

General-Purpose AC Servo

MELSERVO-J3 Series

General-Purpose Interface

MODEL

MR-J3-□A

SERVO AMPLIFIER

INSTRUCTION MANUAL

● Safety Instructions ●

(Always read these instructions before using the equipment.)

Do not attempt to install, operate, maintain or inspect the servo amplifier and servo motor until you have read through this Instruction Manual, Installation guide, Servo motor Instruction Manual and appended documents carefully and can use the equipment correctly. Do not use the servo amplifier and servo motor 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 installation guide, always keep it accessible to the operator.

1. To prevent electric shock, note the following:

WARNING

- Before wiring or inspection, switch power off and wait for more than 15 minutes. Then, confirm the voltage is safe with voltage tester. Otherwise, you may get an electric shock.
- Connect the servo amplifier and servo motor to ground.
- 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, you may get an electric shock.
- Operate the switches with dry hand to prevent an electric shock.
- The cables should not be damaged, stressed, loaded, or pinched. Otherwise, you may get an electric shock.
- During power-on or operation, do not open the front cover of the servo amplifier. You may get an electric shock.
- Do not operate the servo amplifier with the front cover removed. High-voltage terminals and charging area are exposed and you may get an electric shock.
- Except for wiring or periodic inspection, do not remove the front cover even of the servo amplifier if the power is off. The servo amplifier is charged and you may get an electric shock.

2. To prevent fire, note the following:

CAUTION

- Do not install the servo amplifier, servo motor and regenerative brake resistor on or near combustibles. Otherwise a fire may cause.
- When the servo amplifier has become faulty, switch off the main servo amplifier power side. Continuous flow of a large current may cause a fire.
- When a regenerative brake resistor is used, use an alarm signal to switch main power off. Otherwise, a regenerative brake transistor fault or the like may overheat the regenerative brake resistor, causing a fire.

3. To prevent injury, note the follow

CAUTION

- Only the voltage specified in the Instruction Manual should be applied to each terminal, Otherwise, a burst, damage, etc. may occur.
- Connect the terminals correctly to prevent a burst, damage, etc.
- Ensure that polarity (+, -) is correct. Otherwise, a burst, damage, etc. may occur.
- Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the servo amplifier heat sink, regenerative brake resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
- During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

4. Additional instructions

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

(1) Transportation and installation

CAUTION

- Transport the products correctly according to their weights.
- Stacking in excess of the specified number of products is not allowed.
- Do not carry the servo motor by the cables, shaft or encoder.
- Do not hold the front cover to transport the servo amplifier. The servo amplifier may drop.
- Install the servo amplifier in a load-bearing place in accordance with the Instruction Manual.
- Do not climb or stand on servo equipment. Do not put heavy objects on equipment.
- The servo amplifier and servo motor must be installed in the specified direction.
- Leave specified clearances between the servo amplifier and control enclosure walls or other equipment.
- Do not install or operate the servo amplifier and servo motor which has been damaged or has any parts missing.
- Provide adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the servo amplifier.
- Do not drop or strike servo amplifier or servo motor. Isolate from all impact loads.
- When you keep or use it, please fulfill the following environmental conditions.

Environment			Conditions	
			Servo amplifier	Servo motor
Ambient temperature	During operation	[°C]	0 to +55 (non-freezing)	0 to +40 (non-freezing)
		[°F]	32 to 131 (non-freezing)	32 to 104 (non-freezing)
	In storage	[°C]	−20 to +65 (non-freezing)	−15 to +70 (non-freezing)
		[°F]	−4 to 149 (non-freezing)	5 to 158 (non-freezing)
Ambient humidity	In operation	90%RH or less (non-condensing)		80%RH or less (non-condensing)
	In storage	90%RH or less (non-condensing)		
Ambience			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt	
Altitude			Max. 1000m (3280 ft) above sea level	
(Note) Vibration	[m/s ² (ft/s ²)]	5.9 (19.4) or less	HF-KP Series	X • Y : 49 (161)
			HF-SP 52 to 152	X • Y : 24.5 (80)
			HF- SP 202 • 352	X : 24.5 (80) Y : 49 (161)

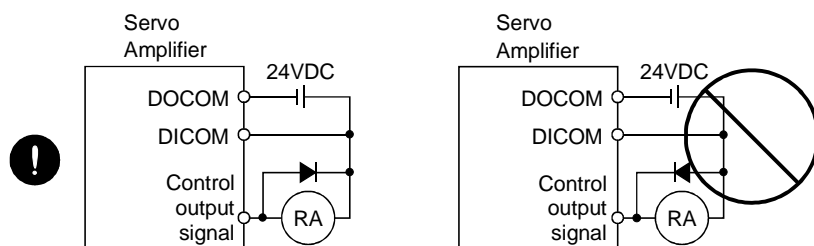
Note. Except the servo motor with reduction gear.

- Securely attach the servo motor to the machine. If attach insecurely, the servo motor may come off during operation.
- The servo motor with reduction gear must be installed in the specified direction to prevent oil leakage.
- Take safety measures, e.g. provide covers, to prevent accidental access to the rotating parts of the servo motor during operation.
- Never hit the servo motor or shaft, especially when coupling the servo motor to the machine. The encoder may become faulty.
- Do not subject the servo motor shaft to more than the permissible load. Otherwise, the shaft may break.
- When the equipment has been stored for an extended period of time, consult Mitsubishi.

(2) Wiring

CAUTION

- Wire the equipment correctly and securely. Otherwise, the servo motor may misoperate.
- Do not install a power capacitor, surge absorber or radio noise filter (FR-BIF option) between the servo motor and servo amplifier.
- Connect the output terminals (U, V, W) correctly. Otherwise, the servo motor will operate improperly.
- Do not connect AC power directly to the servo motor. Otherwise, a fault may occur.
- The surge absorbing diode installed on the DC output signal relay of the servo amplifier must be wired in the specified direction. Otherwise, the emergency stop (EMG) and other protective circuits may not operate.



(3) Test run adjustment

CAUTION

- Before operation, check the parameter settings. Improper settings may cause some machines to perform unexpected operation.
- The parameter settings must not be changed excessively. Operation will be insatiable.

(4) Usage

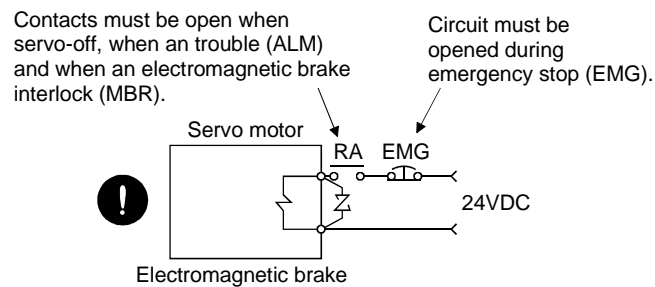
CAUTION

- Provide an external emergency stop circuit to ensure that operation can be stopped and power switched off immediately.
- Any person who is involved in disassembly and repair should be fully competent to do the work.
- Before resetting an alarm, make sure that the run signal of the servo amplifier is off to prevent an accident. A sudden restart is made if an alarm is reset with the run signal on.
- Do not modify the equipment.
- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be caused by electronic equipment used near the servo amplifier.
- 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 ballscrew 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

- When it is assumed that a hazardous condition may take place at the occur due to a power failure or a product fault, use a servo motor with electromagnetic brake or an external brake mechanism for the purpose of prevention.
- Configure the electromagnetic brake circuit so that it is activated not only by the servo amplifier signals but also by an external emergency stop (EMG).



- When any alarm has occurred, eliminate its cause, ensure safety, and deactivate the alarm before restarting operation.
- When power is restored after an instantaneous power failure, keep away from the machine because the machine may be restarted suddenly (design the machine so that it is secured against hazard if restarted).

(6) Maintenance, inspection and parts replacement

CAUTION

- With age, the electrolytic capacitor of the servo amplifier will deteriorate. To prevent a secondary accident due to a fault, it is recommended to replace the electrolytic capacitor every 10 years when used in general environment.
- Please consult our sales representative.

(7) General instruction

- To illustrate details, the equipment in the diagrams of this Specifications and 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 Specifications and Instruction Manual.

● About processing of waste ●

When you discard servo amplifier, a battery (primary battery), and other option articles, please follow the law of each country (area).



FOR MAXIMUM SAFETY

- This product is not designed or manufactured to be used in equipment or systems in situations that can affect or endanger human life.
- When considering this product for operation in special applications such as machinery or systems used in passenger transportation, medical, aerospace, atomic power, electric power, or submarine repeating applications, please contact your nearest Mitsubishi sales representative.
- Although this product was manufactured under conditions of strict quality control, you are strongly advised to install safety devices to forestall serious accidents when it is used in facilities where a breakdown in the product is likely to cause a serious accident.



EEP-ROM life

The number of write times to the EEP-ROM, which stores parameter settings, etc., is limited to 100,000. If the total number of the following operations exceeds 100,000, the servo amplifier and/or converter unit may fail when the EEP-ROM reaches the end of its useful life.

- Write to the EEP-ROM due to parameter setting changes
- Home position setting in the absolute position detection system
- Write to the EEP-ROM due to device changes

COMPLIANCE WITH EC DIRECTIVES

1. WHAT ARE EC DIRECTIVES?

The EC directives were issued to standardize the regulations of the EU countries and ensure smooth distribution of safety-guaranteed products. In the EU countries, the machinery directive (effective in January, 1995), EMC directive (effective in January, 1996) and low voltage directive (effective in January, 1997) of the EC directives require that products to be sold should meet their fundamental safety requirements and carry the CE marks (CE marking). CE marking applies to machines and equipment into which servo amplifiers have been installed.

(1) EMC directive

The EMC directive applies not to the servo units alone but to servo-incorporated machines and equipment. This requires the EMC filters to be used with the servo-incorporated machines and equipment to comply with the EMC directive. For specific EMC directive conforming methods, refer to the EMC Installation Guidelines (IB(NA)67310).

(2) Low voltage directive

The low voltage directive applies also to servo units alone. Hence, they are designed to comply with the low voltage directive.

This servo is certified by TUV, third-party assessment organization, to comply with the low voltage directive.

(3) Machine directive

Not being machines, the servo amplifiers need not comply with this directive.

2. PRECAUTIONS FOR COMPLIANCE

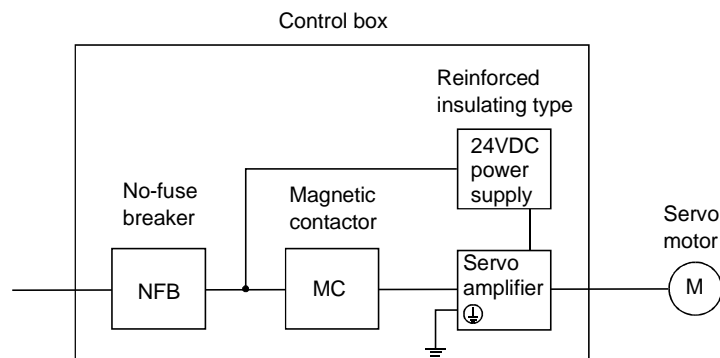
(1) Servo amplifiers and servo motors used

Use the servo amplifiers and servo motors which comply with the standard model.

Servo amplifier :MR-J3-10A to MR-J3-350A
MR-J3-10A1 to MR-J3-40A1 (Under application)
Servo motor :HF-KP□
HF-SP□

(2) Configuration

The control circuit provide safe separation to the main circuit in the servo amplifier.



(3) Environment

Operate the servo amplifier at or above the contamination level 2 set forth in IEC60664-1. For this purpose, install the servo amplifier in a control box which is protected against water, oil, carbon, dust, dirt, etc. (IP54).

(4) Power supply

- (a) This servo amplifier can be supplied from star-connected supply with earthed neutral point of overvoltage category III set forth in IEC60664-1. However, when using the neutral point of 400V system for single phase supply, a reinforced reinforced insulating transformer is required in the power input section.
- (b) When supplying interface power from external, use a 24VDC power supply which has been insulation-reinforced in I/O.

(5) Grounding

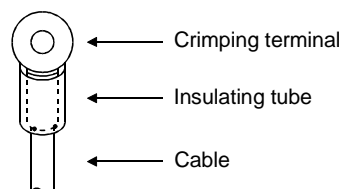
- (a) To prevent an electric shock, always connect the protective earth (PE) terminals (marked \oplus) of the servo amplifier to the protective earth (PE) of the control box.
- (b) Do not connect two ground cables to the same protective earth (PE) terminal. Always connect the cables to the terminals one-to-one.



- (c) If a leakage current breaker is used to prevent an electric shock, the protective earth (PE) terminals of the servo amplifier must be connected to the corresponding earth terminals.

(6) Wiring

- (a) The cables to be connected to the terminal block of the servo amplifier must have crimping terminals provided with insulating tubes to prevent contact with adjacent terminals.



- (b) Use the servo motor side power connector which complies with the EN Standard. The EN Standard compliant power connector sets are available from us as options. (Refer to Section 12.1)

(7) Auxiliary equipment and options

- (a) The no-fuse breaker and magnetic contactor used should be the EN or IEC standard-compliant products of the models described in Section 12.7.

Use a type B (Note) breaker. When it is not used, provide insulation between the servo amplifier and other device by double insulation or reinforced insulation, or install a transformer between the main power supply and servo amplifier.

Note. Type A: AC and pulse detectable

Type B: Both AC and DC detectable

- (b) The sizes of the cables described in Section 12.7 meet the following requirements. To meet the other requirements, follow Table 5 and Appendix C in EN60204-1.

- Ambient temperature: 40 (104) [°C (°F)]
- Sheath: PVC (polyvinyl chloride)
- Installed on wall surface or open table tray

- (c) Use the EMC filter for noise reduction.

(8) Performing EMC tests

When EMC tests are run on a machine/device into which the servo amplifier has been installed, it must conform to the electromagnetic compatibility (immunity/emission) standards after it has satisfied the operating environment/electrical equipment specifications.

For the other EMC directive guidelines on the servo amplifier, refer to the EMC Installation Guidelines (IB(NA)67310).

CONFORMANCE WITH UL/C-UL STANDARD

(1) Servo amplifiers and servo motors used

Use the servo amplifiers and servo motors which comply with the standard model.

Servo amplifier :MR-J3-10A to MR-J3-350A
MR-J3-10A1 to MR-J3-40A1 (Under application)
Servo motor :HF-KP □
HF-SP □

(2) Installation

Install a fan of 100CFM (2.8m³/min) air flow 4 in (10.16 cm) above the servo amplifier or provide cooling of at least equivalent capability.

(3) Short circuit rating

This servo amplifier conforms to the circuit whose peak current is limited to 5000A or less. Having been subjected to the short-circuit tests of the UL in the alternating-current circuit, the servo amplifier conforms to the above circuit.

(4) Capacitor discharge time

The capacitor discharge time is as listed below. To ensure safety, do not touch the charging section for 15 minutes after power-off.

Servo amplifier	Discharge time [min]
MR-J3-10A (1) • 20A (1)	1
MR-J3-40A (1)	2
MR-J3-70A to 350A	3

(5) Options and auxiliary equipment

Use UL/C-UL standard-compliant products.

This servo amplifier is UL/C-UL-listed when using the fuses indicated in the following table. When the servo amplifier must comply with the UL/C-UL Standard, be sure to use these fuses.

Servo amplifier	Fuse		
	Class	Current [A]	Voltage [V]
MR-J3-10A (1) • 20A	T	10	AC250
MR-J3-40A • 20A1		15	
MR-J3-60A to 100A • 40A1		20	
MR-J3-200A		40	
MR-J3-350A		70	

(6) Attachment of a servo motor

For the flange size of the machine side where the servo motor is installed, refer to “CONFORMANCE WITH UL/C-UL STANDARD” in the Servo Motor Instruction Manual.

(7) About wiring 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.

<<About the manuals>>

This Instruction Manual and the MELSERVO Servo Motor Instruction Manual are required if you use the General-Purpose AC servo MR-J3-A for the first time. Always purchase them and use the MR-J3-A safely.

Relevant manuals

Manual name	Manual No.
MELSERVO-J3 Series To Use the AC Servo Safely	IB(NA)0300038
MELSERVO Servo Motor Instruction Manual Vol.2	SH(NA)030041
EMC Installation Guidelines	IB(NA)67310

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1. FUNCTIONS AND CONFIGURATION

1. FUNCTIONS AND CONFIGURATION

1.1 Introduction

The Mitsubishi MELSERVO-J3 series general-purpose AC servo is based on the MELSERVO-J2-Super series and has further higher performance and higher functions.

It has position control, speed control and torque control modes. Further, it can perform operation with the control modes changed, 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.

As this new series has the USB or RS-422 serial communication function, a servo configuration software-installed personal computer or the like can be used to perform parameter setting, test operation, status display monitoring, gain adjustment, etc.

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

The MELSERVO-J3 series servo motor is equipped with an absolute position encoder which has the resolution of 262144 pulses/rev to ensure more accurate control as compared to the MELSERVO-J2-Super series. Simply adding a battery to the servo amplifier makes up an absolute position detection system. This makes home position return unnecessary at power-on or alarm occurrence by setting a home position once.

(1) Position control mode

An up to 1Mpps high-speed pulse train is used to control the speed and direction of a motor and execute precision positioning of 262144 pulses/rev resolution.

The position smoothing function provides a choice of two different modes appropriate for a machine, so a smoother start/stop can be made in response to a sudden position command.

A torque limit is imposed on the servo amplifier by the clamp circuit to protect the power transistor in the main circuit from overcurrent due to sudden acceleration/deceleration or overload. This torque limit value can be changed to any value with an external analog input or the parameter.

(2) Speed control mode

An external analog speed command (0 to ± 10 VDC) or parameter-driven internal speed command (max. 7 speeds) is used to control the speed and direction of a servo motor smoothly.

There are also the acceleration/deceleration time constant setting in response to speed command, the servo lock function at a stop time, and automatic offset adjustment function in response to external analog speed command.

(3) Torque control mode

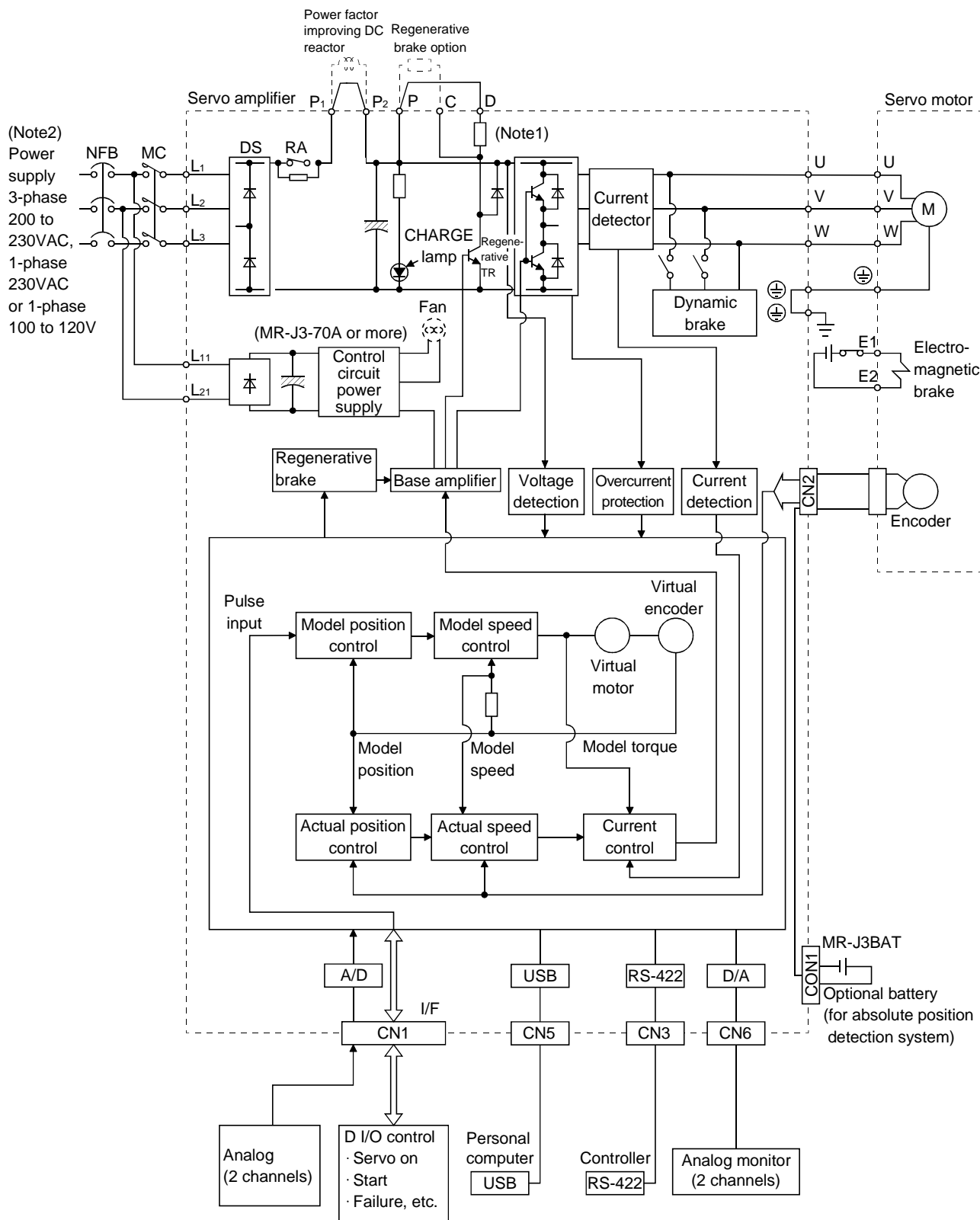
An external analog torque command (0 to ± 8 VDC) or parameter-driven internal torque command is used to control the torque output by the servo motor.

To protect misoperation under no load, the speed limit function (external or internal setting) is also available for application to tension control, etc.

1. FUNCTIONS AND CONFIGURATION

1.2 Function block diagram

The function block diagram of this servo is shown below.



Note 1. The built-in regenerative brake resistor is not provided for the MR-J3-10A (1).

2. For 1-phase 230VAC, connect the power supply to L1,L2 and leave L3 open.

There is no L3 for 1-phase 100 to 120VAC power supply.

1. FUNCTIONS AND CONFIGURATION

1.3 Servo amplifier standard specifications

Servo Amplifier MR-J3-□				10A	20A	40A	70A	100A	200A	350A	10A1	20A1	40A1		
Item															
Power supply	Voltage/frequency			3-phase 200 to 230VAC, 50/60Hz or 1-phase 230VAC, 50/60Hz				3-phase 200 to 230VAC, 50/60Hz				1-phase 100V to 120VAC, 50/60Hz			
	Permissible voltage fluctuation			3-phase 200 to 230VAC: 170 to 253VAC 1-phase 230VAC: 207 to 253VAC				3-phase 170 to 253VAC				1-phase 85 to 132VAC			
	Permissible frequency fluctuation			Within ±5%											
	Power supply capacity			Refer to Section 11.2											
	Inrush current			Refer to Section 11.5											
Control circuit power supply	Voltage, frequency		1-phase 200 to 230VAC, 50/60Hz								1-phase 100 to 120VAC, 50/60Hz				
	Permissible voltage fluctuation		1-phase 170 to 253VAC								1-phase 85 to 132VAC				
	Permissible frequency fluctuation		Within ±5%												
	Power supply capacity		Refer to Section 11.2												
Interface power supply	Voltage, frequency		DC24V±10%												
	Power supply capacity		(Note 1) 300mA or more												
Control System				Sine-wave PWM control, current control system											
Dynamic brake				Built-in											
Protective functions				Overcurrent shut-off, regenerative overvoltage shut-off, overload shut-off (electronic thermal relay), servo motor overheat protection, encoder error protection, regenerative brake error protection, undervoltage, instantaneous power failure protection, overspeed protection, excessive error protection											
Position control mode	Max. input pulse frequency			1Mpps (for differential receiver), 200kpps (for open collector)											
	Command pulse multiplying factor			Electronic gear A:1 to 1048576, B:1 to 1048576, 1/10 < A/B < 2000											
	In-position range setting			0 to ±10000 pulse (command pulse unit)											
	Error excessive			±3 revolutions											
	Torque limit			Set by parameter setting or external analog input (0 to +10VDC/maximum torque)											
Speed control mode	Speed control range			Analog speed command 1: 2000, internal speed command 1: 5000											
	Analog speed command input			0 to ±10VDC / Rated speed											
	Speed fluctuation ratio			±0.01% or less (load fluctuation 0 to 100%) 0% or less (power fluctuation ±10%) ±0.2% max.(ambient temperature 25±10°C) for external speed setting only											
	Torque limit			Set by parameter setting or external analog input (0 to +10VDC/maximum torque)											
Torque control mode	Analog torque command input			0 to ±8VDC / Maximum torque (input impedance 10 to 12kΩ)											
	Speed limit			Set by parameter setting or external analog input (0 to ±10VDC/Rated speed)											
Structure				Self-cooled, open (IP00)				Force-cooling, open (IP00)				Self-cooled, open (IP00)			
Environment	Ambient temperature	During operation	[°C]	(Note 2) 0 to +55 (non-freezing)											
			[°F]	32 to +131 (non-freezing)											
		In storage	[°C]	−20 to +65 (non-freezing)											
			[°F]	−4 to +149 (non-freezing)											
	Ambient humidity	In operation		90%RH or less (non-condensing)											
		In storage													
	Ambient			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt											
	Altitude			Max. 1000m (3280ft) above sea level											
Vibration			5.9 [m/s ²] or less 19.4 [ft/s ²] or less												
Mass		[kg]	0.8	0.8	1.0	1.4	1.4	2.3	2.3	0.8	0.8	1.0			
		[lb]	1.8	1.8	2.2	3.1	3.1	5.071	5.071	1.8	1.8	2.2			

Note 1. 300mA 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.

2. When mounting the servo amplifiers closely, operate them at the ambient temperatures of 0 to 45°C or at 75% or a smaller effective load ratio.

1. FUNCTIONS AND CONFIGURATION

1.4 Function list

The following table lists the functions of this servo. For details of the functions, refer to the reference field.

