed. The content of [Pr. PC60] is added.</p> <p>Section 5.2.4 [Pr. PD43] to [Pr. PC46] are added.</p> <p>Section 5.2.6 [Pr. PF09] is added. The content of [Pr. PF25] is changed.</p> <p>Section 7.2.3 (1) (a) The diagram is changed.</p> <p>Section 7.2.4 (3) Newly added.</p> <p>Section 7.3.2 Sentences are changed. Sentences of POINT are changed.</p> <p>Section 7.4 Newly added.</p> <p>Chapter 8 The content is changed.</p> <p>Section 10.1 The sentences are changed.</p> <p>Section 11.2.4 (1) The diagram is changed. Note is added.</p> <p>Section 11.4.2 (1) The content is changed.</p> <p>Section 11.5 The content of table 11.1 is changed.</p>

Revision Date	*Manual Number	Revision	
Apr. 2015	SH(NA)030128ENG-E	Section 11.6 Section 11.7 (1) Section 11.7 (2) Section 11.11 (2) App. 2 App. 5 App. 6	CAUTION is added. Table is changed. Note is added. The sentences are deleted. The diagram is changed. The table is changed. The diagram is changed. The content is changed. POINT is added. Newly added.
Aug. 2015	SH(NA)030128ENG-F	The content of one-touch tuning is changed. Section 3.4 Section 3.5 Section 3.6.1 Section 4.5.7 Section 5.2.2 Section 5.2.3  Section 6.2 Section 7.1.1 Section 8.2 Section 8.3 Section 11.4.2	Note is partially changed. Partially changed. CAUTION is added. Partially changed. The content of [Pr. PB06] is added. The content of [Pr. PC03] is changed. The content of [Pr. PC35] is added. The content of [Pr. PC51] is added. The content is changed. Partially changed. Partially changed. Partially changed. Partially changed.
Apr. 2016	SH(NA)030128ENG-G	The adaptive filter II is improved, and the lost motion compensation function is added. 3. To prevent injury, note the following 4. Additional instructions (2) Wiring (5) Corrective actions (6) Maintenance, inspection and parts replacement Section 1.5 Section 1.8 (1) Section 2.4 Section 3.1 Section 3.3.3 (1) (a) Section 3.5 (1) (b) Section 5.1.2 Section 5.1.5 Section 5.2.1 Section 5.2.2 Section 5.2.3  Section 5.2.4 Section 5.2.5 Section 6.2.2 (1) (c) Section 7.1.2 Section 7.1.4 Section 7.2.3 (1) (b) Section 7.3.2 Section 7.5 Section 10.5 Section 11.1.1 Section 11.2.2 Section 11.9 Section 11.11	Partially changed. Partially added. Partially added. Partially changed. The function is added. Partially changed. Partially added. Partially changed. Partially added. Partially changed. Partially changed. [Pr. PE44] to [Pr. PE.50] are changed. [Pr. PA25] is partially changed. [Pr. PB01] is partially added. [Pr. PC03], [Pr. PC18], [Pr. PC21] and [Pr. PC26] are partially changed. [Pr. PD32] is partially changed. [Pr. PE44] to [Pr. PE.50] are added. POINT is partially changed. Partially added and the diagrams are partially changed. Partially changed. Partially changed. Partially deleted and POINT is added. Newly added. POINT is changed. Partially added. Partially changed. Partially changed. POINT is added.

Revision Date	*Manual Number	Revision
Apr. 2016	SH(NA)030128ENG-G	Section 12.5.3 (4) (b) Partially changed. App. 2 The contents are changed.
Dec. 2016	SH(NA)030128ENG-H	The HG-KN series servo motors can be operated at a speed of 6000 r/min. 4. Additional instructions (1) Transportation and installation Partially changed. Section 1.2 (2) Partially changed. Section 1.3 Partially changed. Section 3.1 Partially changed. Section 3.1 (2), (3), (4) Partially changed. Section 3.3.1 Partially changed. Section 3.3.3 (1) (b) Partially changed. Section 4.5.3 (3) Partially changed. Chapter 5 Partially changed. Section 5.1.1 [Pr. PA28] is changed. Section 5.2.1 [Pr. PA15] and [Pr. PA16] are partially changed. [Pr. PA28] is added. Section 5.2.3 [Pr. PC14] and [Pr. PC21] are partially changed. Section 6.2.3 (1) (d) Added. Section 8.3 Partially changed. Section 9.1 (3) Partially changed. Section 10.1 Partially changed. Section 10.3.1 (2) Partially changed. Section 11.1.1 Partially changed. App. 1 Partially changed. App. 2 Partially changed. App. 3 Partially changed. App. 7 Newly added. App. 8 Newly added.