Function	Description	(Note) Control mode	Reference
Position control mode	This servo is used as position control servo.	P	Section 3.2.1 Section 3.6.1 Section 4.2
Speed control mode	This servo is used as speed control servo.	S	Section 3.2.2 Section 3.6.2 Section 4.3
Torque control mode	This servo is used as torque control servo.	T	Section 3.2.3 Section 3.6.3 Section 4.4
Position/speed control change mode	Using external input signal, control can be switched between position control and speed control.	P/S	Section 3.6.4
Speed/torque control change mode	Using external input signal, control can be switched between speed control and torque control.	S/T	Section 3.6.5
Torque/position control change mode	Using external input signal, control can be switched between torque control and position control.	T/P	Section 3.6.6
High-resolution encoder	High-resolution encoder of 262144 pulses/rev is used as a servo motor encoder.	P, S, T	
Absolute position detection system	Merely setting a home position once makes home position return unnecessary at every power-on.	P	Chapter 15
Gain changing function	You can switch between gains during rotation and gains during stop or use an external signal to change gains during operation.	P, S	Section 8.6
Advanced vibration suppression control	This function suppresses vibration at the arm end or residual vibration.	P	Section 8.4
Adaptive filter II	Servo amplifier detects mechanical resonance and sets filter characteristics automatically to suppress mechanical vibration.	P, S, T	Section 8.2
Low-pass filter	Suppresses high-frequency resonance which occurs as servo system response is increased.	P, S, T	Section 8.5
Machine analyzer function	Analyzes the frequency characteristic of the mechanical system by simply connecting a servo configuration software-installed personal computer and servo amplifier. MR Configurator (servo configuration software) MRZJW3-SETUP211 is necessary for this function.	P	
Machine simulation	Can simulate machine motions on a personal computer screen on the basis of the machine analyzer results. MR Configurator (servo configuration software) MRZJW3-SETUP211 is necessary for this function.	P	
Gain search function	Personal computer changes gains automatically and searches for overshoot-free gains in a short time. MR Configurator (servo configuration software) MRZJW3-SETUP211 is necessary for this function.	P	
Slight vibration suppression control	Suppresses vibration of ± 1 pulse produced at a servo motor stop.	P	Parameters No. PB24
Electronic gear	Input pulses can be multiplied by 1/50 to 50.	P	Parameters No. PA06, PA07
Auto tuning	Automatically adjusts the gain to optimum value if load applied to the servo motor shaft varies. Higher in performance than MR-J2-Super series servo amplifier.	P, S	Chapter 7
Position smoothing	Speed can be increased smoothly in response to input pulse.	P	Parameter No. PB03
S-pattern acceleration/ deceleration time constant	Speed can be increased and decreased smoothly.	S, T	Parameter No. PC03
Regenerative brake option	Used when the built-in regenerative brake resistor of the servo amplifier does not have sufficient regenerative capability for the regenerative power generated.	P, S, T	Section 12.2

1. FUNCTIONS AND CONFIGURATION


Function	Description	(Note) Control mode	Reference
Alarm history clear	Alarm history is cleared.	P, S, T	Parameter No. PC18
Restart after instantaneous power failure	If the input power supply voltage had reduced to cause an alarm but has returned to normal, the servo motor can be restarted by merely switching on the start signal.	S	Parameter No. PC22
Command pulse selection	Command pulse train form can be selected from among four different types.	P	Section 5.1.11
Input signal selection	Forward rotation start, reverse rotation start, servo-on (SON) and other input signals can be assigned to any pins.	P, S, T	Parameters No. PD03 to PD08, PD10 to PD12
Torque limit	Servo motor torque can be limited to any value.	P, S	Section 3.6.1 (5) Section 5.1.11
Speed limit	Servo motor speed can be limited to any value.	T	Section 3.6.3 (3) Parameter No. PC05 to PC11
Status display	Servo status is shown on the 5-digit, 7-segment LED display	P, S, T	Section 6.3
External I/O signal display	ON/OFF statuses of external I/O signals are shown on the display.	P, S, T	Section 6.7
Output signal (DO) forced output	Output signal can be forced on/off independently of the servo status. Use this function for output signal wiring check, etc.	P, S, T	Section 6.8
Automatic VC offset	Voltage is automatically offset to stop the servo motor if it does not come to a stop at the analog speed command (VC) or analog speed limit (VLA) of 0V.	S, T	Section 6.4
Test operation mode	JOG operation • positioning operation • motor-less operation • DO forced output. However, MR Configurator (servo configuration software) MRZJW3-SETUP211 is necessary for positioning operation.	P, S, T	Section 6.9
Analog monitor output	Servo status is output in terms of voltage in real time.	P, S, T	Parameter No. PC14
MR configurator (Servo configuration software)	Using a personal computer, parameter setting, test operation, status display, etc. can be performed.	P, S, T	Section 12.4
Alarm code output	If an alarm has occurred, the corresponding alarm number is output in 3-bit code.	P, S, T	Section 9.1
Amplifier diagnosis function	The DI/DO signals, analog monitor input I/F, analog monitor output, command pulse I/F and encoder pulse output are checked. The diagnosis cable (MR-J3ACHECK) and MR Configurator (servo configuration software) MRZJW3-SETUP211 are necessary for this function.	P, S, T	Section 12.4 (2)(C)

Note. P: Position control mode, S: Speed control mode, T: Torque control mode

P/S: Position/speed control change mode, S/T: Speed/torque control change mode, T/P: Torque/position control change mode

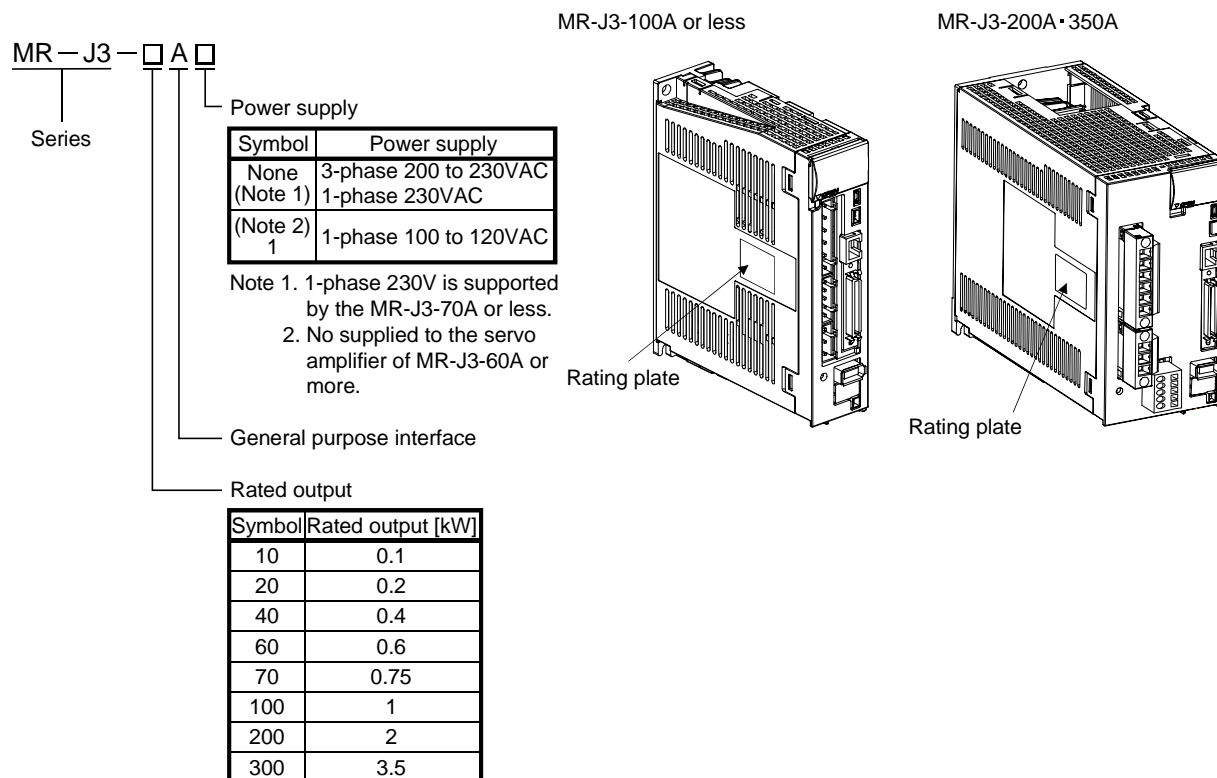
1.5 Model code definition

(1) Rating plate

MITSUBISHI AC SERVO MODE MR-J3-10A <hr/> POWER : 100W INPUT : 0.9A 3PH+1PH200-230V 50Hz 3PH+1PH200-230V 60Hz 1.3A 1PH 230V 50/60Hz <hr/> OUTPUT : 170V 0-360Hz 1.1A SERIAL : A34230001 <hr/>  MITSUBISHI ELECTRIC CORPORATION <small>MADE IN JAPAN</small>	<div data-bbox="813 1780 1187 1982"> <div>Model</div> <div>Capacity</div> <div>Applicable power supply</div> <div>Rated output current</div> <div>Serial number</div> </div> <div data-bbox="710 1937 798 2024"> <div>PASSED</div> </div>
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1. FUNCTIONS AND CONFIGURATION

(2) Model



1.6 Combination with servo motor

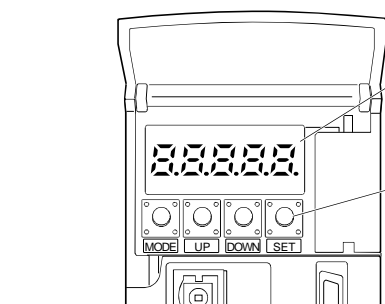
The following table lists combinations of servo amplifiers and servo motors. The same combinations apply to the models with electromagnetic brakes.

Servo amplifier	Servo motors	
	HF-KP□	HF-SP□
MR-J3-10A (1)	053 • 13	
MR-J3-20A (1)	23	
MR-J3-40A (1)	43	
MR-J3-60A		52
MR-J3-70A	73	
MR-J3-100A		102
MR-J3-200A		152 • 202
MR-J3-350A		352

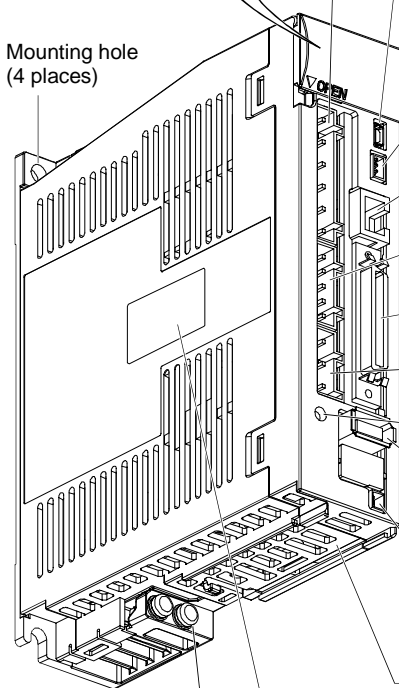
1. FUNCTIONS AND CONFIGURATION





1.7 Parts identification

(1) MR-J3-100A or less



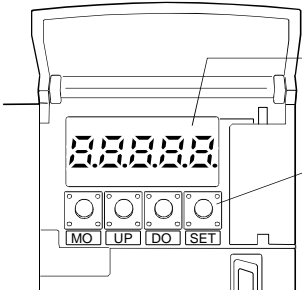
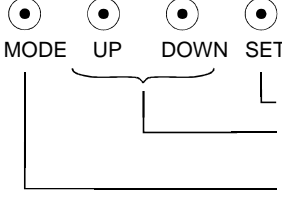
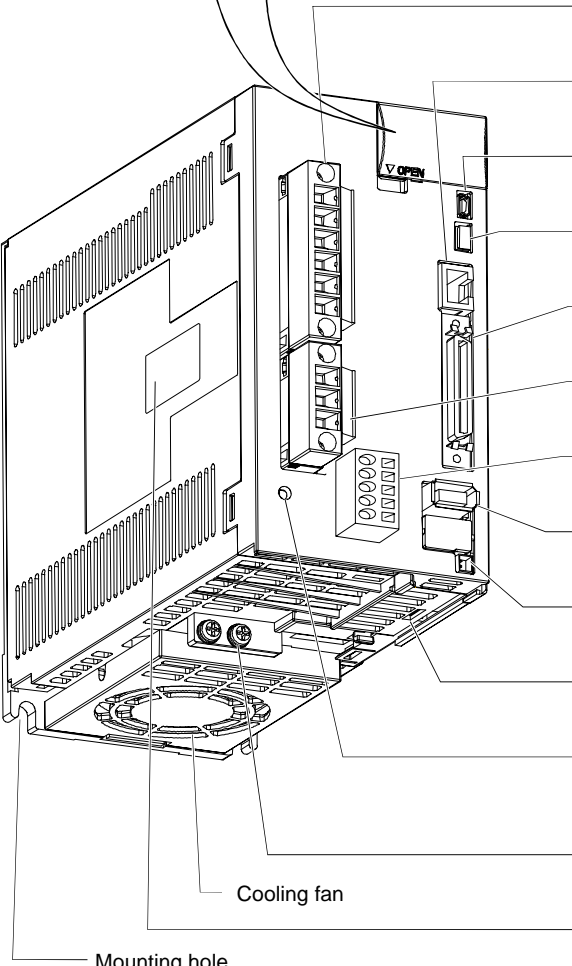
Mounting hole
(4 places)



Name/Application	Detailed Explanation
Display The 5-digit, seven-segment LED shows the servo status and alarm number.	Chapter 6
Operation section Used to perform status display, diagnostic, alarm and parameter setting operations. <div style="display: flex; justify-content: space-around; align-items: center;"> <div style="text-align: center;">  MODE </div> <div style="text-align: center;">  UP </div> <div style="text-align: center;">  DOWN </div> <div style="text-align: center;">  SET </div> </div> <div style="margin-left: 150px;"> <p>└ Used to set data.</p> <p>└ Used to change the display or data in each mode.</p> <p>└ Used to change the mode.</p> </div>	Chapter 6
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
USB communication connector (CN5) Connect with the personal computer.	Section 12.4
Analog monitor connector (CN6) Outputs the analog monitor.	Section 3.2 Section 3.4
RS-422 communication connector (CN3) Connect with the personal computer.	Section 12.4 Chapter 13
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative brake option.	Section 3.1 Section 3.3
I/O signal connector (CN1) Used to connect digital I/O signals.	Section 3.2 Section 3.4
Motor power supply connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Encoder connector (CN2) Connector for connection of the servo motor encoder.	Section 3.4 Section 12.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 12.5 Chapter 14
Battery holder Contains the battery for absolute position data backup.	Section 14.3
Name plate	Section 1.5
Protective earth (PE) terminal (⊕) Ground terminal.	Section 3.1 Section 3.3

1. FUNCTIONS AND CONFIGURATION

(2) MR-J3-200A • MR-J3-350A

Name/Application		Detailed Explanation
		Chapter 6
<p>Display The 5-digit, seven-segment LED shows the servo status and alarm number.</p> <p>Operation section Used to perform status display, diagnostic, alarm and parameter setting operations.</p> <p>  </p>		Chapter 6
 <p>Main circuit power supply connector (CNP1) Connect the input power supply.</p> <p>RS-422 communication connector (CN3) Connect with the personal computer.</p> <p>USB communication connector (CN5) Connect with the personal computer.</p> <p>Analog monitor connector (CN6) Outputs the analog monitor.</p> <p>I/O signal connector (CN1) Used to connect digital I/O signals.</p> <p>Motor power supply connector (CNP3) Connect the servo motor.</p> <p>Control circuit connector (CNP2) Connect the control circuit power supply/regenerative</p> <p>Encoder connector (CN2) Connector for connection of the servo motor encoder.</p> <p>Battery connector (CN4) Used to connect the battery for absolute position data</p> <p>Battery holder Contains the battery for absolute position data backup.</p> <p>Charge lamp Lit to indicate that the main circuit is charged. While</p> <p>Protective earth (PE) terminal (⊕) Ground terminal.</p> <p>Name plate</p>		<p>Section 3.1 Section 3.3</p> <p>Section 12.4 Chapter 13</p> <p>Section 12.4</p> <p>Section 3.2 Section 3.4</p> <p>Section 3.2 Section 3.4</p> <p>Section 3.1 Section 3.3</p> <p>Section 3.1 Section 3.3</p> <p>Section 3.4 Section 12.1</p> <p>Section 12.5 Chapter 14</p> <p>Section 14.3</p> <p></p> <p>Section 3.1 Section 3.3</p> <p>Section 1.5</p>

1. FUNCTIONS AND CONFIGURATION

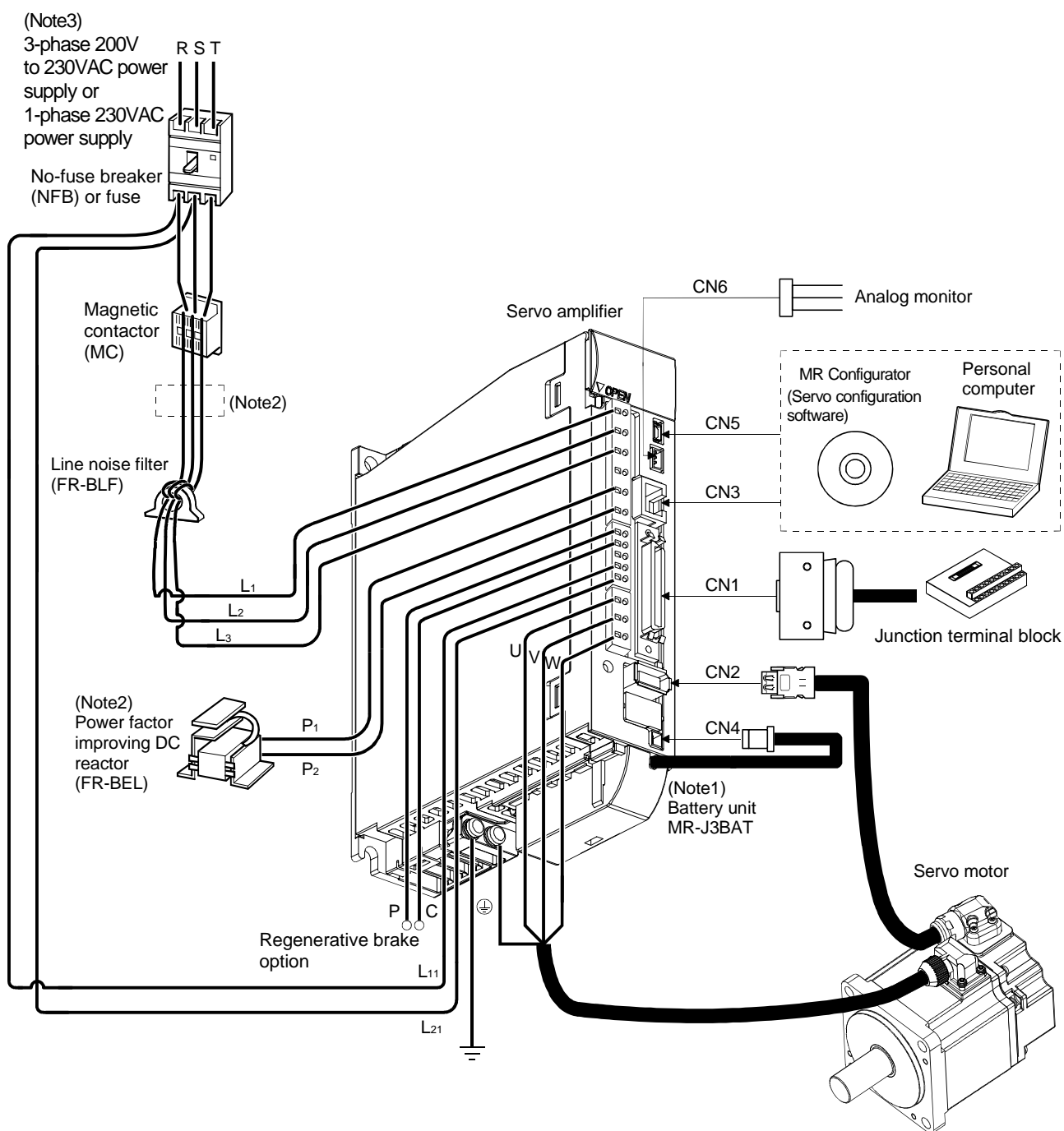
1.8 Configuration including auxiliary equipment

POINT

- Equipment other than the servo amplifier and servo motor are optional or recommended products.

(1) MR-J3-100A or less

(a) For 3-phase 200V to 230VAC or 1-phase 230VAC



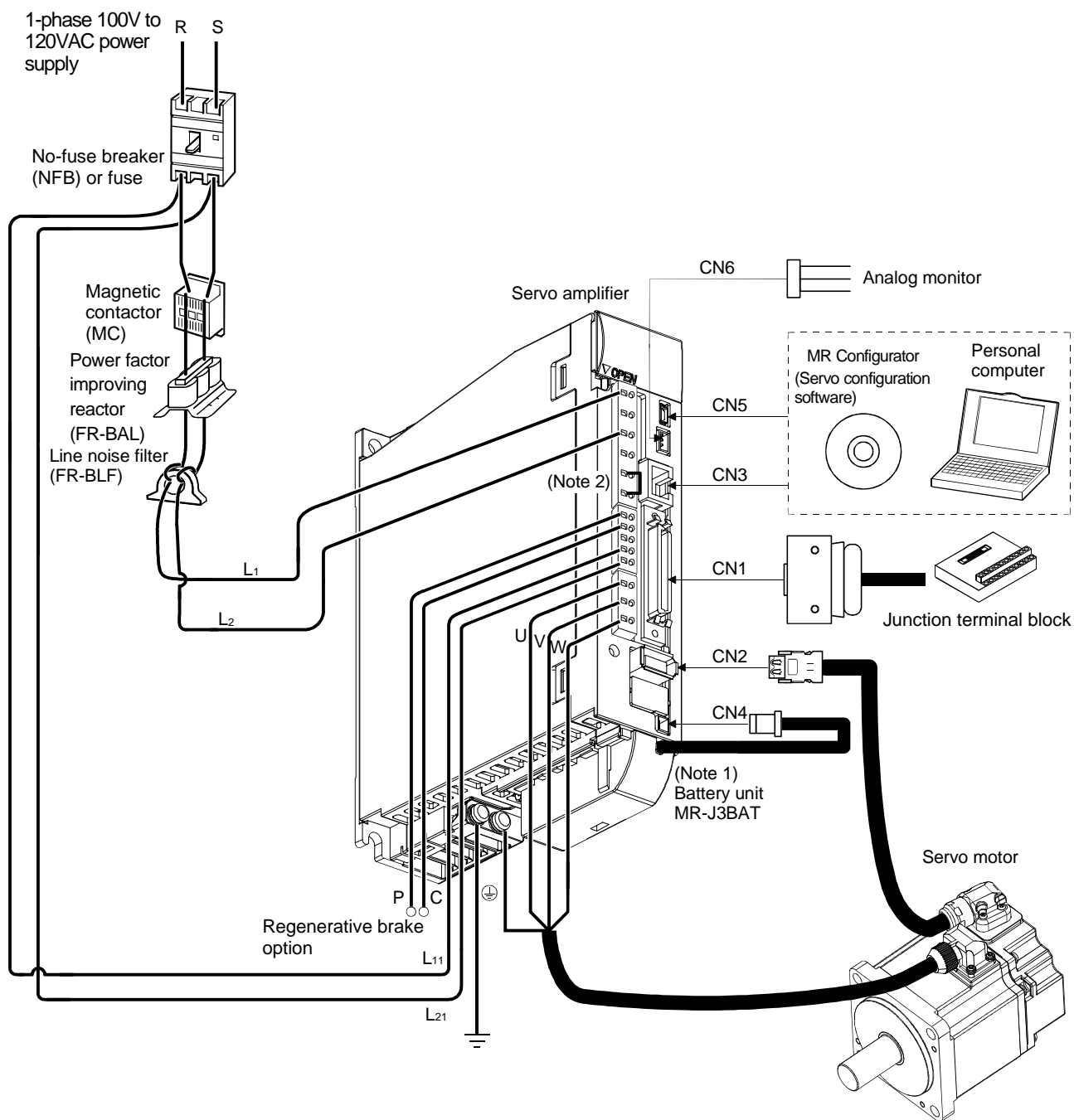
Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The AC reactor can also be used. In this case, the DC reactor cannot be used.

3. A 1-phase 230VAC power supply may be used with the servo amplifier of MR-J3-70A or less.

1. FUNCTIONS AND CONFIGURATION

(b) For 1-phase 100V to 120VAC

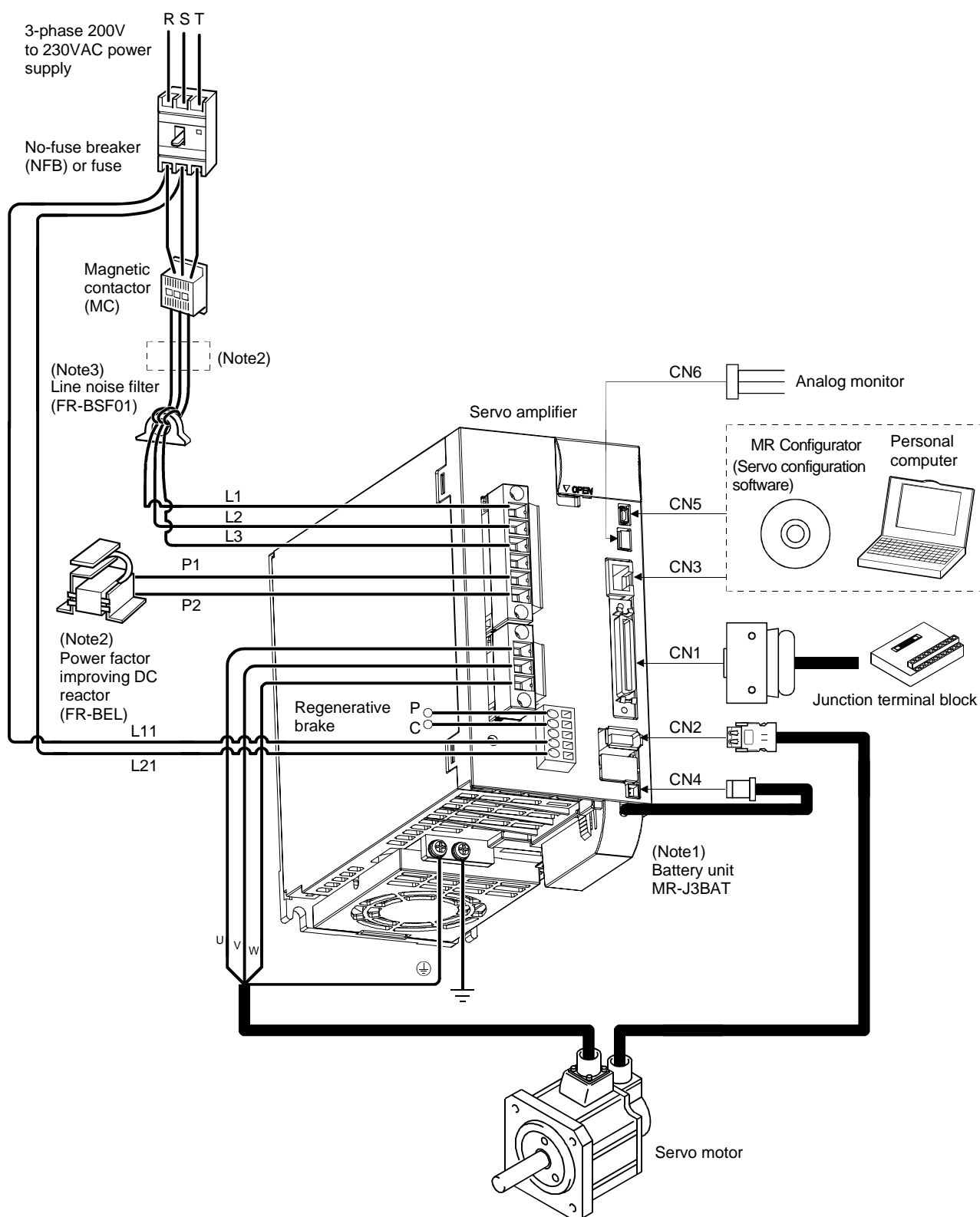


Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The power factor improving DC reactor cannot be used.

1. FUNCTIONS AND CONFIGURATION

(2) MR-J3-200A • MR-J3-350A



Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The AC reactor can also be used. In this case, the DC reactor cannot be used.

3. For MR-J3-350A, use FR-BLF.

[illegible]

2. INSTALLATION

2. INSTALLATION



CAUTION

- Stacking in excess of the limited number of products is not allowed.
- Install the equipment to incombustibles. Installing them directly or close to combustibles will led to a fire.
- Install the equipment in a load-bearing place in accordance with this Instruction Manual.
- Do not get on or put heavy load on the equipment to prevent injury.
- Use the equipment within the specified environmental condition range.
- Provide an adequate protection to prevent screws, metallic detritus and other conductive matter or oil and other combustible matter from entering the servo amplifier.
- Do not block the intake/exhaust ports of the servo amplifier. Otherwise, a fault may occur.
- Do not subject the servo amplifier to drop impact or shock loads as they are precision equipment.
- Do not install or operate a faulty servo amplifier.
- When the product has been stored for an extended period of time, consult Mitsubishi.

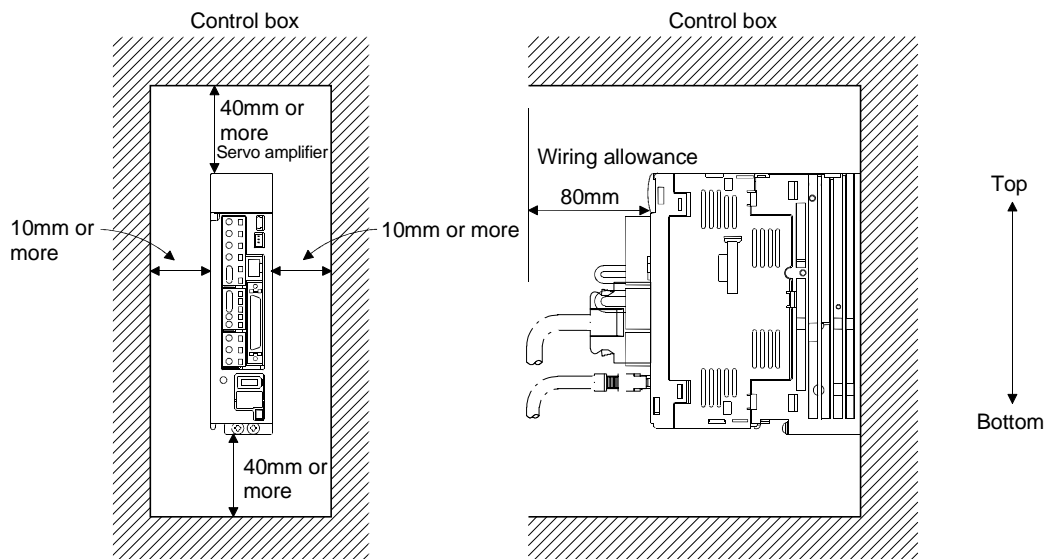
2.1 Installation direction and clearances



CAUTION

- The equipment must be installed in the specified direction. Otherwise, a fault may occur.
- Leave specified clearances between the servo amplifier and control box inside walls or other equipment.