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## Warranty

### 1. Warranty period and coverage

We will repair any failure or defect hereinafter referred to as "failure" in our FA equipment hereinafter referred to as the "Product" arisen during warranty period at no charge due to causes for which we are responsible through the distributor from which you purchased the Product or our service provider. However, we will charge the actual cost of dispatching our engineer for an on-site repair work on request by customer in Japan or overseas countries. We are not responsible for any on-site readjustment and/or trial run that may be required after a defective unit are repaired or replaced.

### [Term]

The term of warranty for Product is twelve (12) months after your purchase or delivery of the Product to a place designated by you or eighteen (18) months from the date of manufacture whichever comes first ("Warranty Period"). Warranty period for repaired Product cannot exceed beyond the original warranty period before any repair work.

### [Limitations]

- (1) You are requested to conduct an initial failure diagnosis by yourself, as a general rule.  
It can also be carried out by us or our service company upon your request and the actual cost will be charged. However, it will not be charged if we are responsible for the cause of the failure.
- (2) This limited warranty applies only when the condition, method, environment, etc. of use are in compliance with the terms and conditions and instructions that are set forth in the instruction manual and user manual for the Product and the caution label affixed to the Product.
- (3) Even during the term of warranty, the repair cost will be charged on you in the following cases;
  - (i) a failure caused by your improper storing or handling, carelessness or negligence, etc., and a failure caused by your hardware or software problem
  - (ii) a failure caused by any alteration, etc. to the Product made on your side without our approval
  - (iii) a failure which may be regarded as avoidable, if your equipment in which the Product is incorporated is equipped with a safety device required by applicable laws and has any function or structure considered to be indispensable according to a common sense in the industry
  - (iv) a failure which may be regarded as avoidable if consumable parts designated in the instruction manual, etc. are duly maintained and replaced
  - (v) any replacement of consumable parts (battery, fan, smoothing capacitor, etc.)
  - (vi) a failure caused by external factors such as inevitable accidents, including without limitation fire and abnormal fluctuation of voltage, and acts of God, including without limitation earthquake, lightning and natural disasters
  - (vii) a failure generated by an unforeseeable cause with a scientific technology that was not available at the time of the shipment of the Product from our company
  - (viii) any other failures which we are not responsible for or which you acknowledge we are not responsible for

### 2. Term of warranty after the stop of production

- (1) We may accept the repair at charge for another seven (7) years after the production of the product is discontinued. The announcement of the stop of production for each model can be seen in our Sales and Service, etc.
- (2) Please note that the Product (including its spare parts) cannot be ordered after its stop of production.

### 3. Service in overseas countries

Our regional FA Center in overseas countries will accept the repair work of the Product. However, the terms and conditions of the repair work may differ depending on each FA Center. Please ask your local FA center for details.

### 4. Exclusion of loss in opportunity and secondary loss from warranty liability

Regardless of the gratis warranty term, Mitsubishi shall not be liable for compensation to:

- (1) Damages caused by any cause found not to be the responsibility of Mitsubishi.
- (2) Loss in opportunity, lost profits incurred to the user by Failures of Mitsubishi products.
- (3) Special damages and secondary damages whether foreseeable or not, compensation for accidents, and compensation for damages to products other than Mitsubishi products.
- (4) Replacement by the user, maintenance of on-site equipment, start-up test run and other tasks.

### 5. Change of Product specifications

Specifications listed in our catalogs, manuals or technical documents may be changed without notice.

### 6. Application and use of the Product

- (1) For the use of our General-Purpose AC Servo, its applications should be those that may not result in a serious damage even if any failure or malfunction occurs in General-Purpose AC Servo, and a backup or fail-safe function should operate on an external system to General-Purpose AC Servo when any failure or malfunction occurs.
- (2) Our General-Purpose AC Servo is designed and manufactured as a general purpose product for use at general industries. Therefore, applications substantially influential on the public interest for such as atomic power plants and other power plants of electric power companies, and also which require a special quality assurance system, including applications for railway companies and government or public offices are not recommended, and we assume no responsibility for any failure caused by these applications when used  
In addition, applications which may be substantially influential to human lives or properties for such as airlines, medical treatments, railway service, incineration and fuel systems, man-operated material handling equipment, entertainment machines, safety machines, etc. are not recommended, and we assume no responsibility for any failure caused by these applications when used. We will review the acceptability of the abovementioned applications, if you agree not to require a specific quality for a specific application. Please contact us for consultation.

MODEL	MR-JE-A SERVOAMPLIFIER INSTRUCTIONMANUAL
MODEL CODE	1CW706

# MITSUBISHI ELECTRIC CORPORATION

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