(1) Installation of one servo amplifier



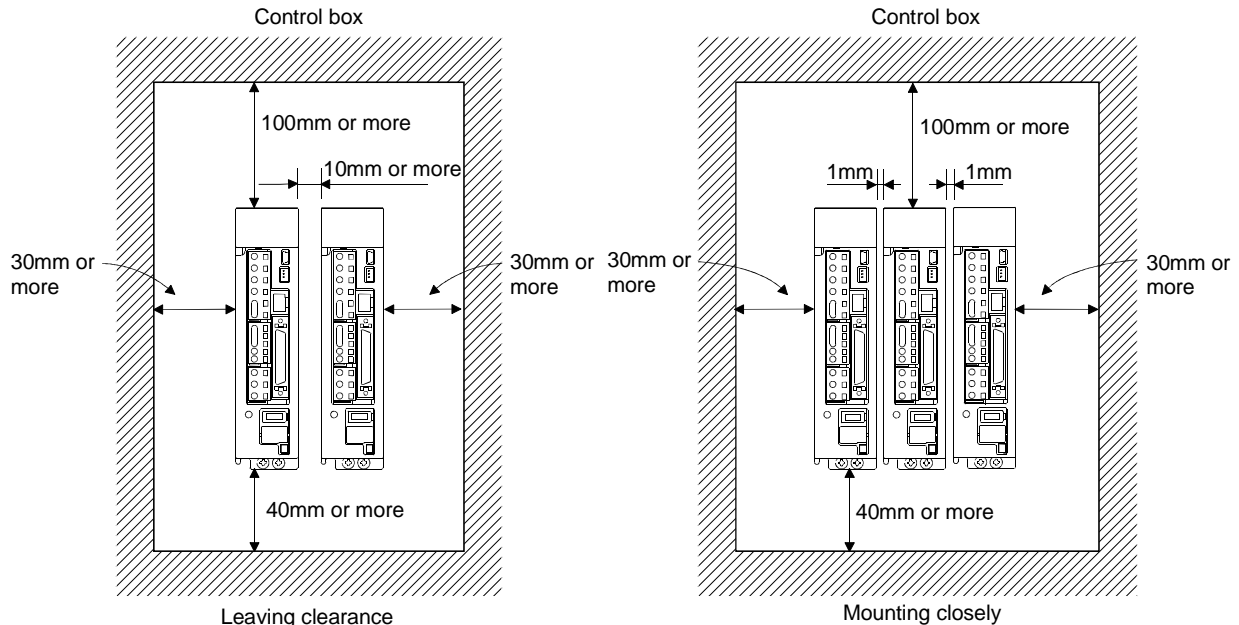
2. INSTALLATION

(2) Installation of two or more servo amplifiers

Leave a large clearance between the top of the servo amplifier and the internal surface of the control box, and install a fan to prevent the internal temperature of the control box from exceeding the environmental conditions.

When installing the servo amplifiers closely, leave a clearance of 1mm between the adjacent servo amplifiers in consideration of mounting tolerances.

In this case, make circumference temperature into 0 to 45°C, or use it at 75% or a smaller effective load ratio.



(3) Others

When using heat generating equipment such as the regenerative brake 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 installing the unit in a control box, 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 control box or a fan installed on the ceiling.
- (3) When installing the control box in a place where there are much toxic gas, dirt and dust, conduct an air purge (force clean air into the control box from outside to make the internal pressure higher than the external pressure) to prevent such materials from entering the control box.

2.3 Cable stress

- (1) The way of clamping the cable must be fully examined so that flexing 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, brake) supplied with the servo motor, and flex the optional encoder cable or the power supply and brake wiring cables. Use the optional encoder cable within the flexing life range. Use the power supply and brake wiring cables within the flexing life of the cables.
- (3) Avoid any probability that the cable sheath 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 will move, the flexing radius should be made as large as possible. Refer to section 11.4 for the flexing life.

2. INSTALLATION

2.4 Inspection Items



WARNING

- Before starting maintenance and/or inspection, make sure that the charge lamp is off more than 15 minutes after power-off. Then, confirm that the voltage is safe in the tester or the like. Otherwise, you may get an electric shock.
- Any person who is involved in inspection should be fully competent to do the work. Otherwise, you may get an electric shock. For repair and parts replacement, contact your sales representative.

POINT

- Do not test the servo amplifier with a megger (measure insulation resistance), or it may become faulty.
- Do not disassemble and/or repair the equipment on customer side.

It is recommended to make the following checks periodically:

- (a) Check for loose terminal block screws. Retighten any loose screws.
- (b) Check the cables and the like for scratches and cracks. Perform periodic inspection according to operating conditions.

2.5 Parts Having Service Lives

The following parts must be changed periodically as listed below. If any part is found faulty, it must be changed immediately even when it has not yet reached the end of its life, which depends on the operating method and environmental conditions. For parts replacement, please contact your sales representative.

	Part name	Life guideline
Servo amplifier	Smoothing capacitor	10 years
	Relay	Number of power-on and number of emergency stop times : 100,000 times
	Cooling fan	10,000 to 30,000hours (2 to 3 years)
	Absolute position battery	Refer to Section 14.2

(a) Smoothing capacitor

Affected by ripple currents, etc. and deteriorates in characteristic. 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.

(b) Relays

Their contacts will wear due to switching currents and contact faults occur. Relays reach the end of their life when the cumulative number of power-on and emergency stop times is 100,000, which depends on the power supply capacity.

(c) Servo amplifier cooling fan

The cooling fan bearings reach the end of their life in 10,000 to 30,000 hours. Normally, therefore, the fan must be changed in a few years of continuous operation as a guideline.

It must also be changed if unusual noise or vibration is found during inspection.

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3. SIGNALS AND WIRING

3. SIGNALS AND WIRING



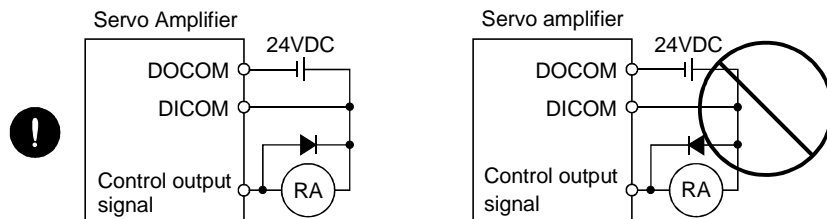
WARNING

- Any person who is involved in wiring should be fully competent to do the work.
- Before starting wiring, switch power off, then wait for more than 15 minutes, and after the charge lamp has gone off, make sure that the voltage is safe in the tester or like. Otherwise, you may get an electric shock.
- Ground the servo amplifier and the servo motor securely.
- Do not attempt to wire the servo amplifier and servo motor until they have been installed. Otherwise, you may get an electric shock.
- The cables should not be damaged, stressed excessively, loaded heavily, or pinched. Otherwise, you may get an electric shock.



CAUTION

- Wire the equipment correctly and securely. Otherwise, the servo motor may misoperate, resulting in injury.
- Connect cables to correct terminals to prevent a burst, fault, etc.
- Ensure that polarity (+, -) is correct. Otherwise, a burst, damage, etc. may occur.
- The surge absorbing diode installed to the DC relay designed for control output should be fitted in the specified direction. Otherwise, the signal is not output due to a fault, disabling the emergency stop (EMG) and other protective circuits.



- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be given to electronic equipment used near the servo amplifier.
- Do not install a power capacitor, surge suppressor or radio noise filter (FR-BIF option) with the power line of the servo motor.
- When using the regenerative brake resistor, switch power off with the alarm signal. Otherwise, a transistor fault or the like may overheat the regenerative brake resistor, causing a fire.
- Do not modify the equipment.

3. SIGNALS AND WIRING

3.1 Input power supply circuit



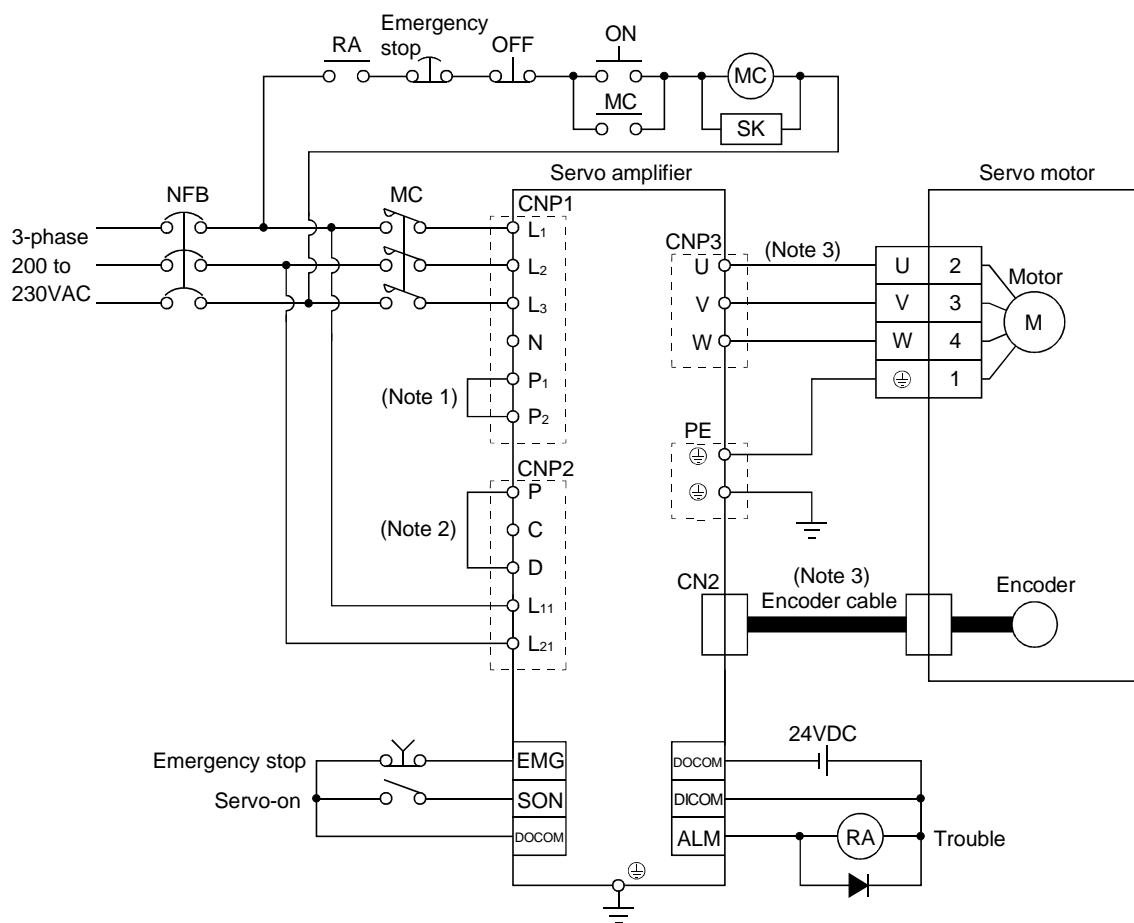
CAUTION

- When the servo amplifier has become faulty, switch power off on the servo amplifier power side. Continuous flow of a large current may cause a fire.
- Use the trouble signal to switch power off. Otherwise, a regenerative brake transistor fault or the like may overheat the regenerative brake resistor, causing a fire.

Wire the power supply and main circuit as shown below so that the servo-on (SON) turns off as soon as alarm occurrence is detected and power is shut off.

A no-fuse breaker (NFB) must be used with the input cables of the power supply.

(1) For 3-phase 200 to 230VAC power supply



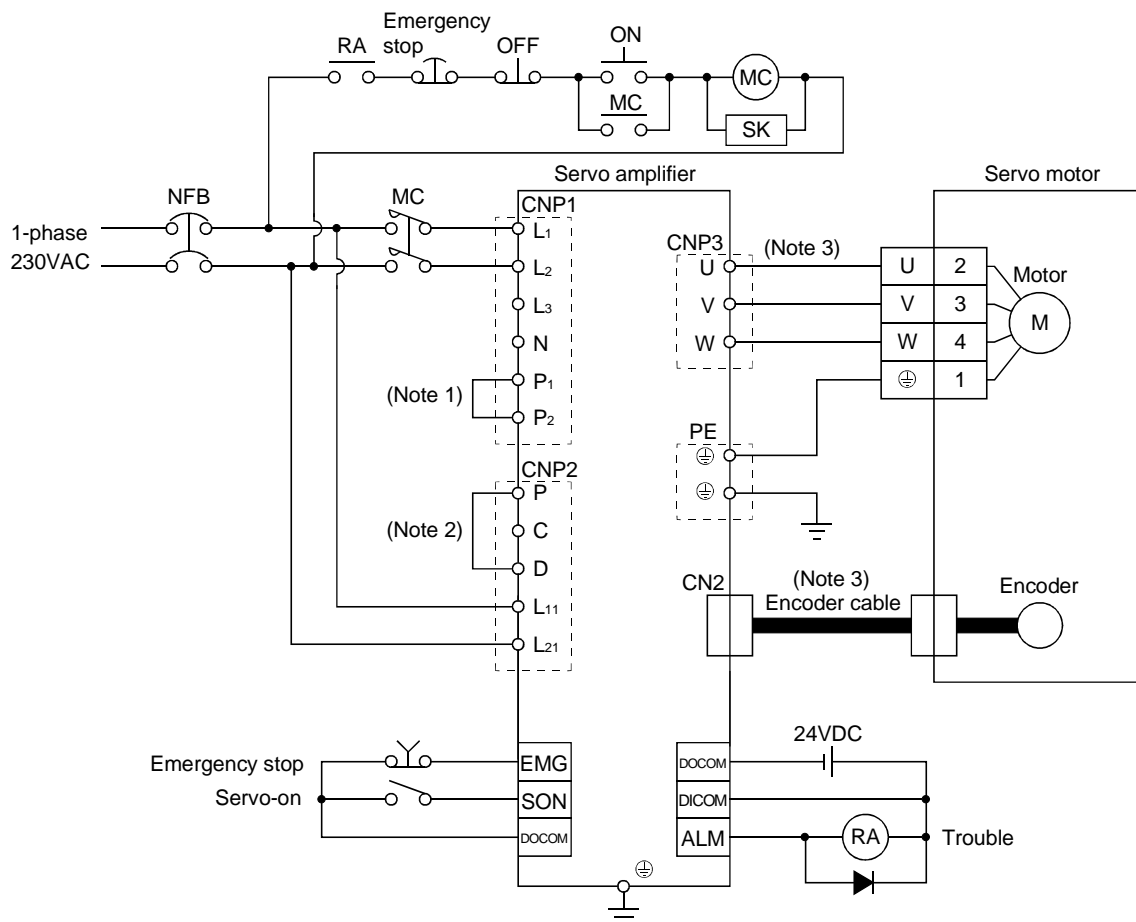
Note 1. Always connect P1-P2. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 12.8.

2. Always connect P-D. (Factory-wired.) When using the regenerative brake option, refer to Section 12.2.

3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 12.1 for selection of the cable.

3. SIGNALS AND WIRING

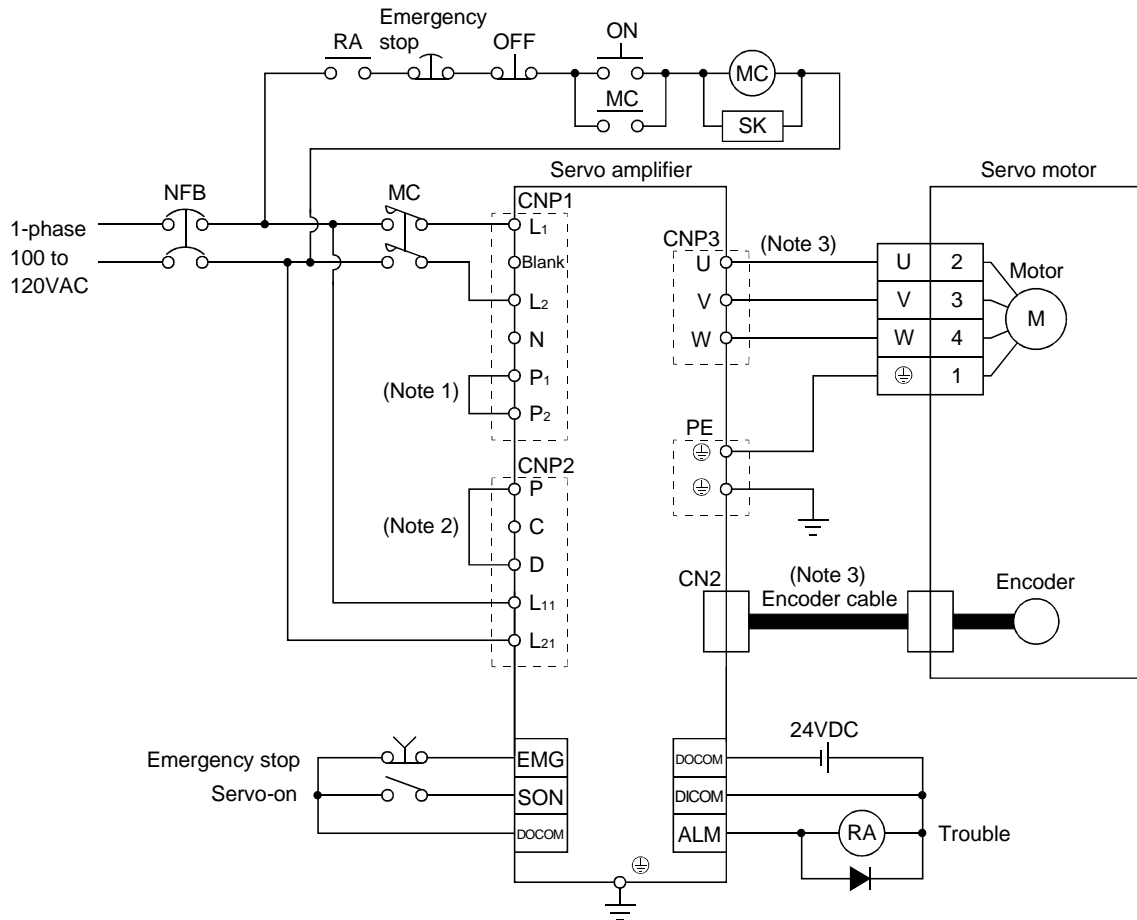
(2) 1-phase 230VAC power supply



Note 1. Always connect P₁-P₂. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 12.8.

Note 2. Always connect P-D. (Factory-wired.) When using the regenerative brake option, refer to Section 12.2.

Note 3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 12.1 for selection of the cable.



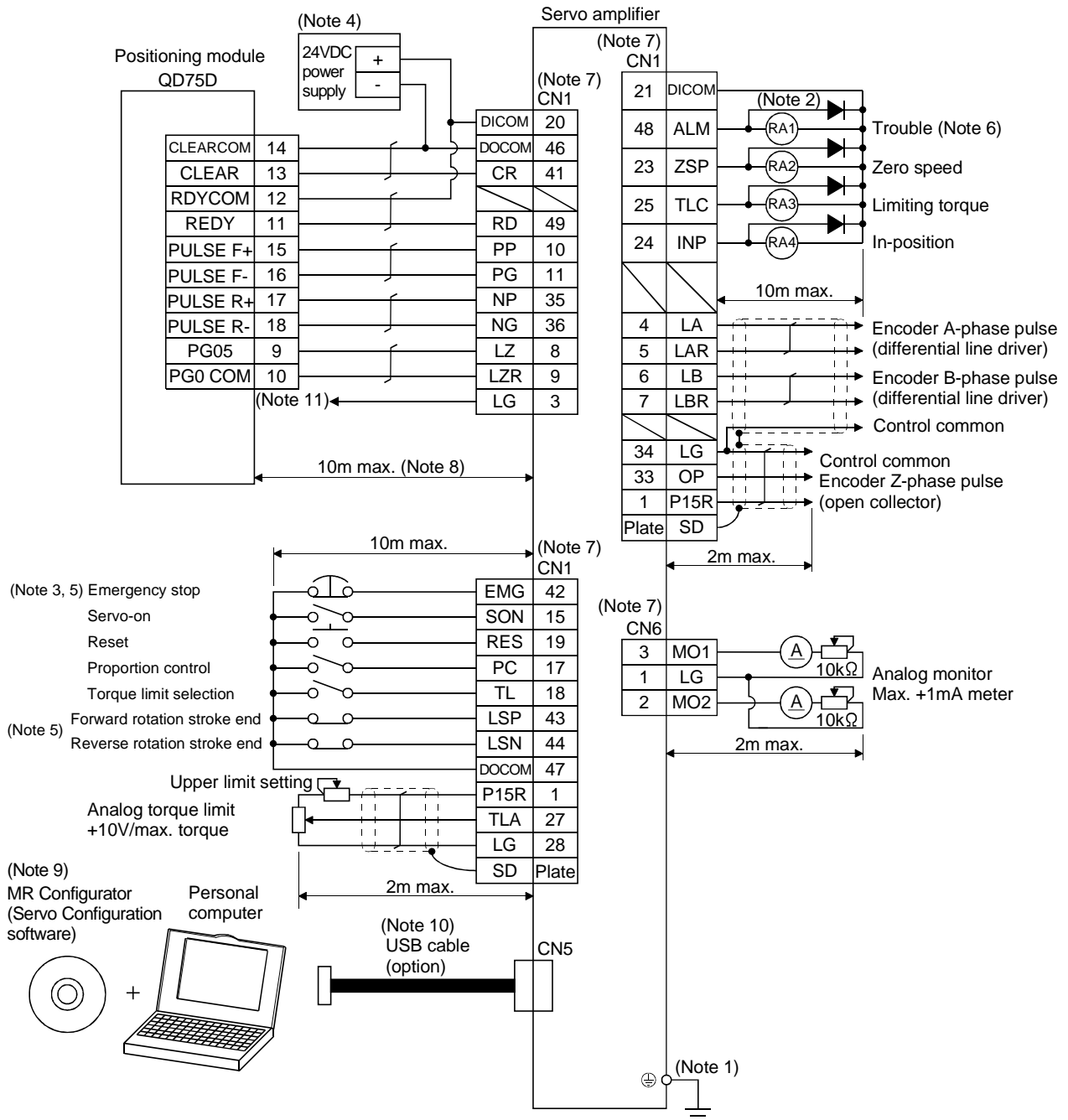
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3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 12.1 for selection of the cable.

3. SIGNALS AND WIRING

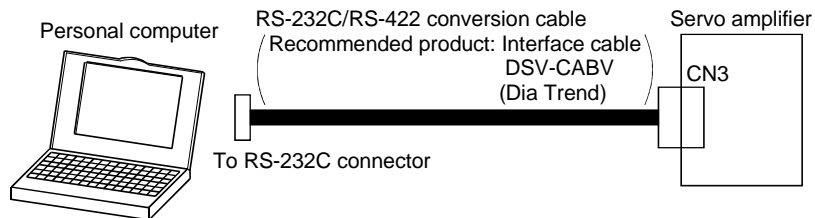
3.2 I/O Signal Connection Example

3.2.1 Position control mode



3. SIGNALS AND WIRING

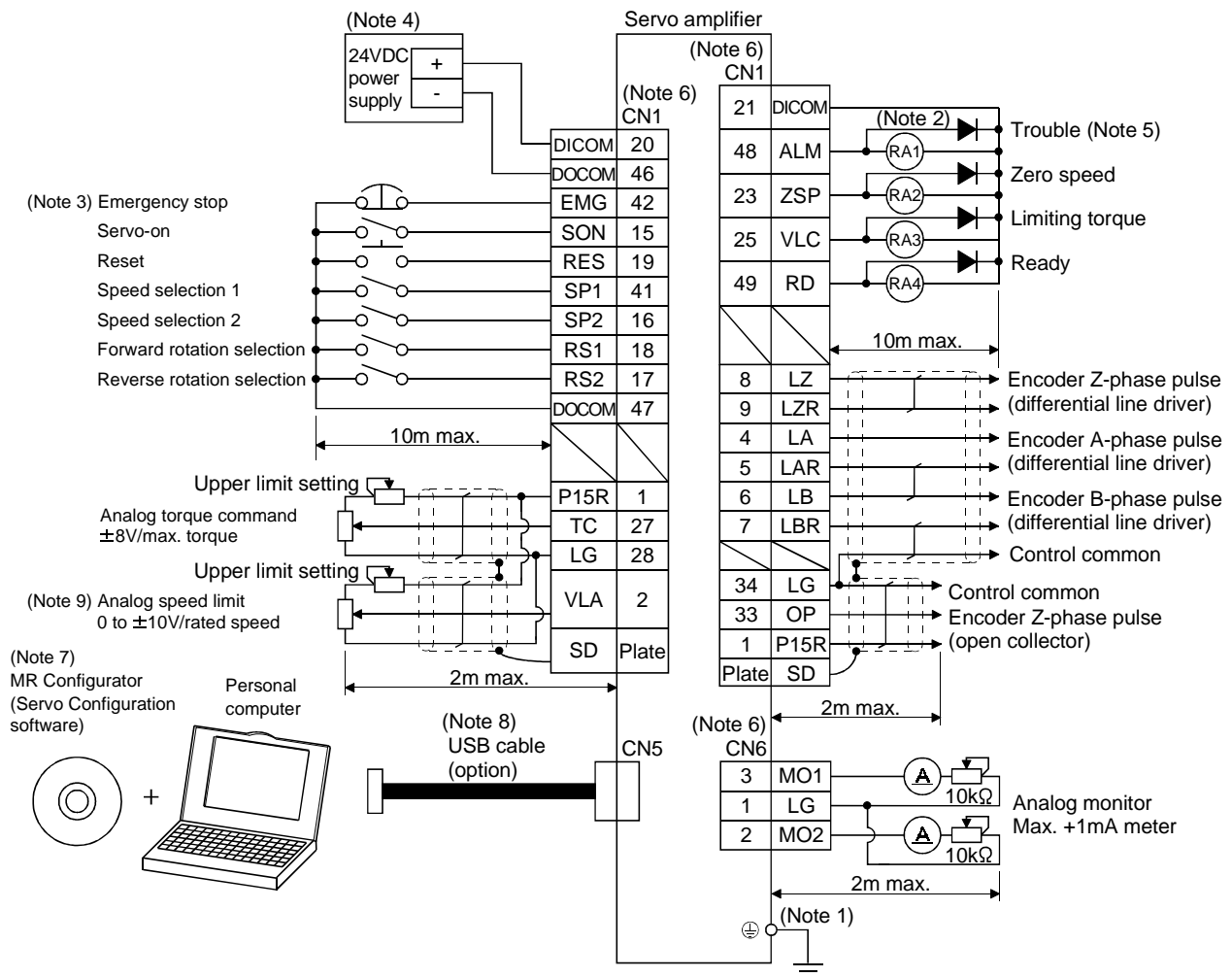
- Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal (terminal marked \oplus) of the servo amplifier to the protective earth (PE) of the control box.
2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will be faulty and will not output signals, disabling the emergency stop (EMG) and other protective circuits.
 3. The emergency stop switch (normally closed contact) must be installed.
 4. Supply $24\text{VDC} \pm 10\%$ 300mA current for interfaces from the outside. 300mA 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 3.8.2 (1) that gives the current value necessary for the interface.
 5. When starting operation, always turn on emergency stop (EMG) and Forward/Reverse rotation stroke end (LSP/LSN). (Normally closed contacts)
 6. Trouble (ALM) turns on in normal alarm-free condition. 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 opencollector system. It is 10m (32ft) or less in the differential line driver system.
 9. Use MRZJW3-SETUP 211E.
 10. RS-422 can also be used to connect the servo amplifier and personal computer.



11. This connection is not required for the QD75D. Depending on the used positioning module, however, it is recommended to connect the LG and control common terminals of the servo amplifier to enhance noise immunity.

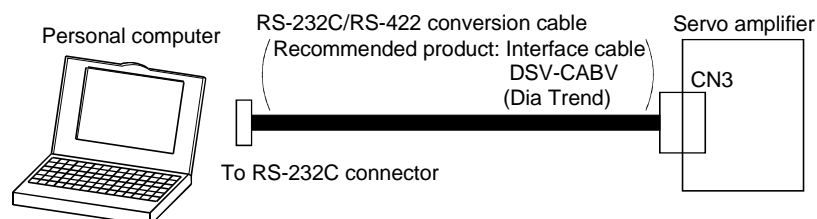
3. SIGNALS AND WIRING

3.2.3 Torque control mode



Note 1. To prevent an electric shock, always connect the protective earth (PE) terminal of the (terminal marked \oplus) servo amplifier to the protective earth (PE) of the control box.

2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will be faulty and will not output signals, disabling the emergency stop (EMG) and other protective circuits.
3. The emergency stop switch (normally closed contact) must be installed.
4. Supply $24\text{VDC} \pm 10\%$ 300mA current for interfaces from the outside. 300mA 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 3.8.2 (1) that gives the current value necessary for the interface.
5. Trouble (ALM) turns on in normal alarm-free condition.
6. The pins with the same signal name are connected in the servo amplifier.
7. Use MRZJW3-SETUP 211E.
8. RS-422 can also be used to connect the servo amplifier and personal computer.



9. Use an external power supply when inputting a negative voltage.

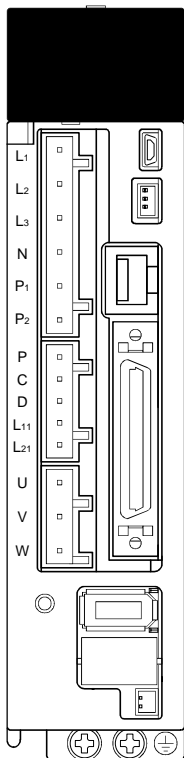
3. SIGNALS AND WIRING


3.3 Explanation of Power Supply System

3.3.1 Signal explanations

The servo amplifier shown in this section is MR-J3-100A or smaller capacities. For the appearance and connector layout of the other servo amplifiers, refer to outline drawings in Section 10.

Servo amplifier



Abbreviation	Connection Target (Application)	Description																
L ₁ L ₂ L ₃	Main circuit power supply	<div>Supply the following power to L₁, L₂, L₃. For the 1-phase 230VAC power supply, connect the power supply to L₁, L₂, and keep L₃ open.</div> <table><tr><td><div>Servo amplifier Power supply</div></td><td>MR-J3-10A to 70A</td><td>MR-J3-100A to 350A</td><td>MR-J3-10A1 to 40A1</td></tr><tr><td>3-phase 200 to 230VAC, 50/60Hz</td><td colspan="2">L₁ • L₂ • L₃</td><td></td></tr><tr><td>1-phase 230VAC, 50/60Hz</td><td>L₁ • L₂</td><td></td><td></td></tr><tr><td>1-phase 100 to 120VAC, 50/60Hz</td><td></td><td></td><td>L₁ • L₂</td></tr></table>	<div>Servo amplifier Power supply</div>	MR-J3-10A to 70A	MR-J3-100A to 350A	MR-J3-10A1 to 40A1	3-phase 200 to 230VAC, 50/60Hz	L ₁ • L ₂ • L ₃			1-phase 230VAC, 50/60Hz	L ₁ • L ₂			1-phase 100 to 120VAC, 50/60Hz			L ₁ • L ₂
<div>Servo amplifier Power supply</div>	MR-J3-10A to 70A	MR-J3-100A to 350A	MR-J3-10A1 to 40A1															
3-phase 200 to 230VAC, 50/60Hz	L ₁ • L ₂ • L ₃																	
1-phase 230VAC, 50/60Hz	L ₁ • L ₂																	
1-phase 100 to 120VAC, 50/60Hz			L ₁ • L ₂															
N	For manufacturer adjustment	Keep open.																
P ₁ P ₂	Power factor improving DC reactor	<div>When not using the power factor improving DC reactor, connect P₁-P₂. (Factory-wired.)</div> <div>When using the power factor improving DC reactor, disconnect the wiring across P₁-P₂ and connect the power factor improving DC reactor across P₁-P₂. (Refer to Section 12.8.)</div>																
P C D	Regenerative brake option	<div>When using the regenerative brake resistor built in the servo amplifier, connect P-D. (Factory-wired.)</div> <div>When using the regenerative brake option, disconnect the wiring across P-D and connect the regenerative brake option across P-C. (Refer to Section 12.2.)</div>																
L ₁₁ L ₂₁	Control circuit power supply	<div>Supply L₁₁ and L₂₁ with the following power.</div> <table><tr><td><div>Servo amplifier Power supply</div></td><td>MR-J3-10A to 350A</td><td>MR-J3-10A1 to 40A1</td></tr><tr><td>1-phase 200 to 230VAC, 50/60Hz</td><td>L₁₁ • L₂₁</td><td></td></tr><tr><td>1-phase 100 to 120VAC, 50/60Hz</td><td></td><td>L₁₁ • L₂₁</td></tr></table>	<div>Servo amplifier Power supply</div>	MR-J3-10A to 350A	MR-J3-10A1 to 40A1	1-phase 200 to 230VAC, 50/60Hz	L ₁₁ • L ₂₁		1-phase 100 to 120VAC, 50/60Hz		L ₁₁ • L ₂₁							
<div>Servo amplifier Power supply</div>	MR-J3-10A to 350A	MR-J3-10A1 to 40A1																
1-phase 200 to 230VAC, 50/60Hz	L ₁₁ • L ₂₁																	
1-phase 100 to 120VAC, 50/60Hz		L ₁₁ • L ₂₁																
U V W	Servo motor power	Connect to the servo motor power supply terminals (U, V, W).																
	Protective earth (PE)	Connect to the earth terminal of the servo motor and to the protective earth (PE) of the control box to perform grounding.																

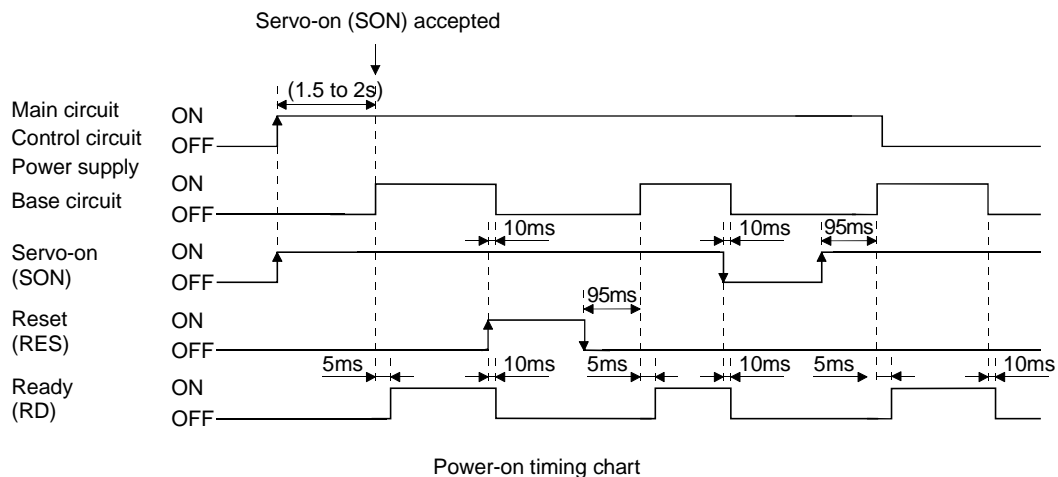
3. SIGNALS AND WIRING

3.3.2 Power-on sequence

(1) Power-on procedure

- 1) Always wire the power supply as shown in above Section 3.7.1 using the magnetic contactor with the main circuit power supply (three-phase 200V: L1, L2, L3, single-phase 230V • signal-phase 100V: L1, L2). Configure up an external sequence to switch off the magnetic contactor as soon as an alarm occurs.
- 2) Switch on the control circuit power supply L11, L21 simultaneously with the main circuit power supply or before switching on the main circuit power supply. If the main circuit power supply is not on, the display shows the corresponding warning. However, by switching on the main circuit power supply, the warning disappears and the servo amplifier will operate properly.
- 3) The servo amplifier can accept the servo-on (SON) about 1 to 2s after the main circuit power supply is switched on. Therefore, when SON is switched on simultaneously with the main circuit power supply, the base circuit will switch on in about 1 to 2s, and the ready (RD) will switch on in further about 20ms, making the servo amplifier ready to operate. (Refer to paragraph (2) in this section.)
- 4) When the reset (RES) is switched on, the base circuit is shut off and the servo motor shaft coasts.

(2) Timing chart



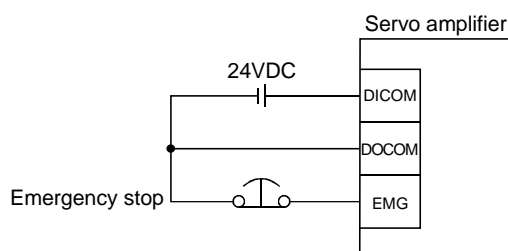
(3) Emergency stop

Make up a circuit that shuts off main circuit power as soon as EMG is turned off at an emergency stop. When EMG is turned off, the dynamic brake is operated to bring the servo motor to a sudden stop. At this time, the display shows the servo emergency stop warning (AL.E6).

During ordinary operation, do not use the external emergency stop (EMG) to alternate stop and run.

The servo amplifier life may be shortened.

Also, if the forward rotation start (ST1) and reverse rotation start (ST2) are on or a pulse train is input during an emergency stop, the servo motor will rotate as soon as the warning is reset. During an emergency stop, always shut off the run command.



3. SIGNALS AND WIRING

3.3.3 CNP1, CNP2, CNP3 wiring method

POINT

- Refer to Table 12.1 in Section 12.6 for the wire sizes used for wiring.

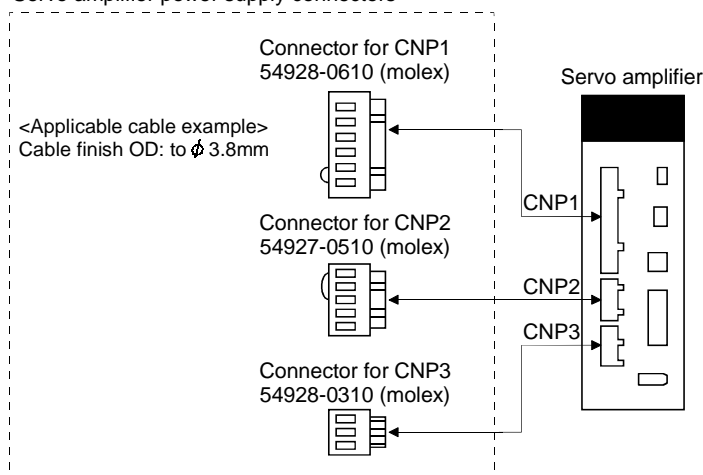
Use the supplied servo amplifier power supply connectors for wiring of CNP1, CNP2 and CNP3.

(1) MR-J3-100A or less

(a) Servo amplifier power supply connectors

(Note)

Servo amplifier power supply connectors



Note. These connectors are of insert type. As the crimping type, the following connectors (molex) are recommended.

For CNP1: 51241-0600 (connector), 56125-0118 (terminal)

For CNP2: 51240-0500 (connector), 56125-0118 (terminal)

For CNP3: 51241-0300 (connector), 56125-0118 (terminal)

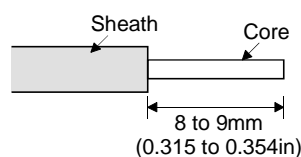
Crimping tool: CNP57349-5300

<Connector applicable cable example>

Cable finish OD: to ϕ 3.8mm

(b) Termination of the cables

Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a bar terminal may be used to put the wires together.

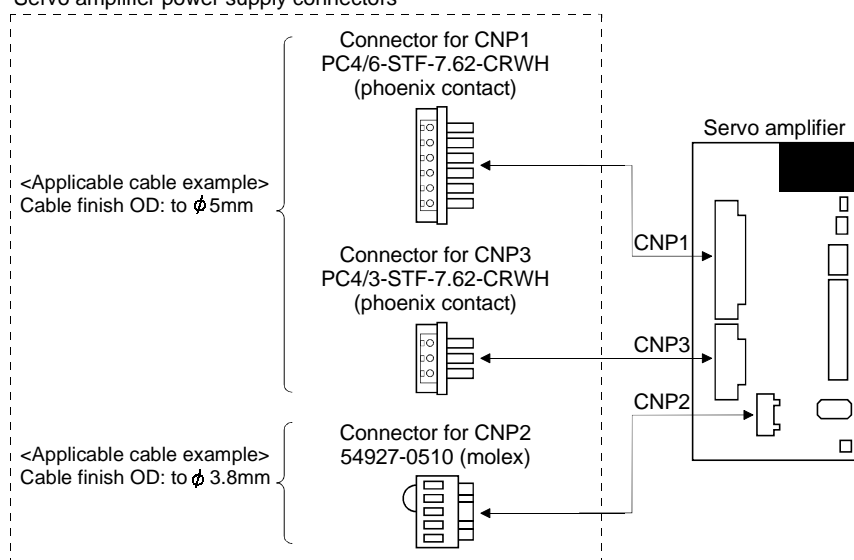
Cable size		Bar terminal type		Crimping tool	Maker
[mm ²]	AWG	For 1 cable	For 2 cables		
1.25	16	BT1.25-9-1		NH1	NICHIFU
		TUB-1.25		YHT-2210	JST
1.5	16	AI1.5-8BK	AI-TWIN2 \times 1.5-8BK AI-TWIN2 \times 1.5-12BK	CRIMPFOX-UD6	Phoenix Contact
2	14	BT2-9-1		NH1	NICHIFU
		TUB-2		YHT-2210	JST

3. SIGNALS AND WIRING

(2) MR-J3-200A • MR-J3-350A

(a) Servo amplifier power supply connectors

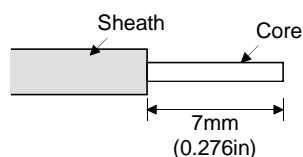
Servo amplifier power supply connectors



(b) Termination of the cables

1) CNP1 • CNP3

Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a bar terminal may be used to put the wires together.

Cable size		Bar terminal type		Crimping tool	Maker
[mm ²]	AWG	For 1 cable	For 2 cables		
0.34	22	AI0.34-8TQ		CRIMPFOX-ZA3	Phoenix Contact
0.5	20	AI0.5-8WH	AI-TWIN2 × 0.5-8WH		
0.75	18	AI0.75-8GY	AI-TWIN2 × 0.75-8GY		
1	18	AI1-8RD	AI-TWIN2 × 1-8RD		
1.5	16	AI1.5-8BK	AI-TWIN2 × 1.5-8BK		
2.5	14	AI2.5-8BU	AI-TWIN2 × 2.5-8BU		

2) CNP2

CNP2 is the same as MR-J3-100A or smaller capacities. Refer to (1) (b) in this section.

3. SIGNALS AND WIRING

(3) Insertion of cable into servo amplifier power supply connector

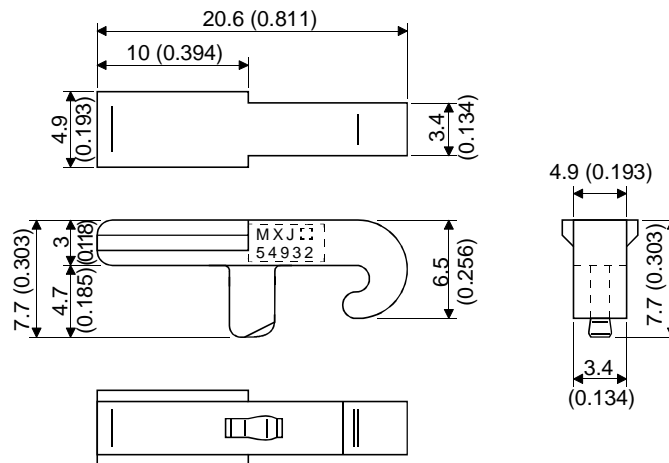
How to connect a cable to the servo amplifier power supply connector is shown below.

(a) When using the supplied cable connection lever

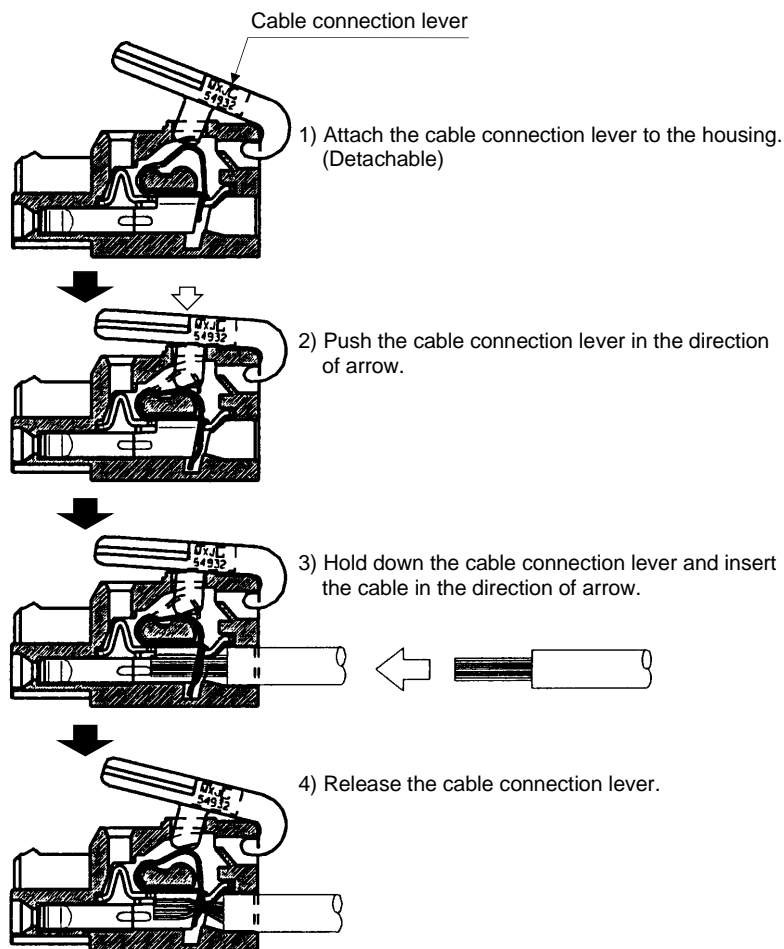
- 1) The servo amplifier is packed with the cable connection lever 54932-0000 (molex).

[Unit: mm]

[Unit: in]



2) Cable connection procedure



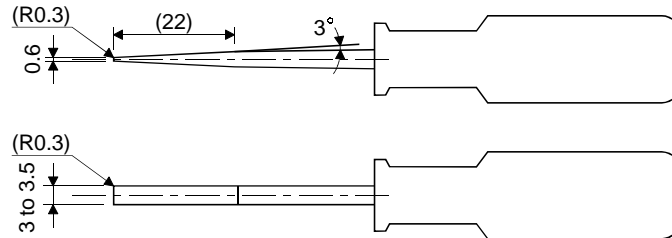
3. SIGNALS AND WIRING

(b) Inserting the cable into the connector

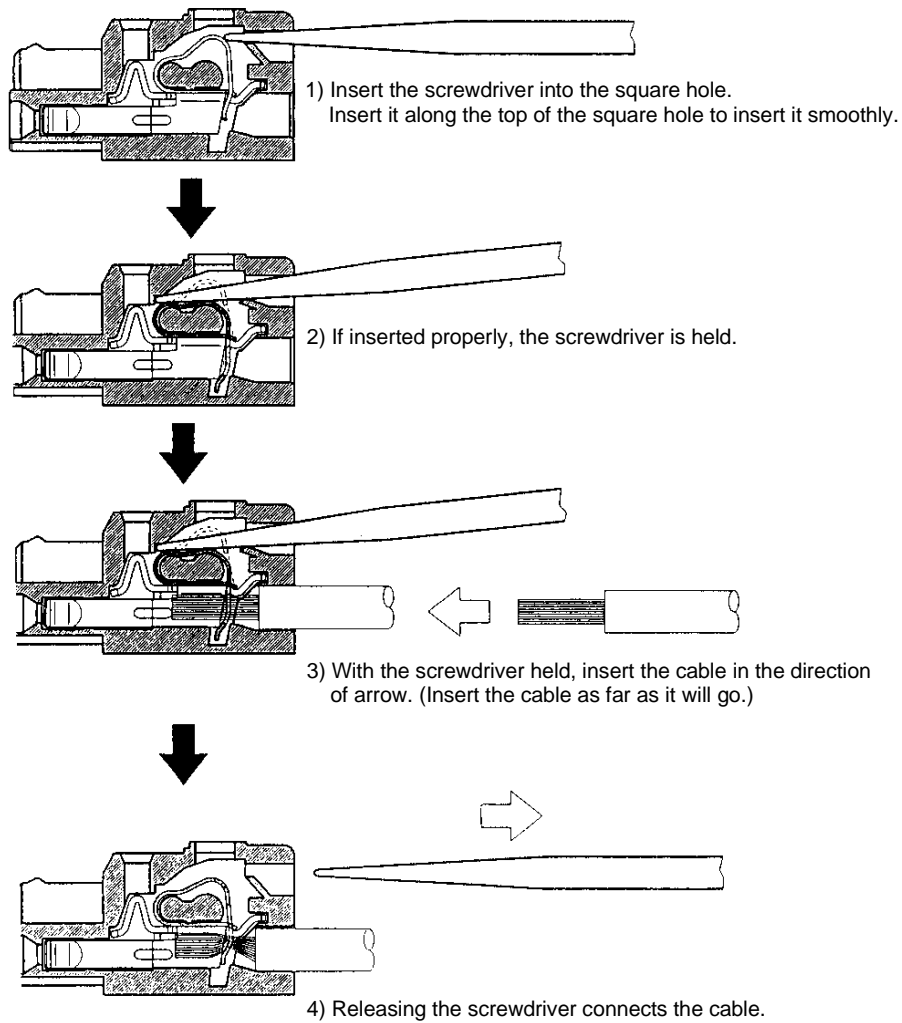
1) Applicable flat-blade screwdriver dimensions

Always use the screwdriver shown here to do the work.

[Unit: mm]

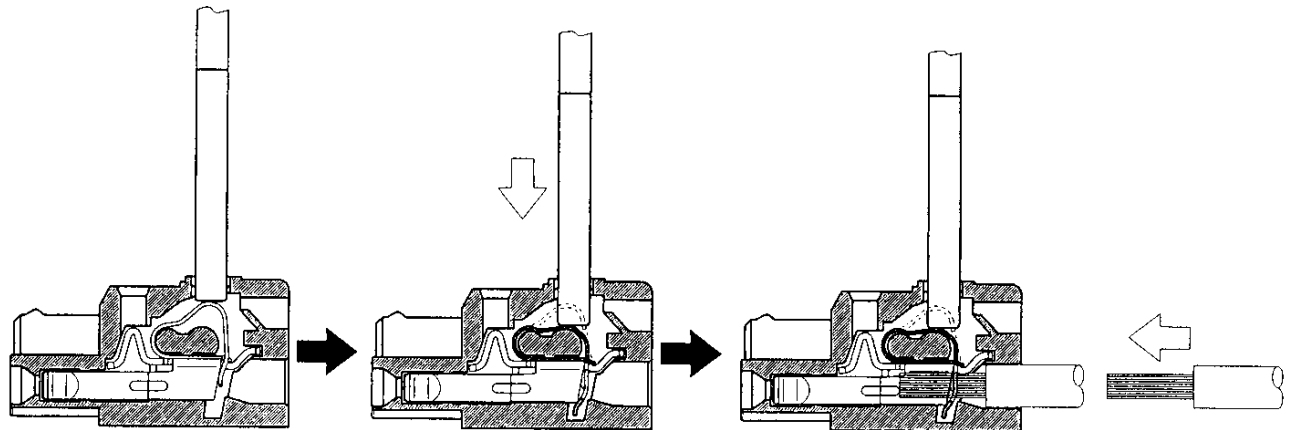


2) When using the flat-blade screwdriver - part 1



3. SIGNALS AND WIRING

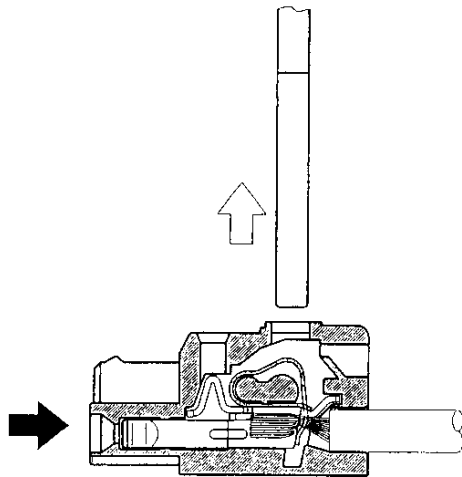
3) When using the flat-blade screwdriver - part 2



1) Insert the screwdriver into the square window at top of the connector.

2) Push the screwdriver in the direction of arrow.

3) With the screwdriver pushed, insert the cable in the direction of arrow. (Insert the cable as far as it will go.)

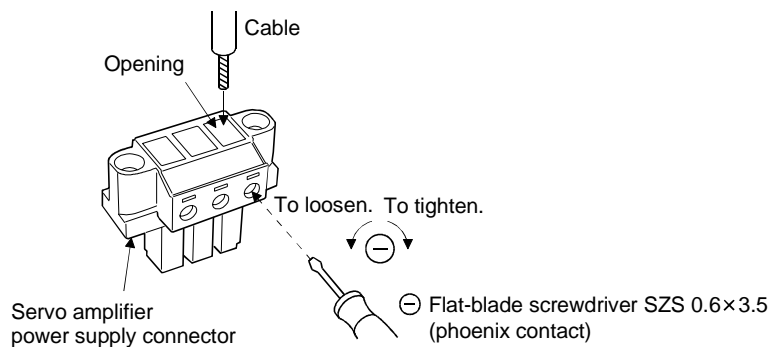


4) Releasing the screwdriver connects the cable.

(4) How to insert the cable into PC4/6-STF-7.62-CRWH or PC4/3-STF-7.62-CRWH connector

Insert the core of the cable into the opening and tighten the screw with a flat-blade screwdriver so that the cable does not come off. (Tightening torque: 0.5 to 0.6N m(4.425 to 5.31 lb in)) Before inserting the cable into the opening, make sure that the screw of the terminal is fully loose.

When using a cable of 1.5mm^2 or less, two cables may be inserted into one opening.



3. SIGNALS AND WIRING

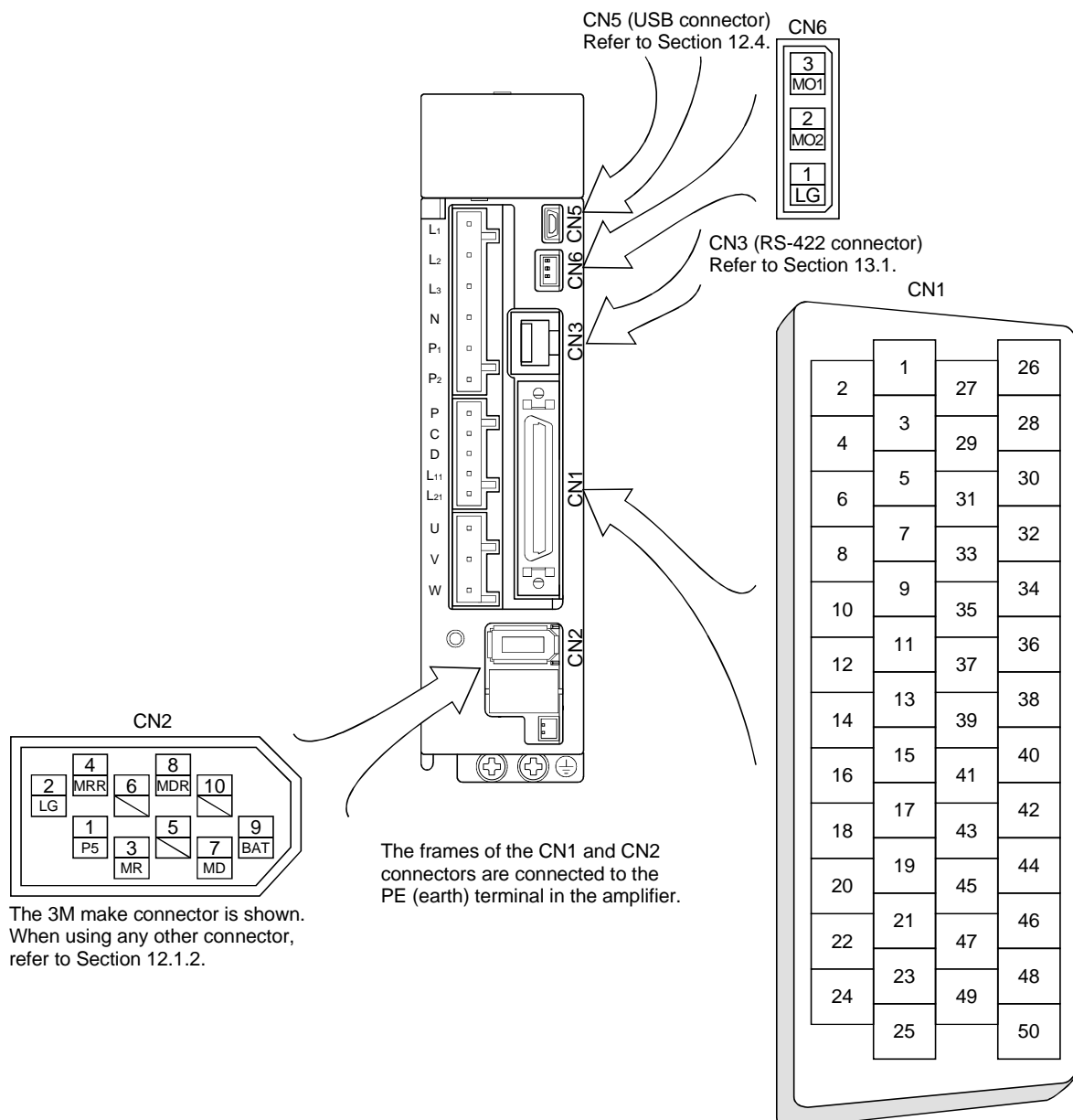
3.4 Connectors and signal arrangements

POINT

- The pin configurations of the connectors are as viewed from the cable connector wiring section.
- Refer to (2) in this section for CN1 signal assignment.

(1) Signal arrangement

The servo amplifier front view shown is that of the MR-J3-20A or less. Refer to Chapter 10 Outline Drawings for the appearances and connector layouts of the other servo amplifiers.



3. SIGNALS AND WIRING

(2) CN1 signal assignment

The signal assignment of connector changes with the control mode as indicated below;

For the pins which are given parameter No.s in the related parameter column, their signals can be changed using those parameters.

Pin No.	(Note 1) I/O	(Note 2) I/O Signals in Control Modes						Related Parameter No.
		P	P/S	S	S/T	T	T/P	
1		P15R	P15R	P15R	P15R	P15R	P15R	
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/-				-/PP	
11	I	PG	PG/-				-/PG	
12		OPC	OPC/-				-/OPC	
13								
14								
15	I	SON	SON	SON	SON	SON	SON	PD03
16	I		-/SP2	SP2	SP2/SP2	SP2	SP2/-	PD04
17	I	PC	PC/ST1	ST1	ST1/RS2	RS2	RS2/PC	PD05
18	I	TL	TL/ST2	ST2	ST2/RS1	RS1	RS1/TL	PD06
19	I	RES	RES	RES	RES	RES	RES	PD07
20		DICOM	DICOM	DICOM	DICOM	DICOM	DICOM	
21		DICOM	DICOM	DICOM	DICOM	DICOM	DICOM	
22	O	INP	INP/SA	SA	SA/-		-/INP	PD13
23	O	ZSP	ZSP	ZSP	ZSP	ZSP	ZSP	PD14
24	O	INP	INP/SA	SA	SA/-		-/INP	PD15
25	O	TLC	TLC	TLC	TLC/VLC	VLC	VLC/TLC	PD16
26								
27	I	TLA	(Note 3) TLA	(Note 3) TLA	(Note 3) TLA/TC	TC	TC/TLA	
28		LG	LG	LG	LG	LG	LG	
29								
30		LG	LG	LG	LG	LG	LG	
31								
32								
33	O	OP	OP	OP	OP	OP	OP	
34		LG	LG	LG	LG	LG	LG	
35	I	NP	NP/-				-/NP	
36	I	NG	NG/-				-/NG	
37								
38								
39								
40								
41	I	CR	CR/SP1	SP1	SP1/SP1	SP1	SP1/CR	PD08
42	I	EMG	EMG	EMG	EMG	EMG	EMG	
43	I	LSP	LSP	LSP	LSP/-		-/LSP	PD10
44	I	LSN	LSN	LSN	LSN/-		-/LSN	PD11
45	I	LOP	LOP	LOP	LOP	LOP	LOP	PD12

3. SIGNALS AND WIRING

Pin No.	(Note 1) I/O	(Note 2) I/O Signals in Control Modes						Related Parameter No.
		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	PD18
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 changeover mode, S/T: Speed/torque control changeover mode, T/P: Torque/position control changeover mode

3. TLA can be used when TL is made usable by setting the parameter No. PD03 to PD08/PD10 to PD12.

(3) Explanation of abbreviations

Abbreviation	Signal Name	Abbreviation	Signal Name
SON	Servo-on	TLC	Limiting torque
LSP	Forward rotation stroke end	VLC	Limiting speed
LSN	Reverse rotation stroke end	RD	Ready
CR	Clear	ZSP	Zero speed
SP1	Speed selection 1	INP	In-position
SP2	Speed selection 2	SA	Speed reached
PC	Proportion control	ALM	Trouble
ST1	Forward rotation start	WNG	Warning
ST2	Reverse rotation start	BWNG	Battery warning
TL	Torque limit selection	OP	Encoder Z-phase pulse (open collector)
RES	Reset	MBR	Electromagnetic brake interlock
EMG	Emergency stop	LZ	Encoder Z-phase pulse (differential line driver)
LOP	Control selection	LZR	
VC	Analog speed command	LA	Encoder A-phase pulse (differential line driver)
VLA	Analog speed limit	LAR	
TLA	Analog torque limit	LB	Encoder B-phase pulse (differential line driver)
TC	Analog torque command	LBR	
RS1	Forward rotation selection	DICOM	Digital I/F power supply input
RS2	Reverse rotation selection	OPC	Open collector power input
PP	Forward/reverse rotation pulse train	DOCOM	Digital I/F common
NP		P15R	15VDC power supply
PG		LG	Control common
NG		SD	Shield

3. SIGNALS AND WIRING

3.5 Signal explanations

For the I/O interfaces (symbols in I/O division column in the table), refer to Section 3.6.2.

In the control mode field of the table

P : Position control mode, S: Speed control mode, T: Torque control mode

○ : Denotes that the signal may be used in the initial setting status.

△ : Denotes that the signal may be used by setting the corresponding parameter No. PD03 to PD08, PD10 to PD12, PD13 to PD16, PD18.

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

(1) Input devices

Device	Symbol	Conne- tor pin No.	Functions/Applications	I/O division	Control mode																										
					P	S	T																								
Servo-on	SON	CN1-15	Turn SON on to power on the base circuit and make the servo amplifier ready to operate (servo-on). Turn it off to shut off the base circuit and coast the servo motor (servo off). Set "□□□4" in parameter No. PD01 to switch this signal on (keep terminals connected) automatically in the servo amplifier.	DI-1	○	○	○																								
Reset	RES	CN1-19	Turn RES on for more than 50ms to reset the alarm. Some alarms cannot be deactivated by the reset (RES). Refer to Section 9.2. 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 parameter No. PD20.	DI-1	○	○	○																								
Forward rotation stroke end	LSP	CN1-43	To start operation, turn LSP/LSN on. Turn it off to bring the motor to a sudden stop and make it servo-locked. Set "□□□1" in parameter No. PD20 to make a slow stop. (Refer to Section 5.4.3.) <table border="1"><tr><th colspan="2">(Note) Input signals</th><th colspan="2">Operation</th></tr><tr><th>LSP</th><th>LSN</th><th>CCW direction</th><th>CW direction</th></tr><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></table>	(Note) Input signals		Operation		LSP	LSN	CCW direction	CW direction	1	1	○	○	0	1		○	1	0	○		0	0			DI-1	○	○	
(Note) Input signals		Operation																													
LSP	LSN	CCW direction	CW direction																												
1	1	○	○																												
0	1		○																												
1	0	○																													
0	0																														
Reverse rotation stroke end	LSN	CN1-44	Note. 0: off 1: on Set parameter No. PD01 as indicated below to switch on the signals (keep terminals connected) automatically in the servo amplifier: <table border="1"><tr><th>Parameter No. PD01</th><th>Automatic ON</th></tr><tr><td>□4□□</td><td>LSP</td></tr><tr><td>□8□□</td><td>LSN</td></tr></table> When LPS or LSN turns OFF, an external stroke limit warning (AL. 99) occurs, and Warning (WNG) turns OFF. However, when using WNG, set the parameter No. PD13 to PD16/PD18 to make it usable.	Parameter No. PD01	Automatic ON	□4□□	LSP	□8□□	LSN																						
Parameter No. PD01	Automatic ON																														
□4□□	LSP																														
□8□□	LSN																														

3. SIGNALS AND WIRING

Device	Symbol	Conne- tor pin No.	Functions/Applications	I/O division	Control mode																			
					P	S	T																	
External torque limit selection	TL	CN1-18	Turn TL off to make Forward torque limit (parameter No. PA11) and Reverse torque limit (parameter No. PA12) valid, or turn it on to make Analog torque limit (TLA) valid. For details, refer to (5), Section 3.6.1.	DI-1	○	△																		
Internal torque limit selection	TL1		When using this signal, make it usable by making the setting of parameter No. PD03 to PD08, PD10 to PD12. For details, refer to (5), Section 3.6.1.	DI-1	△	△	△																	
Forward rotation start	ST1	CN1-17	Used to start the servo motor in any of the following directions: <table border="1"><thead><tr><th colspan="2">(Note) Input signals</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>	(Note) Input signals		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 signals		Servo motor starting direction																						
ST2	ST1																							
0	0	Stop (servo lock)																						
0	1	CCW																						
1	0	CW																						
1	1	Stop (servo lock)																						
Reverse rotation start	ST2	CN1-18	<table border="1"><tbody><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 parameter No. 12 setting and servo-locked.</p> <p>When "□□□1" is set in parameter No. PC23, the servo motor is not servo-locked after deceleration to a stop.</p>	0	1	CCW	1	0	CW	1	1	Stop (servo lock)												
0	1	CCW																						
1	0	CW																						
1	1	Stop (servo lock)																						
Forward rotation selection	RS1	CN1-18	Used to select any of the following servo motor torque generation directions: <table border="1"><thead><tr><th colspan="2">(Note) Input signals</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 driving mode / reverse rotation in regenerative mode</td></tr><tr><td>1</td><td>0</td><td>Reverse rotation in driving 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) Input signals		Torque generation direction	RS2	RS1	0	0	Torque is not generated.	0	1	Forward rotation in driving mode / reverse rotation in regenerative mode	1	0	Reverse rotation in driving mode / forward rotation in regenerative mode	1	1	Torque is not generated.	DI-1			○
(Note) Input signals		Torque generation direction																						
RS2	RS1																							
0	0	Torque is not generated.																						
0	1	Forward rotation in driving mode / reverse rotation in regenerative mode																						
1	0	Reverse rotation in driving mode / forward rotation in regenerative mode																						
1	1	Torque is not generated.																						
Reverse rotation selection	RS2	CN1-17	<table border="1"><tbody><tr><td>0</td><td>1</td><td>Forward rotation in driving mode / reverse rotation in regenerative mode</td></tr><tr><td>1</td><td>0</td><td>Reverse rotation in driving mode / forward rotation in regenerative mode</td></tr><tr><td>1</td><td>1</td><td>Torque is not generated.</td></tr></tbody></table> <p>Note. 0: off 1: on</p>	0	1	Forward rotation in driving mode / reverse rotation in regenerative mode	1	0	Reverse rotation in driving mode / forward rotation in regenerative mode	1	1	Torque is not generated.												
0	1	Forward rotation in driving mode / reverse rotation in regenerative mode																						
1	0	Reverse rotation in driving mode / forward rotation in regenerative mode																						
1	1	Torque is not generated.																						

3. SIGNALS AND WIRING

Device	Symbol	Conncetor pin No.	Functions/Applications	I/O division	Control mode																																																													
					P	S	T																																																											
Speed selection 1	SP1	CN1-41	<p><Speed control mode></p> <p>Used to select the command speed for operation.</p> <p>When using SP3, make it usable by making the setting of parameter No. PD03 to PD08, PD10 to PD12.</p>	DI-1		○	○																																																											
Speed selection 2	SP2	CN1-16	<table><tr><th colspan="3">(NOTE) Input signals</th><th rowspan="2">Speed command</th></tr><tr><th>SP3</th><th>SP2</th><th>SP1</th></tr><tr><td>0</td><td>0</td><td>0</td><td>Analog speed command (VC)</td></tr><tr><td>0</td><td>0</td><td>1</td><td>Internal speed command 1 (parameter No. PC05)</td></tr><tr><td>0</td><td>1</td><td>0</td><td>Internal speed command 2 (parameter No. PC06)</td></tr></table>	(NOTE) Input signals			Speed command	SP3	SP2	SP1	0	0	0	Analog speed command (VC)	0	0	1	Internal speed command 1 (parameter No. PC05)	0	1	0	Internal speed command 2 (parameter No. PC06)	DI-1		○	○																																								
(NOTE) Input signals			Speed command																																																															
SP3	SP2	SP1																																																																
0	0	0	Analog speed command (VC)																																																															
0	0	1	Internal speed command 1 (parameter No. PC05)																																																															
0	1	0	Internal speed command 2 (parameter No. PC06)																																																															
Speed selection 3	SP3		<table><tr><td>0</td><td>1</td><td>1</td><td>Internal speed command 3 (parameter No. PC07)</td></tr><tr><td>1</td><td>0</td><td>0</td><td>Internal speed command 4 (parameter No. PC08)</td></tr><tr><td>1</td><td>0</td><td>1</td><td>Internal speed command 5 (parameter No. PC09)</td></tr><tr><td>1</td><td>1</td><td>0</td><td>Internal speed command 6 (parameter No. PC10)</td></tr><tr><td>1</td><td>1</td><td>1</td><td>Internal speed command 7 (parameter No. PC11)</td></tr></table> <p>Note. 0: off 1: on</p> <p><Torque control mode></p> <p>Used to select the limit speed for operation.</p> <p>When using SP3, make it usable by making the setting of parameter No. PD03 to PD08, PD10 to PD12.</p> <table><tr><th colspan="3">(NOTE) Input signals</th><th rowspan="2">Speed limit</th></tr><tr><th>SP3</th><th>SP2</th><th>SP1</th></tr><tr><td>0</td><td>0</td><td>0</td><td>Analog speed limit (VLA)</td></tr><tr><td>0</td><td>0</td><td>1</td><td>Internal speed limit 1 (parameter No. PC05)</td></tr><tr><td>0</td><td>1</td><td>0</td><td>Internal speed limit 2 (parameter No. PC06)</td></tr><tr><td>0</td><td>1</td><td>1</td><td>Internal speed limit 3 (parameter No. PC07)</td></tr><tr><td>1</td><td>0</td><td>0</td><td>Internal speed limit 4 (parameter No. PC08)</td></tr><tr><td>1</td><td>0</td><td>1</td><td>Internal speed limit 5 (parameter No. PC09)</td></tr><tr><td>1</td><td>1</td><td>0</td><td>Internal speed limit 6 (parameter No. PC10)</td></tr><tr><td>1</td><td>1</td><td>1</td><td>Internal speed limit 7 (parameter No. PC11)</td></tr></table> <p>Note. 0: off 1: on</p>	0	1	1	Internal speed command 3 (parameter No. PC07)	1	0	0	Internal speed command 4 (parameter No. PC08)	1	0	1	Internal speed command 5 (parameter No. PC09)	1	1	0	Internal speed command 6 (parameter No. PC10)	1	1	1	Internal speed command 7 (parameter No. PC11)	(NOTE) Input signals			Speed limit	SP3	SP2	SP1	0	0	0	Analog speed limit (VLA)	0	0	1	Internal speed limit 1 (parameter No. PC05)	0	1	0	Internal speed limit 2 (parameter No. PC06)	0	1	1	Internal speed limit 3 (parameter No. PC07)	1	0	0	Internal speed limit 4 (parameter No. PC08)	1	0	1	Internal speed limit 5 (parameter No. PC09)	1	1	0	Internal speed limit 6 (parameter No. PC10)	1	1	1	Internal speed limit 7 (parameter No. PC11)	DI-1		△	△
0	1	1	Internal speed command 3 (parameter No. PC07)																																																															
1	0	0	Internal speed command 4 (parameter No. PC08)																																																															
1	0	1	Internal speed command 5 (parameter No. PC09)																																																															
1	1	0	Internal speed command 6 (parameter No. PC10)																																																															
1	1	1	Internal speed command 7 (parameter No. PC11)																																																															
(NOTE) Input signals			Speed limit																																																															
SP3	SP2	SP1																																																																
0	0	0	Analog speed limit (VLA)																																																															
0	0	1	Internal speed limit 1 (parameter No. PC05)																																																															
0	1	0	Internal speed limit 2 (parameter No. PC06)																																																															
0	1	1	Internal speed limit 3 (parameter No. PC07)																																																															
1	0	0	Internal speed limit 4 (parameter No. PC08)																																																															
1	0	1	Internal speed limit 5 (parameter No. PC09)																																																															
1	1	0	Internal speed limit 6 (parameter No. PC10)																																																															
1	1	1	Internal speed limit 7 (parameter No. PC11)																																																															

3. SIGNALS AND WIRING

Device	Symbol	Conne- ctor pin No.	Functions/Applications	I/O division	Control mode																			
					P	S	T																	
Proportion control	PC	CN1-17	Turn PC on to switch the speed amplifier from the proportional integral type to the proportional type. 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 proportion control (PC) upon positioning completion will suppress the unnecessary torque generated to compensate for a position shift. When the shaft is to be locked for a long time, switch on the proportion control (PC) and torque control (TL) at the same time to make the torque less than the rated by the analog torque limit.	DI-1	○	△																		
Emergency stop	EMG	CN1-42	Turn EMG on to bring the motor to an emergency stop state, in which the servo is switched off and the dynamic brake is operated. Turn EMG off in the emergency stop state to reset that state.	DI-1	○	○	○																	
Clear	CR	CN1-41	Turn CR on to clear the position control counter droop pulses on its leading edge. The pulse width should be 10ms or more. The delay amount set in parameter No. PB03 (position command acceleration/deceleration time constant) is also cleared. When the parameter No. 42 setting is "□□1□", the pulses are always cleared while CR is on.	DI-1	○																			
Electronic gear selection 1	CM1		When using CM1 and CM2, make them usable by the setting of parameters No. PD03 to PD08, PD10 to PD12. The combination of CM1 and CM2 gives you a choice of four different electronic gear numerators set in the parameters. CM1 and CM2 cannot be used in the absolute position detection system.	DI-1	△																			
Electronic gear selection 2	CM2		<table border="1"><thead><tr><th colspan="2">(Note) Input signals</th><th rowspan="2">Electronic gear molecule</th></tr><tr><th>CM2</th><th>CM1</th></tr></thead><tbody><tr><td>0</td><td>0</td><td>Parameter No. PA06</td></tr><tr><td>0</td><td>1</td><td>Parameter No. PC32</td></tr><tr><td>1</td><td>0</td><td>Parameter No. PC33</td></tr><tr><td>1</td><td>1</td><td>Parameter No. PC34</td></tr></tbody></table> <p>Note. 0: off 1: on</p>	(Note) Input signals		Electronic gear molecule	CM2	CM1	0	0	Parameter No. PA06	0	1	Parameter No. PC32	1	0	Parameter No. PC33	1	1	Parameter No. PC34	DI-1	△		
(Note) Input signals		Electronic gear molecule																						
CM2	CM1																							
0	0	Parameter No. PA06																						
0	1	Parameter No. PC32																						
1	0	Parameter No. PC33																						
1	1	Parameter No. PC34																						
Gain changing	CDP		When using this signal, make it usable by the setting of parameter No. PD03 to PD08, PD10 to PD12. Turn CDP on to change the load inertia moment ratio and gain values into the parameter No. PB29 to PB32 values.	DI-1	△	△	△																	

3. SIGNALS AND WIRING

Device	Symbol	Conne- tor pin No.	Functions/Applications	I/O division	Control mode																				
					P	S	T																		
Control change	LOP	CN1-45	<p><Position/speed control change mode> Used to select the control mode in the position/speed control change mode.</p> <table border="1"><tr><th>(Note) LOP</th><th>Control mode</th></tr><tr><td>0</td><td>Position</td></tr><tr><td>1</td><td>Speed</td></tr></table> <p>Note. 0: off 1: on</p> <p><Speed/torque control change mode> Used to select the control mode in the speed/torque control change mode.</p> <table border="1"><tr><th>(Note) LOP</th><th>Control mode</th></tr><tr><td>0</td><td>Speed</td></tr><tr><td>1</td><td>Torque</td></tr></table> <p>Note. 0: off 1: on</p> <p><Torque/position control mode> Used to select the control mode in the torque/position control change mode.</p> <table border="1"><tr><th>(Note) LOP</th><th>Control mode</th></tr><tr><td>0</td><td>Torque</td></tr><tr><td>1</td><td>Position</td></tr></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 Functions/ Appli- cations.		
(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>When using this signal, set the parameter No. PD03 to PD08/PD10 to PD12 to make it usable. This signal allows selection of the acceleration/deceleration time constant 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"><tr><th>(Note) STAB2</th><th>Acceleration/deceleration time constant</th></tr><tr><td>0</td><td>Acceleration time constant (parameter No. PC10) Deceleration time constant (parameter No. PC11)</td></tr><tr><td>1</td><td>Acceleration time constant 2 (parameter No. PC30) Deceleration time constant 2 (parameter No. PC31)</td></tr></table> <p>Note. 0: off 1: on</p>	(Note) STAB2	Acceleration/deceleration time constant	0	Acceleration time constant (parameter No. PC10) Deceleration time constant (parameter No. PC11)	1	Acceleration time constant 2 (parameter No. PC30) Deceleration time constant 2 (parameter No. PC31)	DI-1		△	△												
(Note) STAB2	Acceleration/deceleration time constant																								
0	Acceleration time constant (parameter No. PC10) Deceleration time constant (parameter No. PC11)																								
1	Acceleration time constant 2 (parameter No. PC30) Deceleration time constant 2 (parameter No. PC31)																								
ABS transfer mode	ABSM	CN1-17	<p>ABS transfer mode request device. The CN1-17 pin acts as ABSM only during absolute position data transfer. (Refer to Chapter 14.)</p>	DI-1	○																				
ABS request	ABSR	CN1-18	<p>ABS request device. The CN1-18 pin acts as ABSR only during absolute position data transfer. (Refer to Chapter 14.)</p>	DI-1	○																				

3. SIGNALS AND WIRING

(b) Output devices

Device	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Trouble	ALM	CN1-48	ALM turns off when power is switched off or the protective circuit is activated to shut off the base circuit. Without alarm occurring, ALM turns on within 1.5s after power-on.	DO-1	○	○	○
Ready	RD	CN1-49	RD turns on when the servo is switched on and the servo amplifier is ready to operate.	DO-1	○	○	○
In position	INP	CN1-24	INP turns on when the number of droop pulses is in the preset in-position range. The in-position range can be changed using parameter No. PA10. When the in-position range is increased, INP-SG may be kept connected during low-speed rotation. INP turns on when servo on turns on.	DO-1	○		
Speed reached	SA		SA turns off when servo on (SON) turns off or the servomotor speed has not reached the preset speed with both forward rotation start (ST1) and reverse rotation start (ST2) turned off. SA turns on when the servomotor speed has nearly reached the preset speed. When the preset speed is 30r/min or less, SA always turns on.	DO-1			
Limiting speed	VLC		VLC turns on when speed reaches the value limited using any of the internal speed limits 1 to 7 (parameter No. PC05 to PC11) or the analog speed limit (VLA) in the torque control mode. VLC turns off when servo on (SON) turns off.	DO-1			
Limiting torque	TLC	CN1-25	TLC turns on when the torque generated reaches the value set to the Forward torque limit (parameter No. PA11), Reverse torque limit (parameter No. PA12) or analog torque limit (TLA). TLC turns off when servo on (SON) turns off.	DO-1	○	○	
Zero speed	ZSP	CN1-23	ZSP turns on when the servo motor speed is zero speed (50r/min) or less. Zero speed can be changed using parameter No. PC17.	DO-1	○	○	○
Electromagnetic brake interlock	MBR		Set the parameter No. PD13 to PD16/PD18 or parameter No. PA04 to make this signal usable. Note that ZSP will be unusable. MBR turns off when the servo is switched off or an alarm occurs.	DO-1	△	△	△
Warning	WNG		To use this signal, assign the connector pin for output using parameter No. PD13 to PD16, PD18. The old signal before assignment will be unusable. When warning has occurred, WNG turns on. When there is no warning, WNG turns off within 1.5s after power-on.	DO-1	△	△	△
Battery warning	BWNG		To use this signal, assign the connector pin for output using parameter No. PD13 to PD16, PD18. The old signal before assignment will be unusable. BWNG turns on when battery cable breakage warning (AL. 92) or battery warning (AL. 9F) has occurred. When there is no battery warning, BWNG turns off within 1.5s after power-on.	DO-1	△	△	△

3. SIGNALS AND WIRING

Signal	Symbol	Conne- tor pin No.	Functions/Applications	I/O division	Control mode																																																																																									
					P	S	T																																																																																							
Alarm code	ACD 0	CN1-24	To use this signal, set "□□□1" in parameter No. PD24. This signal is output when an alarm occurs. When there is no alarm, respective ordinary signals (RD, INP, SA, ZSP) are output. Alarm codes and alarm names are listed below: <table border="1"><thead><tr><th colspan="3">(Note) Alarm code</th><th rowspan="2">Alarm display</th><th rowspan="2">Name</th></tr><tr><th>CN1-22</th><th>CN1-23</th><th>CN1-24</th></tr></thead><tbody><tr><td rowspan="9">0</td><td rowspan="9">0</td><td rowspan="9">0</td><td>88888</td><td>Watchdog</td></tr><tr><td>AL.12</td><td>Memory error 1</td></tr><tr><td>AL.13</td><td>Clock error</td></tr><tr><td>AL.15</td><td>Memory error 2</td></tr><tr><td>AL.17</td><td>Board error</td></tr><tr><td>AL.19</td><td>Memory error 3</td></tr><tr><td>AL.37</td><td>Parameter error</td></tr><tr><td>AL.8A</td><td>Serial communication timeout</td></tr><tr><td>AL.8E</td><td>Serial communication error</td></tr><tr><td>0</td><td>0</td><td>1</td><td>AL.30</td><td>Regenerative error</td></tr><tr><td></td><td></td><td></td><td>AL.33</td><td>Overvoltage</td></tr><tr><td>0</td><td>1</td><td>0</td><td>AL.10</td><td>Undervoltage</td></tr><tr><td rowspan="5">0</td><td rowspan="5">1</td><td rowspan="5">1</td><td>AL.45</td><td>Main circuit device overheat</td></tr><tr><td>AL.46</td><td>Servo motor overheat</td></tr><tr><td>AL.47</td><td>Cooling fan alarm</td></tr><tr><td>AL.50</td><td>Overload 1</td></tr><tr><td>AL.51</td><td>Overload 2</td></tr><tr><td>1</td><td>0</td><td>0</td><td>AL.24</td><td>Main circuit error</td></tr><tr><td></td><td></td><td></td><td>AL.32</td><td>Overcurrent</td></tr><tr><td rowspan="3">1</td><td rowspan="3">0</td><td rowspan="3">1</td><td>AL.31</td><td>Overspeed</td></tr><tr><td>AL.35</td><td>Command pulse frequency alarm</td></tr><tr><td>AL.52</td><td>Error excessive</td></tr><tr><td rowspan="4">1</td><td rowspan="4">1</td><td rowspan="4">0</td><td>AL.16</td><td>Encoder error 1</td></tr><tr><td>AL.1A</td><td>Monitor combination error</td></tr><tr><td>AL.20</td><td>Encoder error 2</td></tr><tr><td>AL.25</td><td>Absolute position erase</td></tr></tbody></table>	(Note) Alarm code			Alarm display	Name	CN1-22	CN1-23	CN1-24	0	0	0	88888	Watchdog	AL.12	Memory error 1	AL.13	Clock error	AL.15	Memory error 2	AL.17	Board error	AL.19	Memory error 3	AL.37	Parameter error	AL.8A	Serial communication timeout	AL.8E	Serial communication error	0	0	1	AL.30	Regenerative error				AL.33	Overvoltage	0	1	0	AL.10	Undervoltage	0	1	1	AL.45	Main circuit device overheat	AL.46	Servo motor overheat	AL.47	Cooling fan alarm	AL.50	Overload 1	AL.51	Overload 2	1	0	0	AL.24	Main circuit error				AL.32	Overcurrent	1	0	1	AL.31	Overspeed	AL.35	Command pulse frequency alarm	AL.52	Error excessive	1	1	0	AL.16	Encoder error 1	AL.1A	Monitor combination error	AL.20	Encoder error 2	AL.25	Absolute position erase	DO-1	△	△	△
	(Note) Alarm code			Alarm display	Name																																																																																									
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ACD 1	CN1-23																																																																																													
	ACD 2	CN1-22																																																																																												
Variable gain selection	CHGS		CHGS is on during variable gain.	DO-1	△	△	△																																																																																							
Absolute position erasing	ABSV		ABSV turns on when the absolute position is erased.	DO-1	△																																																																																									
ABS transmission data bit 0	ABSB0	CN1-22	Outputs ABS transmission data bit 0. CN1-22 acts as ABSB0 only during ABS transmission data transmission. (Refer to Chapter 14.)	DO-1	○																																																																																									
ABS transmission data bit 1	ABSB1	CN1-23	Outputs ABS transmission data bit 1. CN1-23 acts as ABSB1 only during ABS transmission data transmission. (Refer to Chapter 14.)	DO-1	○																																																																																									
ABS transmission data ready	ABST	CN1-25	Outputs ABS transmission data ready. CN1-25 acts as ABST only during ABS transmission data transmission. (Refer to Chapter 14.)	DO-1	○																																																																																									

3. SIGNALS AND WIRING

(2) Input signals

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Analog torque limit	TLA	CN1-27	To use this signal in the speed control mode, set any of parameters No. PD13 to PD16, PD18 to make TL available. When the analog torque limit (TLA) is valid, torque is limited in the full servo motor output torque range. Apply 0 to +10VDC across TLA-LG. Connect the positive terminal of the power supply to TLA. Maximum torque is generated at +10V. (Refer to (5) in Section 3.6.1.) Resolution:10bit	Analog input	○	△	
Analog torque command	TC		Used to control torque in the full servo motor output torque range. Apply 0 to ±8VDC across TC-LG. Maximum torque is generated at ±8V. (Refer to (1) in Section 3.6.3.) The torque at ±8V input can be changed using parameter No. PC13.	Analog input			○
Analog speed command	VC	CN1-2	Apply 0 to ±10VDC across VC-LG. Speed set in parameter No. PC12 is provided at ±10V. (Refer to (1) in Section 3.6.2.) Resolution:14bit or equivalent	Analog input		○	
Analog speed limit	VLA		Apply 0 to +10VDC across VLA-LG. Speed set in parameter No. PC12 is provided at +10V (Refer to (3) in Section 3.6.3.).	Analog input			○
Forward rotation pulse train Reverse rotation pulse train	PP NP PG NG	CN1-10 CN1-35 CN1-11 CN1-36	Used to enter a command pulse train. • In the open collector system (max. input frequency 200kpps): Forward rotation pulse train across PP-SG Reverse rotation pulse train across NP-SG • In the differential receiver system (max. input frequency 1Mpps): Forward rotation pulse train across PG-PP Reverse rotation pulse train across NG-NP The command pulse train form can be changed using parameter No. PA13.	DI-2	○		

(3) Output signals

Signal	Symbol	Connect or pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Encoder Z-phase pulse (Open collector)	OP	CN1-33	Outputs the zero-point signal of the encoder. One pulse is output per servo motor revolution. OP turns on when the zero-point position is reached. (Negative logic) The minimum pulse width is about 55μs. For home position return using this pulse, set the creep speed to 100r/min. or less.	DO-2	○	○	○
Encoder A-phase pulse (Differential line driver)	LA LAR	CN1-4 CN1-5	Outputs pulses per servo motor revolution set in parameter No. PA15 in the differential line driver system. In CCW rotation of the servo motor, the encoder B-phase pulse lags the encoder A-phase pulse by a phase angle of $\pi/2$.	DO-2	○	○	○
Encoder B-phase pulse (Differential line driver)	LB LBR	CN1-6 CN1-7	The relationships between rotation direction and phase difference of the A- and B-phase pulses can be changed using parameter No. PC19.				
Encoder Z-phase pulse (Differential line driver)	LZ LZR	CN1-8 CN1-9	The same signal as OP is output in the differential line driver system.	DO-2	○	○	○
Analog monitor 1	MO1	CN6-3	Used to output the data set in parameter No. PC14 to across MO1-LG in terms of voltage. Resolution 10 bits	Analog output	○	○	○
Analog monitor 2	MO2	CN6-2	Used to output the data set in parameter No. PC15 to across MO2-LG in terms of voltage. Resolution 10 bits	Analog output	○	○	○

3. SIGNALS AND WIRING

(4) Communication

POINT	
▪ Refer to Chapter 13 for the communication function.	

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
RS-422 I/F	SDP SDN RDP RDN	CN3-5 CN3-4 CN3-3 CN3-6	Terminals for RS-422 communication. (Refer to Chapter 13.)		○	○	○
RS-422 termination	TRE	CN3-8	Termination resistor connection terminal of RS-422 interface. When the servo amplifier is the termination axis, connect this terminal to RDN (CN3-6).		○	○	○

(5) Power supply

Signal	Symbol	Connector pin No.	Functions/Applications	I/O division	Control mode		
					P	S	T
Digital I/F power supply input	DICOM	CN1-20 CN1-21	Used to input 24VDC (300mA) for input interface. The power supply capacity changes depending on the number of I/O interface points to be used. Connect the positive terminal of the 24VDC external power supply. 24VDC±10%		○	○	○
Open collector power input	OPC	CN1-12	When inputting a pulse train in the open collector system, supply this terminal with the positive (+) power of 24VDC.		○	○	○
Digital I/F common	DOCOM	CN1-46 CN1-47	Common terminal for input signals such as SON and EMG. Pins are connected internally. Separated from LG.		○	○	○
15VDC power supply	P15R	CN1-1	Outputs 15VDC to across P15R-LG. Available as power for TC, TLA, VC, VLA. Permissible current: 30mA		○	○	○
Control common	LG	CN1-3 CN1-28 CN1-30 CN1-34 CN3-1 CN3-7 CN6-1	Common terminal for TLA, TC, VC, VLA, FPA, FPB, OP, MO1, MO2 and P15R. Pins are connected internally.		○	○	○
Shield	SD	Plate	Connect the external conductor of the shield cable.		○	○	○

3. SIGNALS AND WIRING

3.6 Detailed description of the signals

3.6.1 Position control mode

(1) Pulse train input

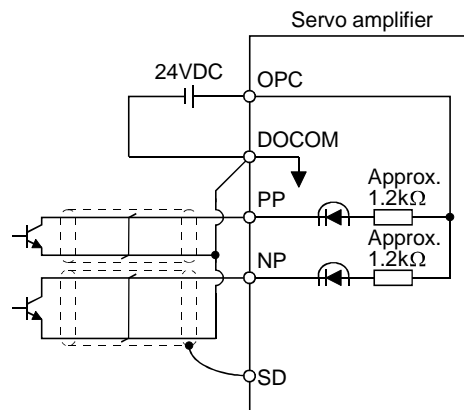
(a) Input pulse waveform selection

Command pulses may be input in any of three different forms, for which positive or negative logic can be chosen. Set the command pulse train form in parameter No. PA13. Refer to Section 5.1.10 for details.

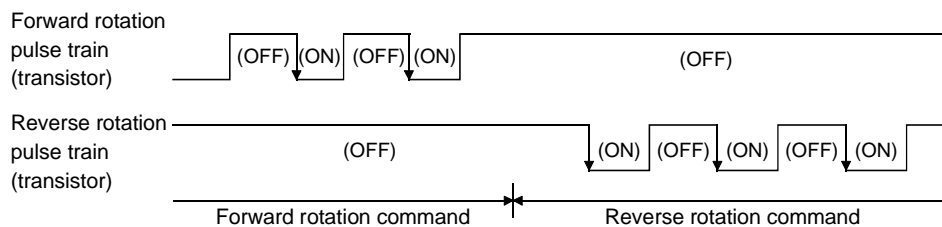
(b) Connections and waveforms

1) Open collector system

Connect as shown below:

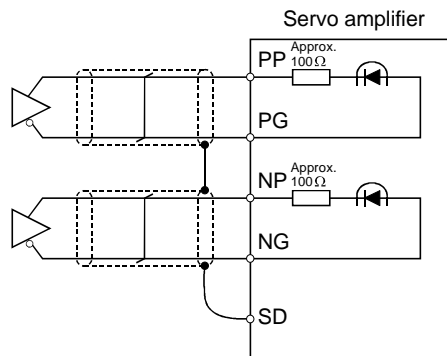


The explanation assumes that the input waveform has been set to the negative logic and forward and reverse rotation pulse trains (parameter No. PA13 has been set to 0010). Their relationships with transistor ON/OFF are as follows:



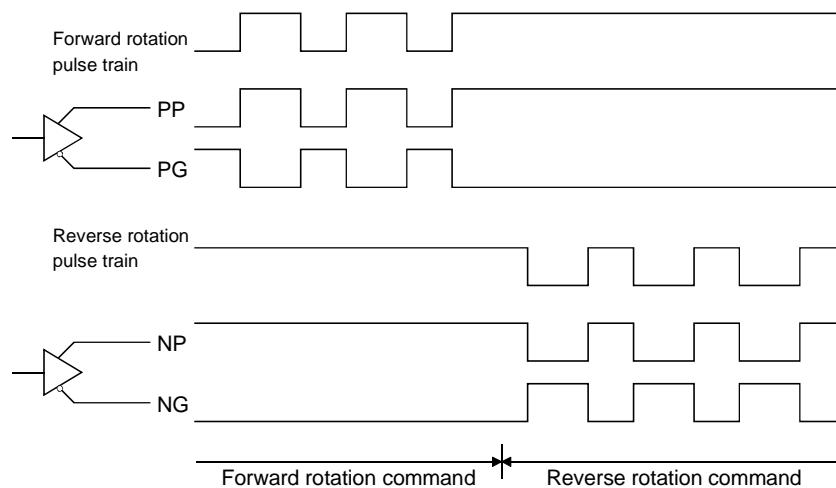
3. SIGNALS AND WIRING

- 2) Differential line driver system
Connect as shown below:



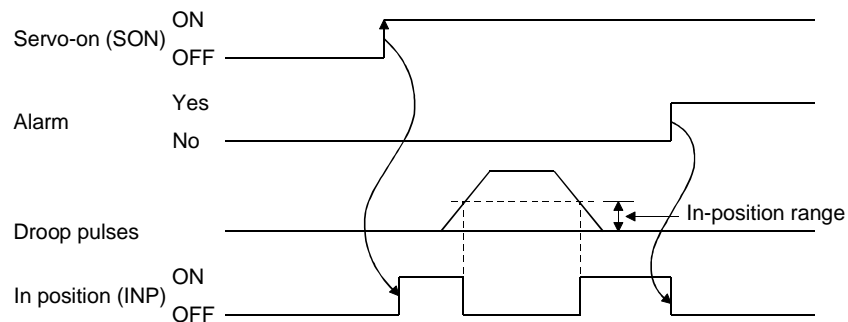
The explanation assumes that the input waveform has been set to the negative logic and forward and reverse rotation pulse trains (parameter No. PA13 has been set to 0010).

The waveforms of PP, PG, NP and NG are based on that of the ground of the differential line driver.



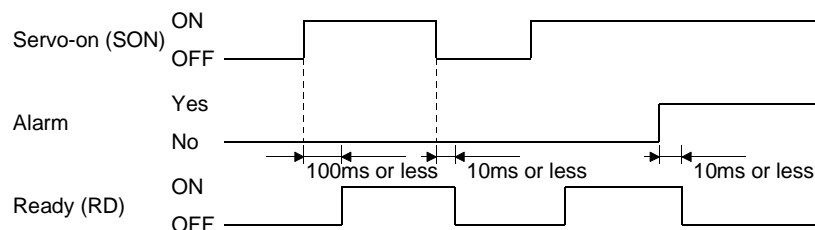
(2) In-position (INP)

PF-SG are connected when the number of droop pulses in the deviation counter falls within the preset in-position range (parameter No. PA16). INP turns on when low-speed operation is performed with a large value set as the in-position range.



3. SIGNALS AND WIRING

(3) Ready (RD)



(4) Electronic gear switching

The combination of CM1 and CM2 gives you a choice of four different electronic gear numerators set in the parameters.

As soon as CM1/CM2 is turned ON or OFF, the molecule of the electronic gear changes. Therefore, if any shock occurs at this change, use position smoothing (parameter No. PB03) to relieve shock.

(Note) External input signal		Electronic gear molecule
CM2	CM1	
0	0	Parameter No. PA06
0	1	Parameter No. PC32
1	0	Parameter No. PC33
1	1	Parameter No. PC34

Note. 0: off
1: on

(5) Torque limit

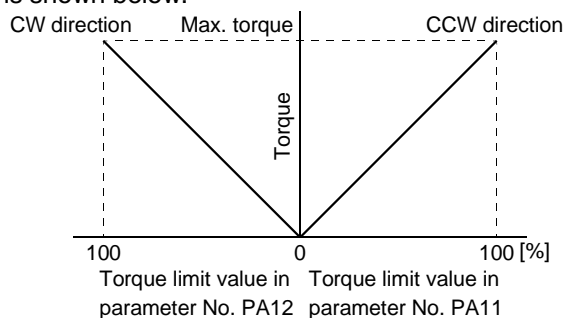


CAUTION

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

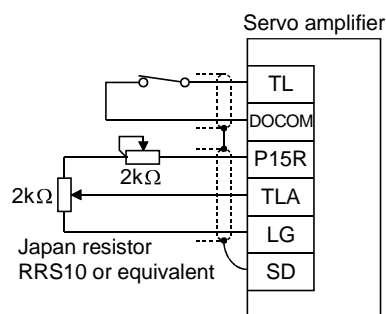
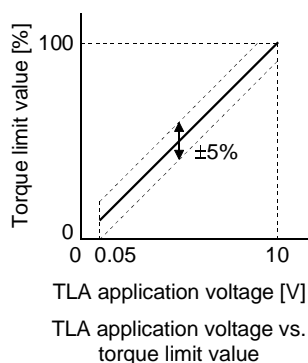
(a) Torque limit and torque

By setting parameter No. PA11 (forward torque limit) or parameter No. PA12 (reverse torque limit), torque is always limited to the maximum value during operation. A relationship between the limit value and servo motor torque is shown below.



A relationship between the applied voltage of the analog torque limit (TLA) and the torque limit value of the servo motor is shown below. Torque limit values will vary about 5% relative to the voltage depending on products.

At the voltage of less than 0.05V, torque may vary as it may not be limited sufficiently. Therefore, use this function at the voltage of 0.05V or more.



3. SIGNALS AND WIRING

(b) Torque limit value selection

As shown below, the forward torque limit (parameter No. PA11), or reverse torque limit (parameter No. PA12) and the analog torque limit (TLA) can be chosen using the external torque limit selection (TL). When internal torque limit selection (TL1) is made usable by parameter No. PD03 to PD08, PD10 to PD12, internal torque limit 2 (parameter No. PC35) can be selected. However, if the parameter No. PA11 and parameter No. PA12 value is less than the limit value selected by TL/TL1, the parameter No. PA11 and parameter No. PA12 value is made valid.

(Note) External Input Signals		Limit Value Status	Validated Torque Limit Values	
TL1	TL		CCW driving/CW regeneration	CW driving/CCW regeneration
0	0		Parameter No. PA11	Parameter No. PA12
0	1	TLA > Parameter No. PA11 Parameter No. PA12	Parameter No. PA11	Parameter No. PA12
		TLA < Parameter No. PA11 Parameter No. PA12	TLA	TLA
1	0	Parameter No. PC35 > Parameter No. PA11 Parameter No. PA12	Parameter No. PA11	Parameter No. PA12
		Parameter No. PC35 < Parameter No. PA11 Parameter No. PA12	Parameter No. PC35	Parameter No. PC35
1	1	Parameter No. PC35 > TLA	Parameter No. PC35	Parameter No. PC35
		Parameter No. PC35 < TLA	TLA	TLA

Note. 0: off
1: on

(c) Limiting torque (TLC)

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

3. SIGNALS AND WIRING

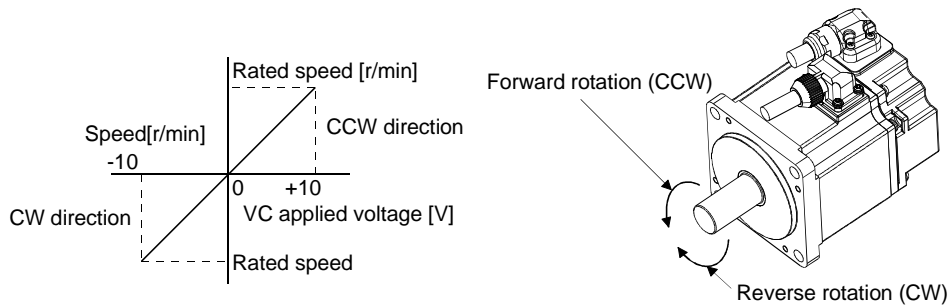
3.6.2 Speed control mode

(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 the analog speed command (VC). A relationship between the analog speed command (VC) applied voltage and the servo motor speed is shown below:

The maximum speed is achieved at $\pm 10\text{V}$. The speed at $\pm 10\text{V}$ can be changed using parameter No. PC12.



The following table indicates the rotation direction according to forward rotation start (ST1) and reverse rotation start (ST2) combination:

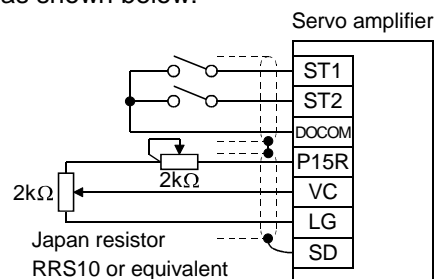
(Note1) External input signals		(Note2) Rotation direction			
ST2	ST1	Analog speed command (VC)			Internal speed commands
		+ Polarity	0V	- Polarity	
0	0	Stop (Servo lock)	Stop (Servo lock)	Stop (Servo lock)	Stop (Servo lock)
0	1	CCW	Stop (No servo lock)	CW	CCW
1	0	CW		CCW	CW
1	1	Stop (Servo lock)	Stop (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 servomotor may suddenly rotate according to position deviation in respect to the command position.

Generally, make connection as shown below:



3. SIGNALS AND WIRING

(b) Speed selection 1 (SP1), speed selection 2 (SP2) and speed command value

Choose any of the speed settings made by the internal speed commands 1 to 3 using speed selection 1 (SP1) and speed selection 2 (SP2) or the speed setting made by the analog speed command (VC).

(Note) External input signals		Speed command value
SP2	SP1	
0	0	Analog speed command (VC)
0	1	Internal speed command 1 (parameter No. PC05)
1	0	Internal speed command 2 (parameter No. PC06)
1	1	Internal speed command 3 (parameter No. PC07)

Note. 0: off

1: on

By making speed selection 3 (SP3) usable by setting of parameter No. 43 to 48, you can choose the speed command values of analog speed command (VC) and internal speed commands 1 to 7.

(Note) External input signals			Speed command value
SP3	SP2	SP1	
0	0	0	Analog speed command (VC)
0	0	1	Internal speed command 1 (parameter No. PC05)
0	1	0	Internal speed command 2 (parameter No. PC06)
0	1	1	Internal speed command 3 (parameter No. PC07)
1	0	0	Internal speed command 4 (parameter No. PC08)
1	0	1	Internal speed command 5 (parameter No. PC09)
1	1	0	Internal speed command 6 (parameter No. PC10)
1	1	1	Internal speed command 7 (parameter No. PC11)

Note. 0: off

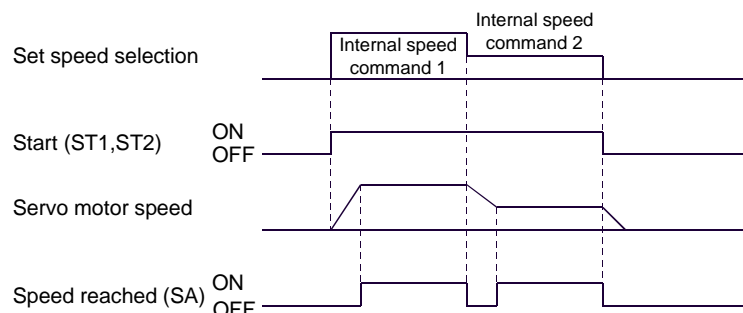
1: on

The speed may be changed during rotation. In this case, the values set in parameters No. PC10, PC11 and 12 are used for acceleration/deceleration.

When the speed has been specified under any internal speed command, it does not vary due to the ambient temperature.

(2) Speed reached (SA)

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

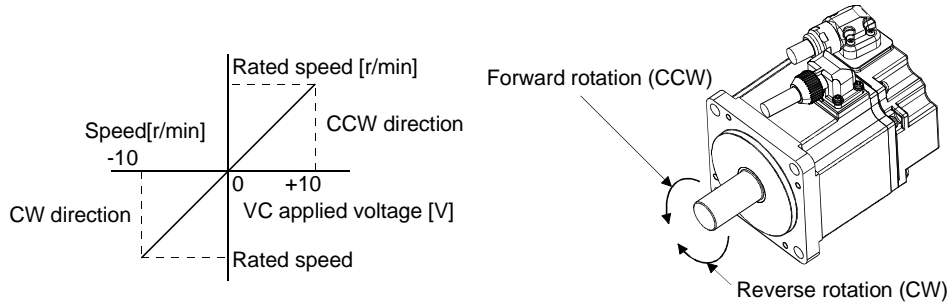
3.6.3 Torque control mode

(1) Torque control

(a) Torque command and torque

A relationship between the applied voltage of the analog torque command (TC) and the torque by the servo motor is shown below.

The maximum torque is generated at $\pm 8V$. Note that the torque at $\pm 8V$ input can be changed with parameter No. PC13.



Generated torque limit values will vary about 5% relative to the voltage depending on products.

Also the torque may vary if the voltage is low (-0.05 to $+0.05V$) and the actual speed is close to the limit value. In such a case, increase the speed limit value.

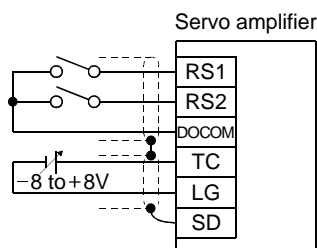
The following table indicates the torque generation directions determined by the forward rotation selection (RS1) and reverse rotation selection (RS2) when the analog torque command (TC) is used.

(Note) External input signals		Rotation direction		
RS2	RS1	Torque control command (TC)		
		+ Polarity	0V	— Polarity
0	0	Torque is not generated.	Torque is not generated.	Torque is not generated.
0	1	CCW (reverse rotation in driving mode/forward rotation in regenerative mode)		CW (forward rotation in driving mode/reverse rotation in regenerative mode)
1	0	CW (forward rotation in driving mode/reverse rotation in regenerative mode)		CCW (reverse rotation in driving mode/forward rotation in regenerative mode)
1	1	Torque is not generated.		Torque is not generated.

Note. 0: off

1: on

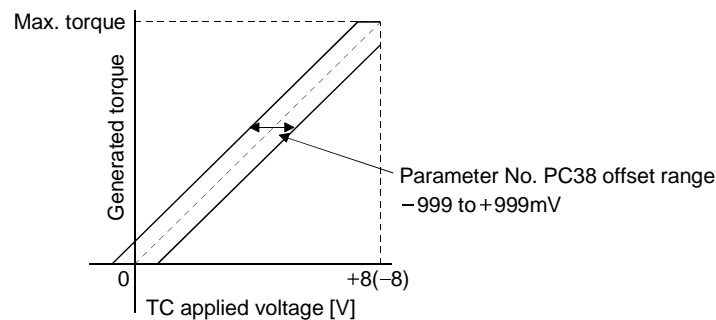
Generally, make connection as shown below:



3. SIGNALS AND WIRING

(b) Analog torque command offset

Using parameter No. PC38, the offset voltage of -999 to $+999\text{mV}$ can be added to the TC applied voltage as shown below.



(2) Torque limit

By setting parameter No. PA11 (forward torque limit) or parameter No. PA12 (reverse torque limit), torque is always limited to the maximum value during operation. A relationship between limit value and servo motor torque is as in (5) in section 3.4.1. Note that the analog torque limit (TLA) is unavailable.

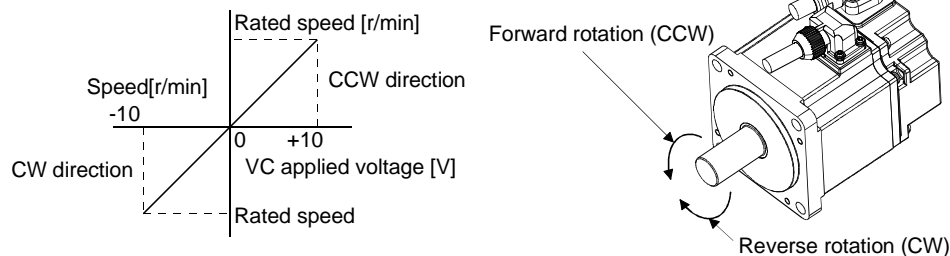
(3) Speed limit

(a) Speed limit value and speed

The speed is limited to the values set in parameters No. PC05 to PC11 (internal speed limits 1 to 7) or the value set in the applied voltage of the analog speed limit (VLA).

A relationship between the analog speed limit (VLA) applied voltage and the servo motor speed is shown below.

When the servo motor speed reaches the speed limit value, torque control may become unstable. Make the set value more than 100r/min greater than the desired speed limit value.

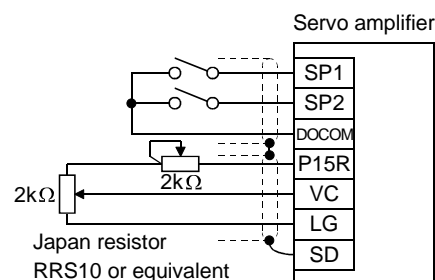


The following table indicates the limit direction according to forward rotation selection (RS1) and reverse rotation selection (RS2) combination:

(Note) External input signals		Speed limit direction		
RS1	RS2	Analog speed limit (VLA)		Internal speed commands
		+ Polarity	- Polarity	
1	0	CCW	CW	CCW
0	1	CW	CCW	CW

Note. 0: off
1: on

Generally, make connection as shown below:



3. SIGNALS AND WIRING

(b) Speed selection 1(SP1)/speed selection 2(SP2)/speed selection 3(SP3) and speed limit values

Choose any of the speed settings made by the internal speed limits 1 to 7 using speed selection 1(SP1), speed selection 2(SP2) and speed selection 3(SP3) or the speed setting made by the speed limit command (VLA), as indicated below.

(Note) Input signals			Speed limit value
SP3	SP2	SP1	
0	0	0	Analog speed limit (VLA)
0	0	1	Internal speed limit 1 (parameter No. PC05)
0	1	0	Internal speed limit 2 (parameter No. PC06)
0	1	1	Internal speed limit 3 (parameter No. PC07)
1	0	0	Internal speed limit 4 (parameter No. PC08)
1	0	1	Internal speed limit 5 (parameter No. PC09)
1	1	0	Internal speed limit 6 (parameter No. PC10)
1	1	1	Internal speed limit 7 (parameter No. PC11)

Note. 0: off

1: on

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

(c) Limiting speed (VLC)

VLC turns on when the servo motor speed reaches the speed limited using any of the internal speed limits 1 to 7 or the analog speed limit (VLA).

3. SIGNALS AND WIRING

3.6.4 Position/speed control change mode

Set "□□□ 1" in parameter No. PA01 to switch to the position/speed control change mode. This function is not available in the absolute position detection system.

(1) Control change (LOP)

Use control change (LOP) to switch between the position control mode and the speed control mode from an external contact. Relationships between LOP and control modes are indicated below:

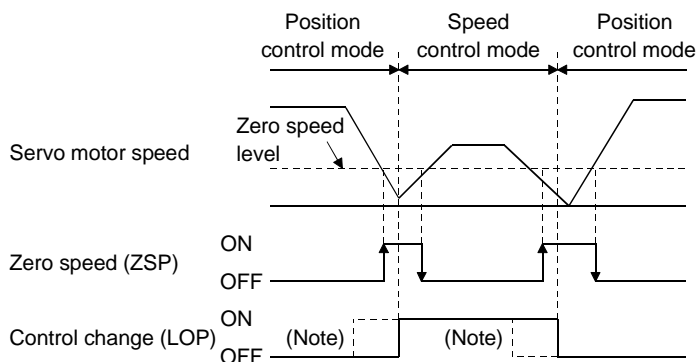
(Note) LOP	Servo control mode
0	Position control mode
1	Speed control mode

Note. 0: off

1: on

The control mode may be changed in the zero-speed status. To ensure safety, change control after the servo motor has stopped. When position control mode is changed to speed control mode, droop pulses are reset.

If the signal has been switched on-off at the speed higher than the zero speed and the speed is then reduced to the zero speed or less, the control mode cannot be changed. A change timing chart is shown below:



Note. When ZSP is not on, control cannot be changed if LOP is switched on-off.
If ZSP switches on after that, control cannot not be changed.

(2) Torque limit in position control mode

As in Section 3.6.1 (5).

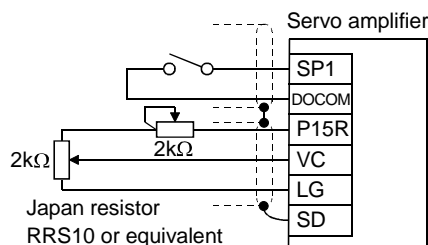
3. SIGNALS AND WIRING

(3) Speed setting in speed control mode

(a) Speed command and speed

The servo motor is run at the speed set in parameter No. 8 (internal speed command 1) or at the speed set in the applied voltage of the analog speed command (VC). A relationship between analog speed command (VC) applied voltage and servo motor speed and the rotation directions determined by the forward rotation start (ST1) and reverse rotation start (ST2) are as in (a), (1) in section 3.6.2.

Generally, make connection as shown below:



(b) Speed selection 1 (SP1) and speed command value

Use speed selection 1 (SP1) to select between the speed set by the internal speed command 1 and the speed set by the analog speed command (VC) as indicated in the following table:

(Note) External input signals	
SP1	Speed command value
0	Analog speed command (VC)
1	Internal speed command 1 (parameter No. PC05)

Note. 0: off

1: on

The speed may also be changed during rotation. In this case, it is increased or decreased according to the value set in parameter No. PC01 or PC02.

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

(c) Speed reached (SA)

As in Section 3.6.2 (2).

3. SIGNALS AND WIRING

3.6.5 Speed/torque control change mode

Set "□□□3" in parameter No. PA01 to switch to the speed/torque control change mode.

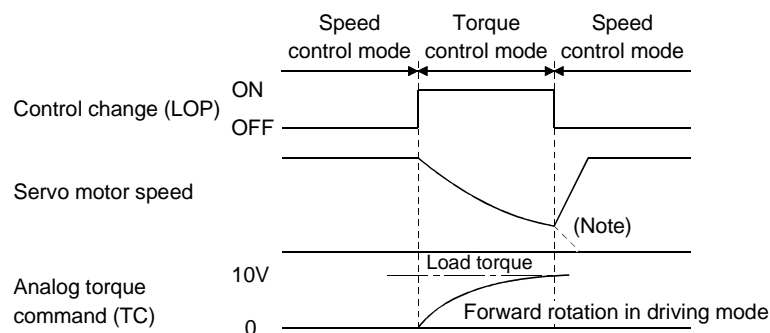
(1) Control change (LOP)

Use control change (LOP) to switch between the speed control mode and the torque control mode from an external contact. Relationships between LOP and control modes are indicated below:

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

Note. 0: off
1: on

The control mode may be changed at any time. A change timing chart is shown below:



Note. When the start (ST1・ST2) is switched off as soon as the mode is changed to speed control, the servo motor comes to a stop according to the deceleration time constant.

(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).

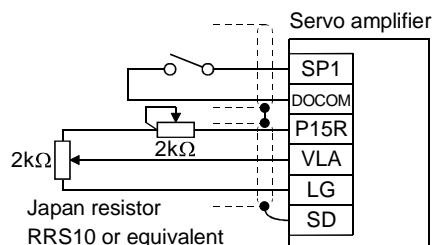
3. SIGNALS AND WIRING

(4) Speed limit in torque control mode

(a) Speed limit value and speed

The speed is limited to the limit value set in parameter No. 8 (internal speed limit 1) or the value set in the applied voltage of the analog speed limit (VLA). A relationship between the analog speed limit (VLA) applied voltage and the servo motor speed is as in (a), (3) in section 3.6.3.

Generally, make connection as shown below:



(b) Speed selection 1 (SP1) and speed limit value

Use speed selection 1 (SP1) to select between the speed set by the internal speed command 1 and the speed set by the analog speed limit (VLA) as indicated in the following table:

(Note) External input signals	Speed command value
SP1	
0	Analog speed limit (VLA)
1	Internal speed limit 1 (parameter No. PC05)

Note. 0: off

1: on

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

(c) Limiting speed (VLC)

As in (c), (3) in section 3.6.3.

(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 change mode

Set "□□□5" in parameter No. PA01 to switch to the torque/position control change mode.

(1) Control change (LOP)

Use control change (LOP) to switch between the torque control mode and the position control mode from an external contact. Relationships between LOP and control modes are indicated below:

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

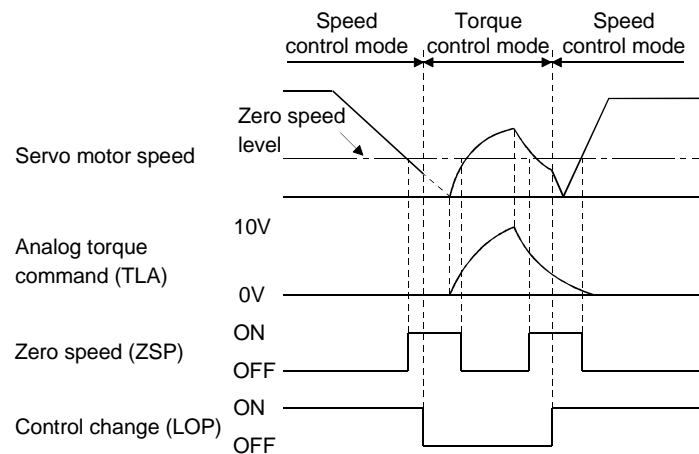
Note. 0: off

1: on

The control mode may be changed in the zero-speed status.

To ensure safety, change control after the servo motor has stopped. When position control mode is changed to torque control mode, droop pulses are reset.

If the signal has been switched on-off at the speed higher than the zero speed and the speed is then reduced to the zero speed or less, the control mode cannot be changed. A change timing chart is shown below:



(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

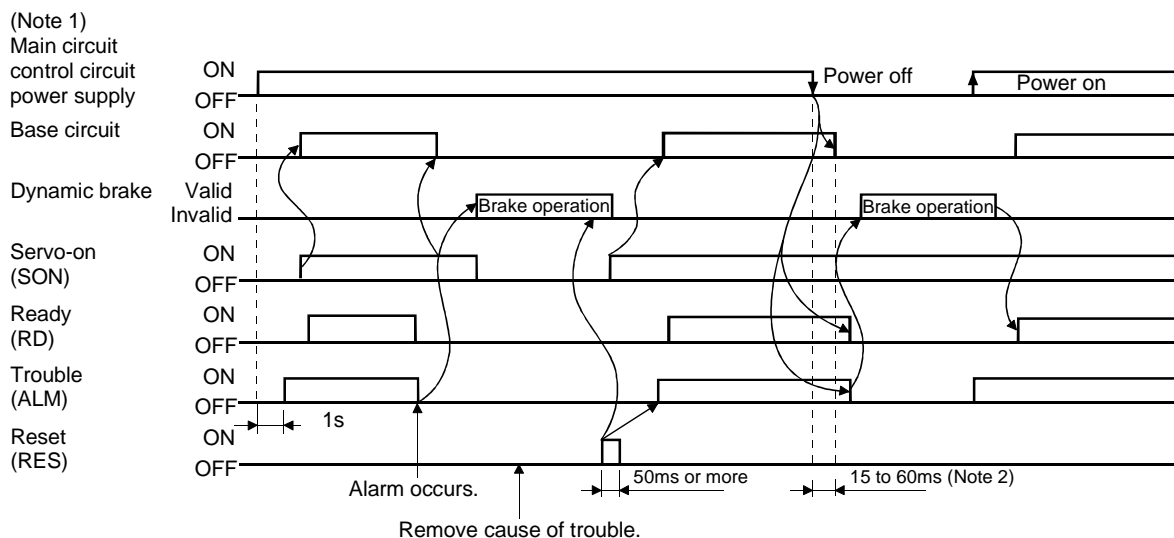
3.7 Alarm occurrence timing chart



CAUTION

- 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.
- As soon as an alarm occurs, turn off Servo-on (SON) and power off the main circuit and control circuit.

When an alarm occurs in the servo amplifier, the base circuit is shut off and the servo motor is coasted to a stop. Switch off the main circuit power supply in the external sequence. To reset the alarm, switch the control circuit power supply from off to on, press the "SET" button on the current alarm screen, or turn the reset (RES) from off to on. However, the alarm cannot be reset unless its cause is removed.



Note 1. Shut off the main circuit power as soon as an alarm occurs.

2. Changes depending on the operating status.

(1) Overcurrent, overload 1 or overload 2

If operation is repeated by switching control circuit power off, then on to reset the overcurrent (AL.32), overload 1 (AL.50) or overload 2 (AL.51) alarm after its occurrence, without removing its cause, the servo amplifier and servo motor may become faulty due to temperature rise. Securely remove the cause of the alarm and also allow about 30 minutes for cooling before resuming operation.

(2) Regenerative alarm

If operation is repeated by switching control circuit power off, then on to reset the regenerative (AL.30) alarm after its occurrence, the external regenerative brake resistor will generate heat, resulting in an accident.

(3) Instantaneous power failure

Undervoltage (AL.10) occurs when the input power is in either of the following statuses.

A power failure of the control circuit power supply continues for 60ms or longer and the control circuit is not completely off. The bus voltage dropped to 200VDC or less for the MR-J3-□A, or to 158VDC or less for the MR-J3-□A1.

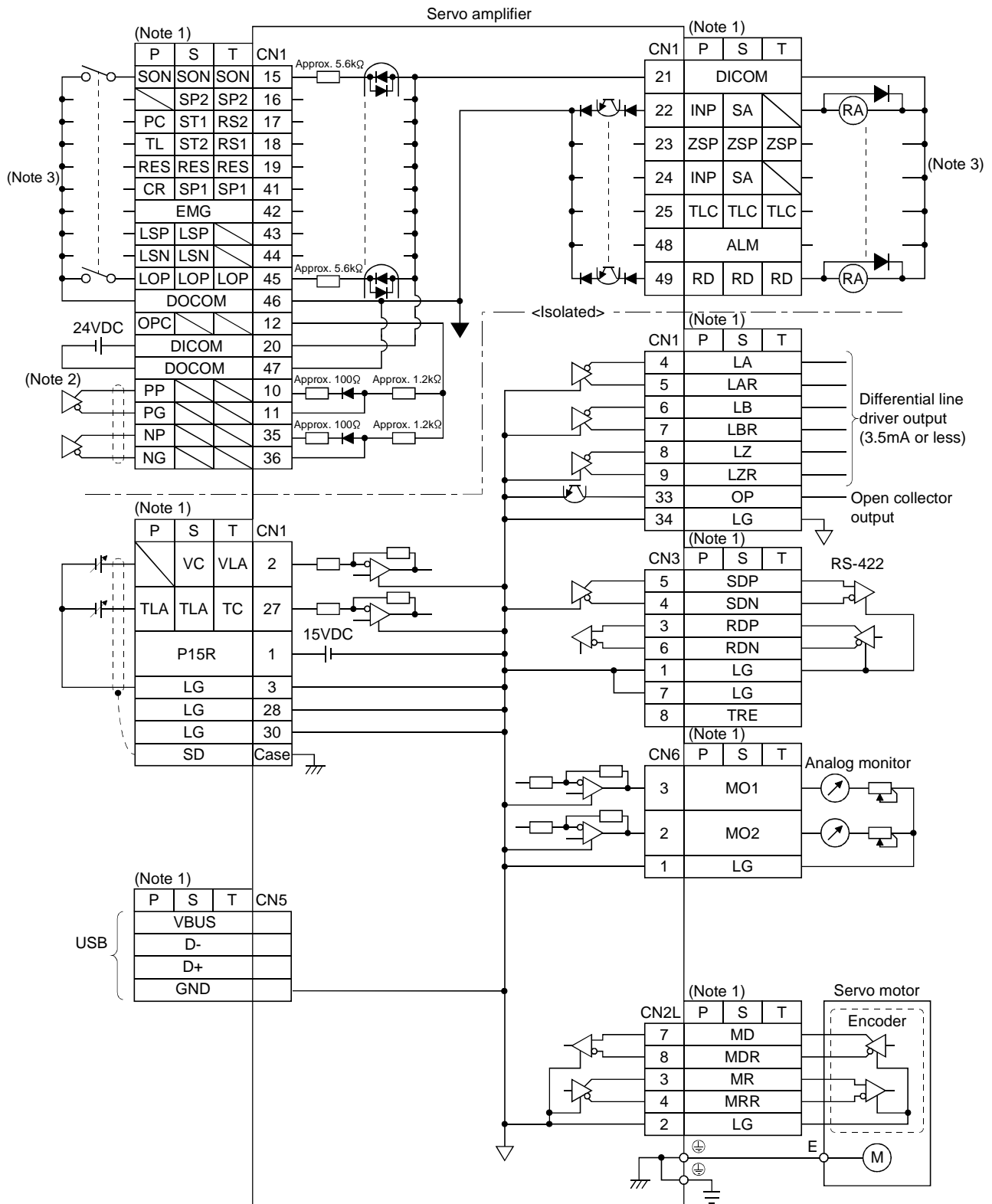
(4) In position control mode (incremental)

When an alarm occurs, the home position is lost. When resuming operation after deactivating the alarm, make a home position return.

3. SIGNALS AND WIRING

3.8 Interfaces

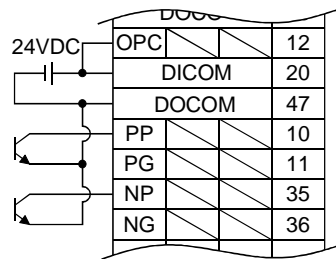
3.8.1 Internal connection diagram



3. SIGNALS AND WIRING

Note 1. P: Position control mode S: Speed control mode T: Torque control mode

2. For the differential line driver pulse train input. For the open collector pulse train input, make the following connection.



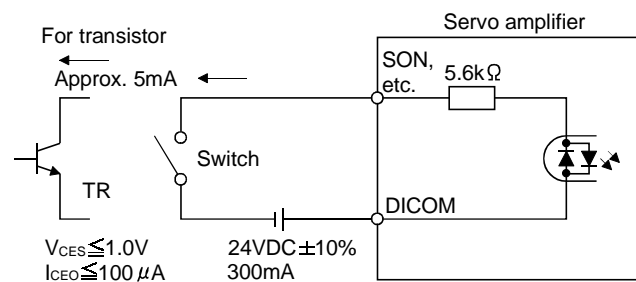
3. For the sink I/O interface. For the source I/O interface, refer to Section 3.8.3.

3.8.2 Detailed description 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 equipment.

(1) Digital input interface DI-1

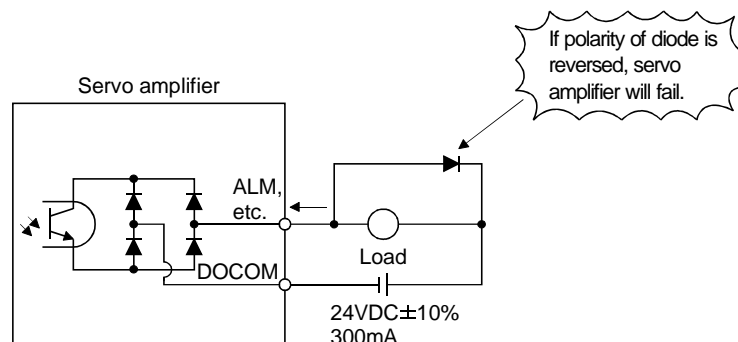
Give a signal with a relay or open collector transistor. Refer to Section 3.8.3 for the source input.



(2) Digital output interface DO-1

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

Refer to Section 3.8.3 for the source output.



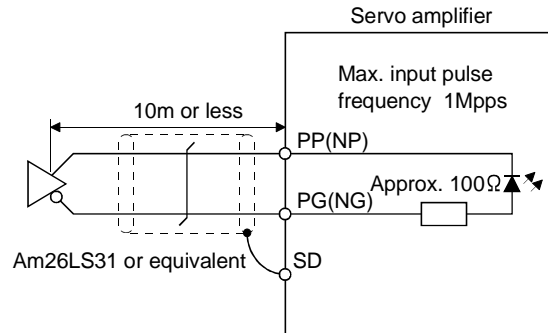
3. SIGNALS AND WIRING

(3) Pulse train input interface DI-2

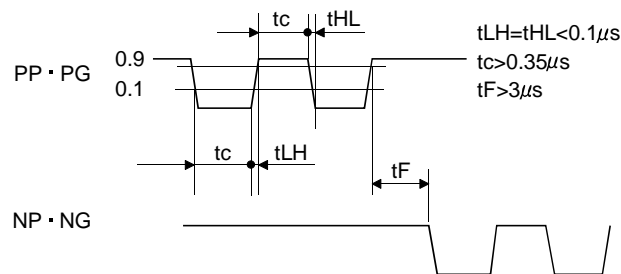
Give a pulse train signal in the differential line driver system or open collector system.

(a) Differential line driver system

1) Interface

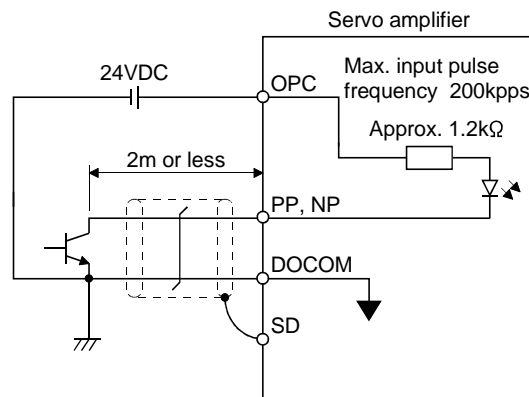


2) Input pulse condition

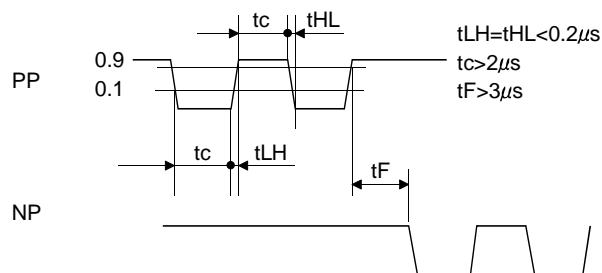


(b) Open collector system

1) Interface



2) Input pulse condition



3. SIGNALS AND WIRING

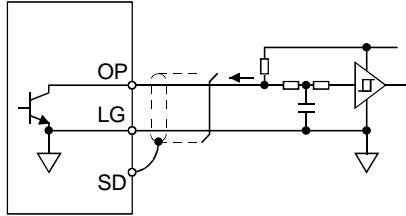
(4) Encoder pulse output DO-2

(a) Open collector system

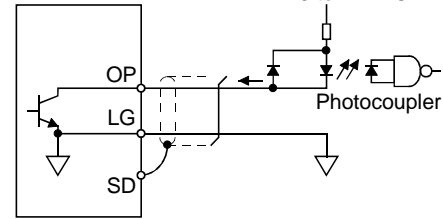
Interface

Max. output current : 35mA

Servo amplifier



Servo amplifier

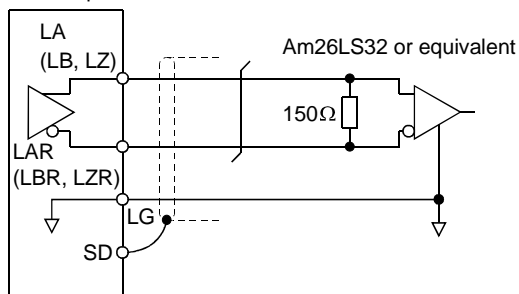


(b) Differential line driver system

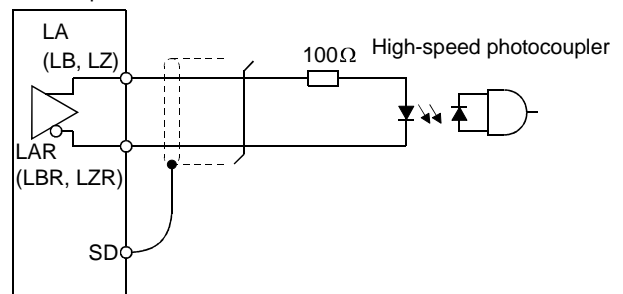
1) Interface

Max. output current: 35mA

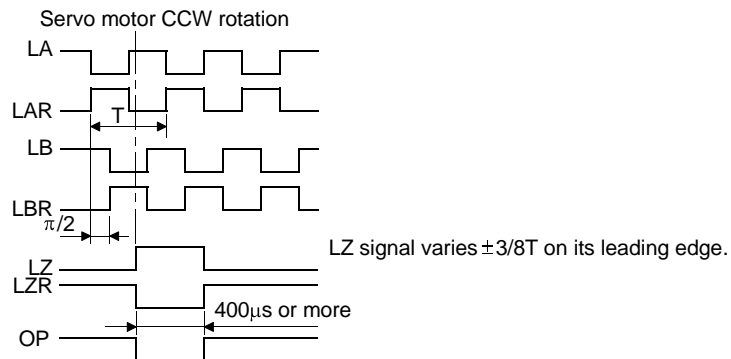
Servo amplifier



Servo amplifier

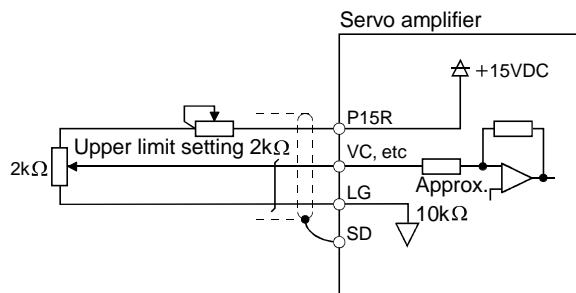


2) Output pulse



(5) Analog input

Input impedance 10 to 12kΩ



3. SIGNALS AND WIRING

(6) Analog output

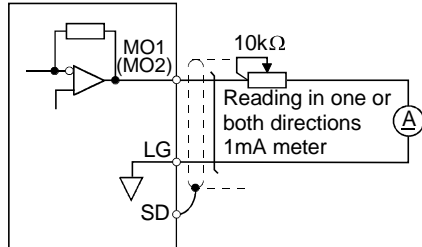
Output voltage $\pm 10V$

Max. 1mA

Max. output current

Resolution : 10bit

Servo amplifier

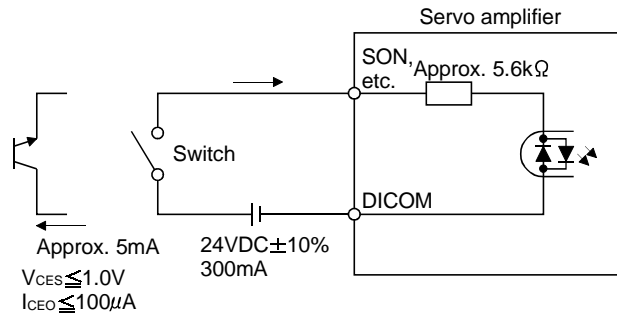


3. SIGNALS AND WIRING

3.8.3 Source I/O interfaces

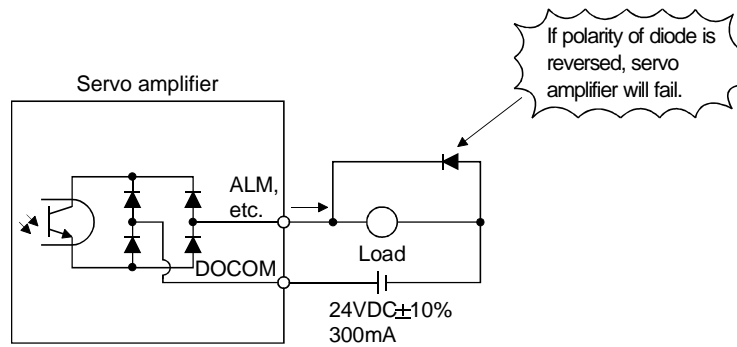
In this servo amplifier, source type I/O interfaces can be used. In this case, all DI-1 input signals and DO-1 output signals are of source type. Perform wiring according to the following interfaces.

(1) Digital input interface DI-1



(2) Digital output interface DO-1

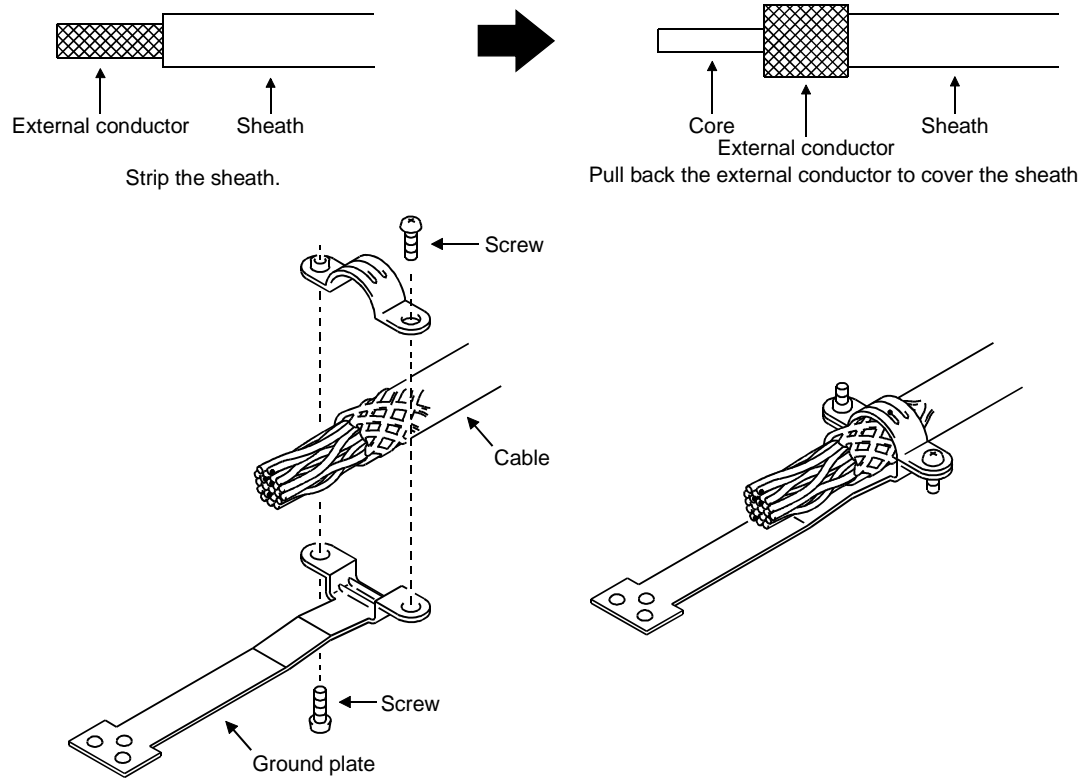
A maximum of 2.6V voltage drop occurs in the servo amplifier.



3. SIGNALS AND WIRING

3.9 Instructions for the 3M connector

In the case of the CN1 connector, securely connect the shielded external conductor of the cable to the ground plate as shown in this section and fix it to the connector shell.



3. SIGNALS AND WIRING

3.10 Connection of servo amplifier and servo motor

3.10.1 Connection instructions



WARNING

- Insulate the connections of the power supply terminals to prevent an electric shock.



CAUTION

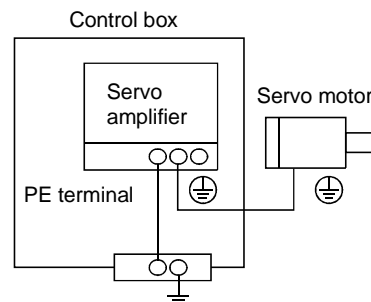
- Connect the wires to the correct phase terminals (U, V, W) of the servo amplifier and servo motor. Otherwise, the servo motor will operate improperly.
- Do not connect AC power supply directly to the servo motor. Otherwise, a fault may occur.

POINT

- Refer to Section 12.1 for the selection of the encoder cable.

This section indicates the connection of the motor power supply (U, V, W). Use of the optional cable and connector set is recommended for connection between the servo amplifier and servo motor. When the options are not available, use the recommended products. Refer to Section 12.1 for details of the options.

- (1) For grounding, connect the earth cable of the servo motor to the protective earth (PE) terminal of the servo amplifier and connect the ground cable of the servo amplifier to the earth via the protective earth of the control box. Do not connect them directly to the protective earth of the control panel.



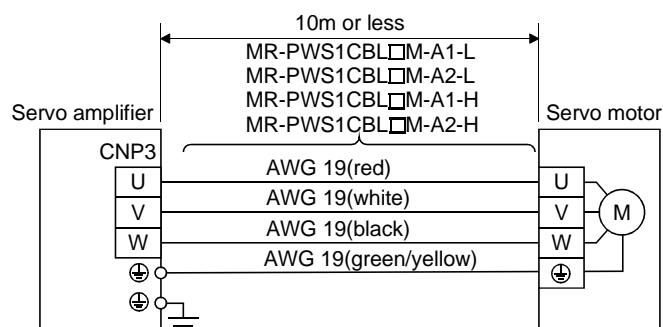
- (2) Do not share the 24VDC interface power supply between the interface and electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake.

3. SIGNALS AND WIRING

3.10.2 Power supply cable wiring diagrams

(1) HF-KP series servo motor

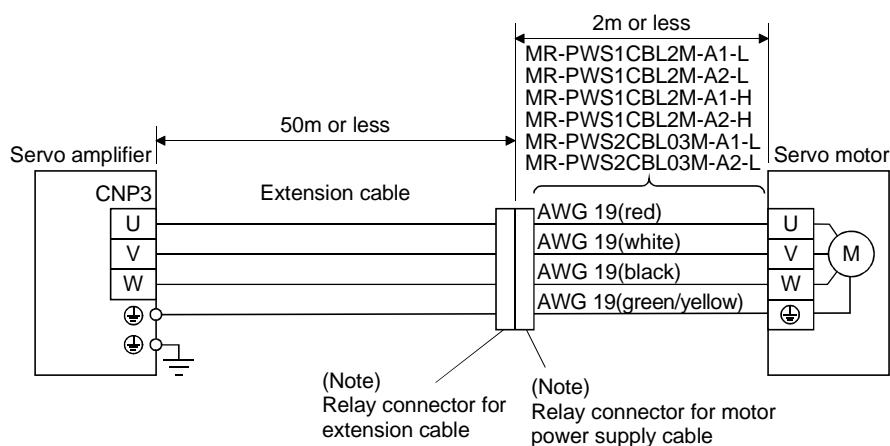
(a) When cable length is 10m or less



(b) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below. In this case, the motor power supply cable pulled from the servo motor should be within 2m long.

Refer to Section 12.6 for the wire used for the extension cable.



Note. Use of the following connectors is recommended when ingress protection (IP65) is necessary.

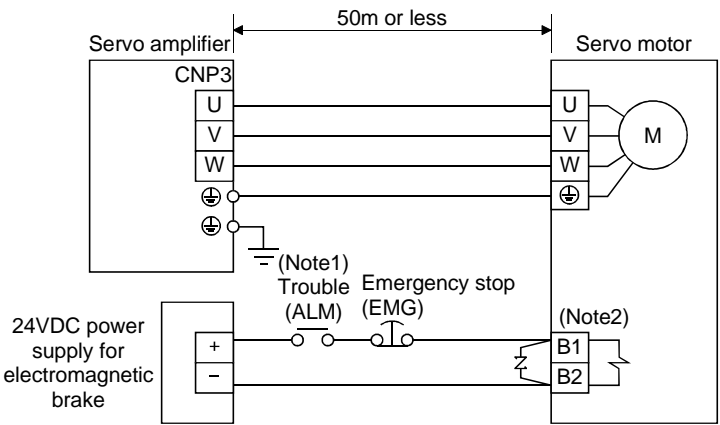
Relay Connector	Description	Protective Structure
Relay connector for extension cable	Connector: RM15WTP-4P Cord clamp: RM-15WTP-CP(5) (Hirose Electric) └ Numeral changes depending on the cable OD	IP65
Relay connector for motor power supply cable	Connector: RM15WTJA-4S Cord clamp: RM-15WTP-CP(8) (Hirose Electric) └ Numeral changes depending on the cable OD	IP65

3. SIGNALS AND WIRING

(2) HF-SP series servo motor

(a) Wiring diagrams

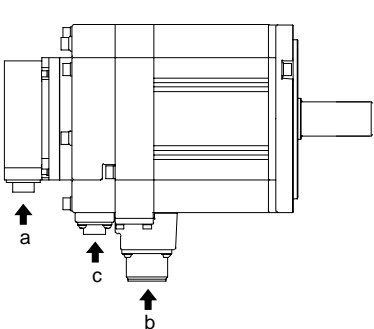
Refer to Section 12.6 for the cables used for wiring.



- Note 1. Shut off the circuit upon detection of a servo alarm.
2. There is no polarity in electromagnetic brake terminals B1 and B2.

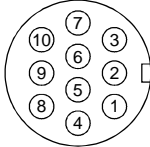
(b) Connector and signal allotment

The connector fitting the servomotor is prepared as optional equipment. Refer to Section 12.1. For types other than those prepared as optional equipment, refer to Section 3 in Servomotor Technical Reference, Vol. 2 to select.



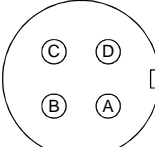
Servo motor	Servo motor side connectors		
	Encoder	Power supply	Electromagnetic brake
HF-SP52 □ 102 □ 152	CN10-R10P (DDK)	MS3102A18-10P	CN10-R2P (DDK)
HF-SP202 □ 352		MS3102A22-22P	

Detector connector signal allotment
CN10-R10P



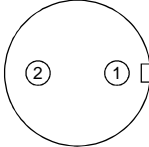
Terminal No.	Signal
1	MR
2	MRR
3	
4	BAT
5	LG
6	
7	
8	P5
9	
10	SHD

Power supply connector signal allotment
MS3102A18-10P
MS3102A22-22P



Terminal No.	Signal
A	U
B	V
C	W
D	⊕

Brake connector signal allotment
CM10-R2P




Terminal No.	Signal
1	B1 (Note)
2	B2 (Note)

Note. For the motor with electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

3. SIGNALS AND WIRING

3.11 Servo motor with electromagnetic brake

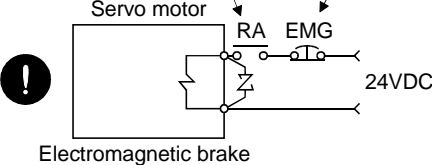
3.11.1 Signals and Wiring

**CAUTION**

- Configure the electromagnetic brake operation circuit so that it is activated not only by the servo amplifier signals but also by an external emergency stop signal.

Contacts must be open when servo-off, when an trouble (ALM) and when an electromagnetic brake interlock (MBR).

Circuit must be opened during emergency stop (EMG).



Servo motor

Electromagnetic brake

RA EMG

24VDC

- The electromagnetic brake is provided for holding purpose and must not be used for ordinary braking.

POINT

- Refer to the Servo Motor Instruction Manual for specifications such as the power supply capacity and operation delay time of the electromagnetic brake.

Note the following when the servo motor equipped with electromagnetic brake is used for applications requiring a brake to hold the motor shaft (vertical lift applications):

- 1) Set "□□□1" in parameter No. PA04 to make the electromagnetic brake interlock (MBR) valid.
- 2) Do not share the 24VDC interface power supply between the interface and electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake.
- 3) The brake will operate when the power (24VDC) switches off.
- 4) While the reset (RES) is on, the base circuit is shut off. When using the servo motor with a vertical shaft, use the electromagnetic brake interlock (MBR).
- 5) Switch off the servo-on (SON) after the servo motor has stopped.

3.11.2 Setting

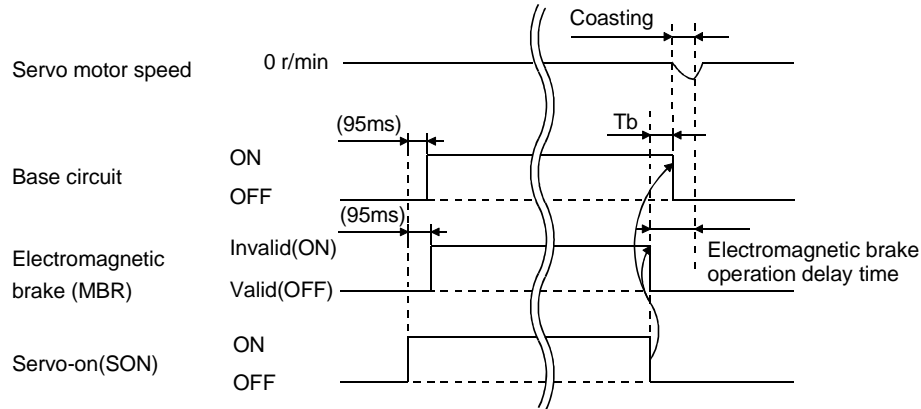
- 1) Set "□□□1" in parameter No. PA04 to make the electromagnetic brake interlock (MBR) valid.
- 2) Using parameter No. PC16 (electromagnetic brake sequence output), set a time delay (Tb) at servo-off from electromagnetic brake operation to base circuit shut-off as in the timing chart shown in (3) in this section.

3. SIGNALS AND WIRING

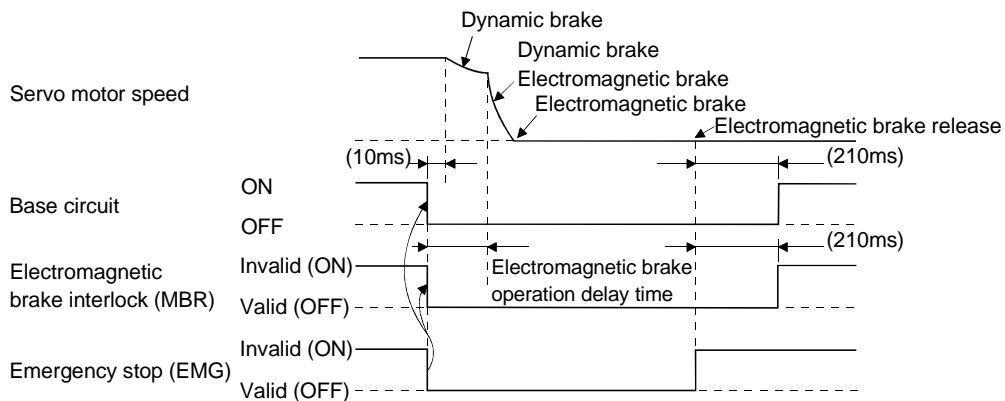
3.11.3 Timing charts

(1) Servo-on (SON) command (from controller) ON/OFF

Tb [ms] after the servo-on (SON) signal is switched off, the servo lock is released and the servo motor coasts. If the electromagnetic brake is made valid in the servo lock status, the brake life may be shorter. Therefore, when using the electromagnetic brake in a vertical lift application or the like, set Tb to about the same as the electromagnetic brake operation delay time to prevent a drop.

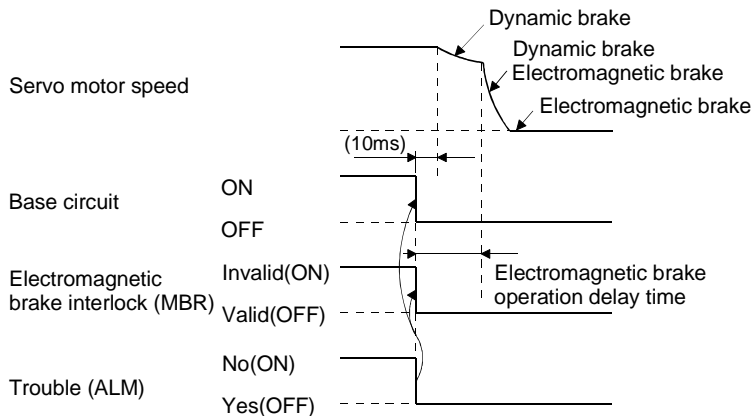


(2) Emergency stop (EMG) ON/OFF

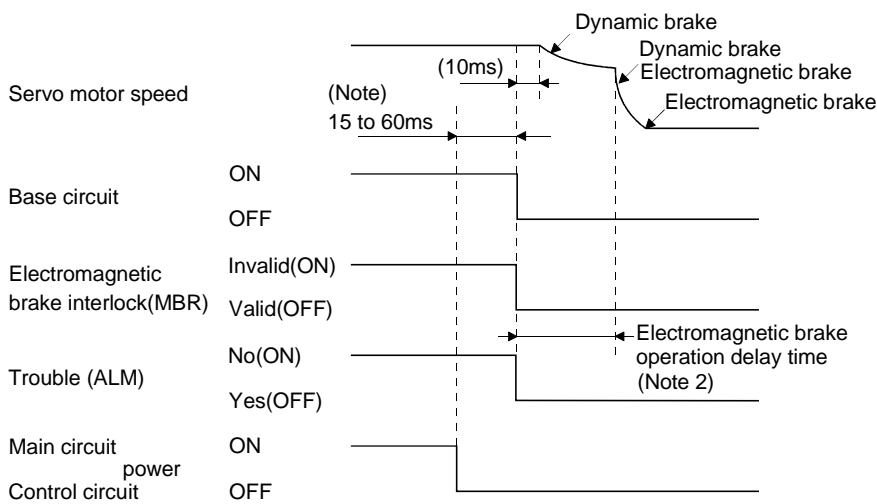


3. SIGNALS AND WIRING

(3) Alarm occurrence

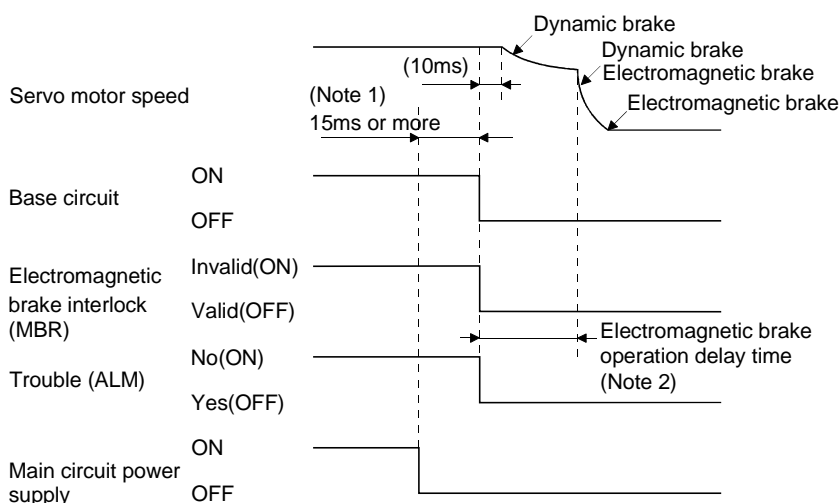


(4) Both main and control circuit power supplies off



Note. Changes with the operating status.

(5) Only main circuit power supply off (control circuit power supply remains on)



Note 1. Changes with the operating status.

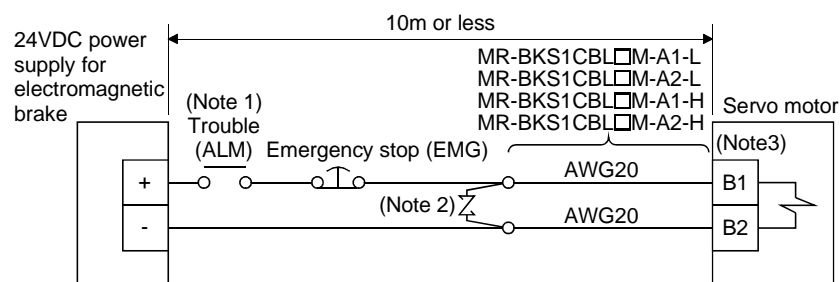
2. When the main circuit power supply is off in a motor stop status, the main circuit off warning (A.E9) occurs and the trouble (ALM) does not turn off.

3. SIGNALS AND WIRING

3.11.4 Wiring diagrams (HF-KP series servo motor)

POINT
▪ For HF-SP series servo motors, refer to Section 3.10.2 (2).

(1) When cable length is 10m or less

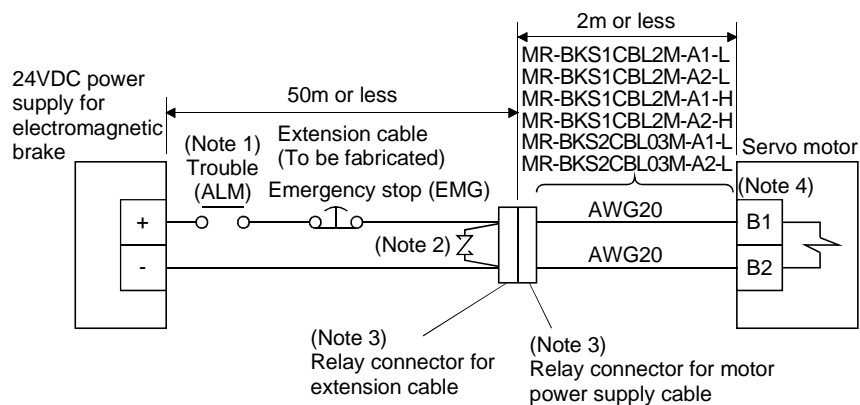


- Note 1. Shut off the circuit on detection of the servo amplifier alarm.
 2. Connect a surge absorber as close to the servo motor as possible.
 3. There is no polarity in electromagnetic brake terminals (B1 and B2).

When fabricating the motor brake cable MR-BKS1CBL-□M-H, refer to Section 12.2.3.

(2) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below on the customer side. In this case, the motor power supply cable pulled from the servo motor should be within 2m long. Refer to Section 12.6 for the wire used for the extension cable.



- Note 1. Shut off the circuit on detection of the servo amplifier alarm.
 2. Connect a surge absorber as close to the servo motor as possible.
 3. Use of the following connectors is recommended when ingress protection (IP65) is necessary.
 4. There is no polarity in electromagnetic brake terminals (B1 and B2).

Relay Connector	Description	Protective Structure
Relay connector for extension cable	CM10-CR2P-* (DDK) Wire size: S, M, L	IP65
Relay connector for motor power supply cable	CM10-SP2S-* (DDK) Wire size: S, M, L	IP65

3. SIGNALS AND WIRING

3.12 Grounding

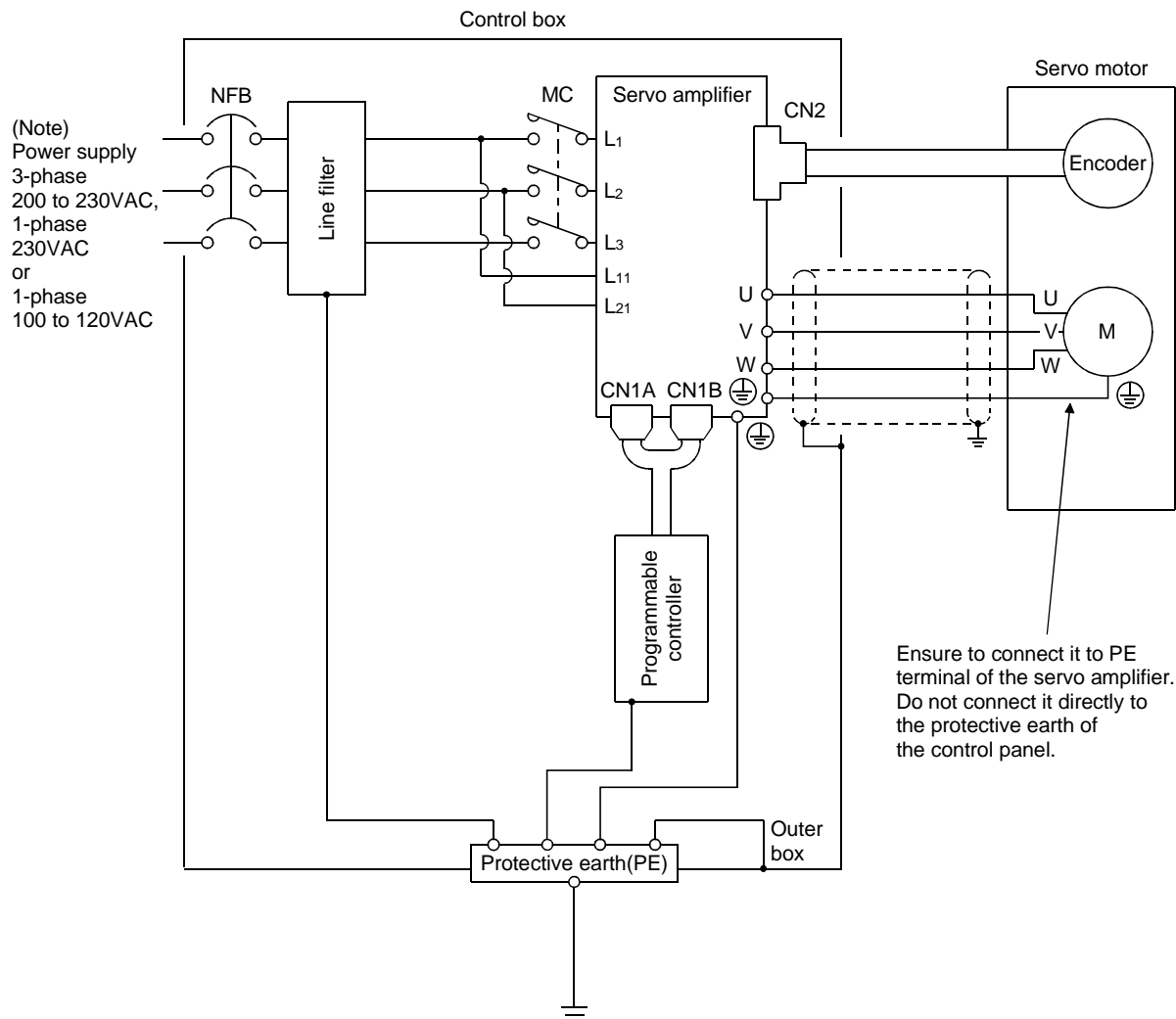


WARNING

- Ground the servo amplifier and servo motor securely.
- To prevent an electric shock, always connect the protective earth (PE) terminal of the servo amplifier with the protective earth (PE) of the control box.

The servo amplifier switches the power transistor on-off to supply power to the servo motor. Depending on the wiring and ground cablerouting, 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 the EMC Installation Guidelines (IB(NA)67310).



Note. For 1-phase 230VAC or 1-phase 100 to 120VAC, connect the power supply to L1 L2 and leave L3 open.
There is no L3 for 1-phase 100 to 120VAC power supply.

[illegible]

4. STARTUP

4. STARTUP



WARNING

▪ Do not operate the switches with wet hands. You may get an electric shock.



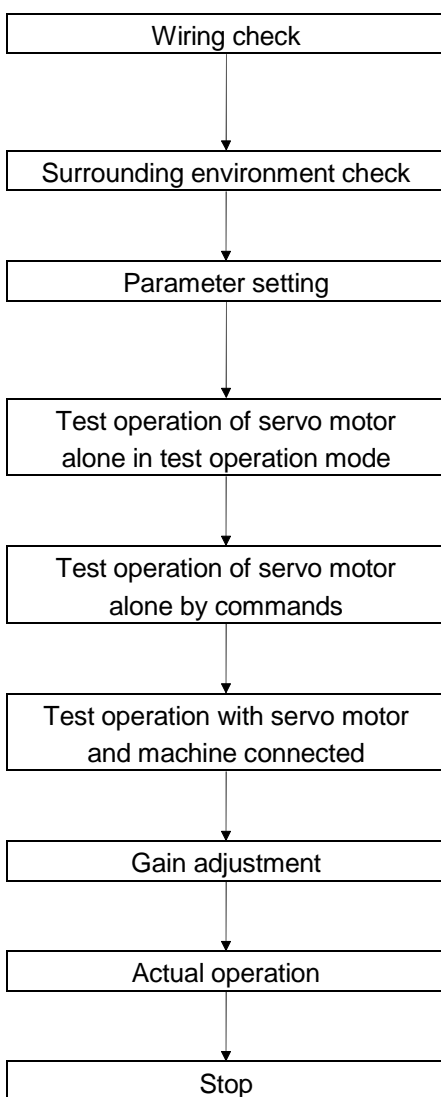
CAUTION

- Before starting operation, check the parameters. Some machines may perform unexpected operation.
- Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the servo amplifier heat sink, regenerative brake resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
- During operation, never touch the rotating parts of the servo motor. Doing so can 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



Check whether the servo amplifier and servo motor are wired correctly using visual inspection, DO forced output function (Section 6.8), etc. (Refer to Section 4.1.2.)

Check the surrounding environment of the servo amplifier and servo motor. (Refer to Section 4.1.3.)

Set the parameters as necessary, such as the used control mode and regenerative brake option selection. (Refer to Chapter 5 and Sections 4.2.4, 4.3.4 and 4.4.4.)

With the servo motor disconnected from the machine, check whether the servo motor rotates correctly. (Refer to Sections 6.9, 4.2.3, 4.3.3 and 4.4.3.)

With the servo motor disconnected from the machine, give commands to the servo amplifier and check whether the servo motor rotates correctly.

Connect the servo motor with the machine, give operation commands from the host command device, and check machine motions.

Make gain adjustment to optimize the machine motions. (Refer to Chapter 7.)

Stop giving commands and stop operation. The other conditions where the servo motor will come to a stop are indicated in Sections 4.2.2, 4.3.2 and 4.4.2.

4. STARTUP

4.1.2 Wiring check

(1) Power supply system wiring

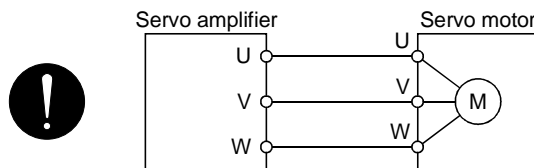
Before switching on the main circuit and control circuit power supplies, check the following items.

(a) Power supply system wiring

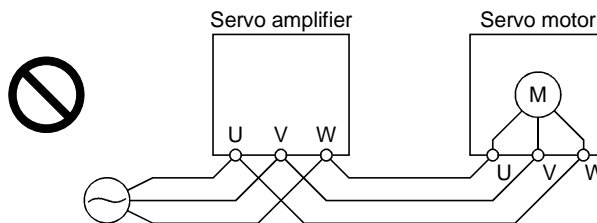
The power supplied to the power input terminals (L1, L2, L3, L11, L21) of the servo amplifier should satisfy the defined specifications. (Refer to Section 1.3.)

(b) Connection of servo amplifier and servo motor

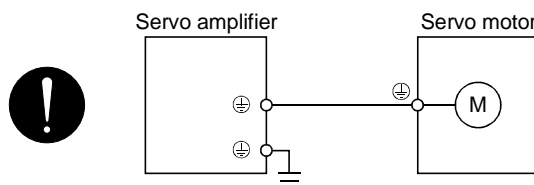
- 1) The servo motor power supply terminals (U, V, W) of the servo amplifier match in phase with the power input terminals (U, V, W) of the servo motor.



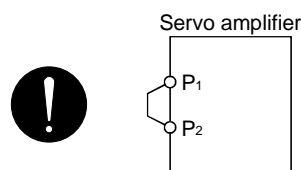
- 2) The power supplied to the servo amplifier should not be connected to the servo motor power supply terminals (U, V, W). To do so will fail the connected servo amplifier and servo motor.



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

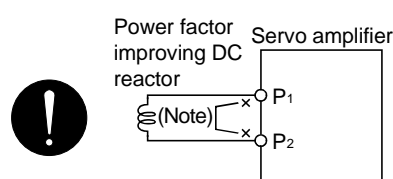


- 4) P1-P2 should be connected.



(c) When option and auxiliary equipment are used

- 1) The regenerative brake option should be connected across P-C using a twisted cable. (Refer to Section 12.2.)
- 2) The power factor improving DC reactor should be connected across P1-P2. (Refer to Section 12.8.)



Note. Always disconnect the wiring across P1-P2.

4. STARTUP

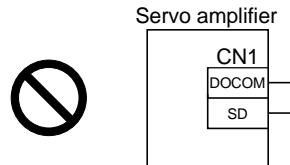
(2) I/O signal wiring

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

Use DO forced output to forcibly turn on/off the pins of the CN1 connector. This function can be used to perform a wiring check. (Refer to Section 6.8.) In this case, switch on the control circuit power supply only.

- (b) 24VDC or higher voltage is not applied to the pins of connectors CN1.

- (c) SD and DOCOM of connector CN1 is not shorted.



4.1.3 Surrounding environment

(1) Cable routing

- (a) The wiring cables are free from excessive force.
- (b) The encoder cable should not be used in excess of its flex life. (Refer to Section 11.4.)
- (c) The connector part of the servo motor should not be strained.

(2) Environment

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

4. STARTUP

4.2 Startup in position control mode

Make a startup in accordance with Section 4.1. This section provides the methods 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 the servo-on (SON).
- 2) Make sure that a command pulse train is not input.
- 3) Switch on the main circuit power supply and control circuit power supply.

At power-on, "88888" appears instantaneously, but it is not an error.

When main circuit power/control circuit power is switched on, the display shows "C (Cumulative feedback pulses)", and in two second later, shows data.



In the absolute position detection system, first power-on results in the absolute position lost (AL.25) alarm and the servo system cannot be switched on. This is not a failure and takes place due to the uncharged capacitor in the encoder.

The alarm can be deactivated by keeping power on for a few minutes in the alarm status and then switching power off once and on again.

Also in the absolute position detection system, if power is switched on at the servo motor speed of 3000r/min or higher, position mismatch may occur due to external force or the like. Power must therefore be switched on when the servo motor is at a stop.

(2) Power-off

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

4.2.2 Stop

In any of the following statuses, the servo amplifier interrupts and stops the operation of the servo motor:
Refer to Section 3.11.3 for the servo motor equipped with electromagnetic brake.

(a) Servo-on (SON) OFF

The base circuit is shut off and the servo motor coasts.

(b) Alarm occurrence

When an alarm occurs, the base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.

(c) Emergency stop (EMG) OFF

The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop. Alarm AL.E6 occurs.

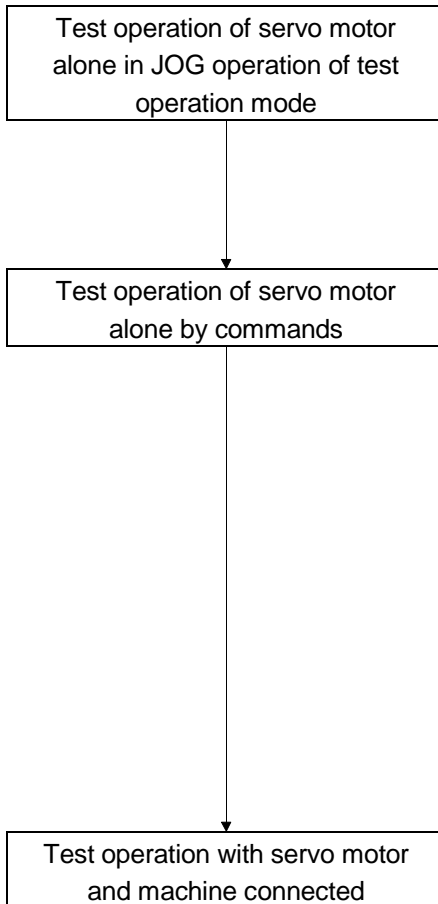
(d) Forward rotation stroke end (LSP), reverse rotation stroke end (LSN) OFF

The droop pulse value is erased and the servo motor is stopped and 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 the power on and off methods of the servo amplifier.



In this step, confirm that the servo amplifier and servo motor operate normally.

With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor rotates correctly. Refer to Section 6.9 for the test operation mode.

In this step, confirm that the servo motor rotates correctly under the commands from the command device.

Make sure that the servo motor rotates in the following procedure.

- 1) Switch on the Emergency stop (EMG) and Servo-on (SON).
When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When a pulse train is input from the command device, the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.

Make sure that the servo motor rotates in the following procedure.

- 1) Switch on the Emergency stop (EMG) and Servo-on (SON).
When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When a pulse train is input from the command device, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display, check for any problems of the servo motor speed, command pulse frequency, load ratio, etc.
- 4) Then, check automatic operation with the program of the command device.

4. STARTUP

4.2.4 Parameter setting

POINT									
	<ul style="list-style-type: none"> The encoder cable MR-EKCBL□M-L/H for the HF-KP series servo motor requires the parameter No. PC22 setting to be changed depending on its length. Check whether the parameter is set correctly. If it is not set correctly, the encoder error 1 (AL. 16) will occur at power-on. 								
	<table> <tr> <th>Encoder Cable</th><th>Parameter No. PC22 Setting</th></tr> <tr> <td>MR-EKCBL20M-L/H</td><td>0 □ □ □ (initial value)</td></tr> <tr> <td>MR-EKCBL30M-H</td><td rowspan="3">1 □ □ □</td></tr> <tr> <td>MR-EKCBL40M-H</td></tr> <tr> <td>MR-EKCBL50M-H</td></tr> </table>	Encoder Cable	Parameter No. PC22 Setting	MR-EKCBL20M-L/H	0 □ □ □ (initial value)	MR-EKCBL30M-H	1 □ □ □	MR-EKCBL40M-H	MR-EKCBL50M-H
Encoder Cable	Parameter No. PC22 Setting								
MR-EKCBL20M-L/H	0 □ □ □ (initial value)								
MR-EKCBL30M-H	1 □ □ □								
MR-EKCBL40M-H									
MR-EKCBL50M-H									

In the position control mode, the servo amplifier can be used by merely changing the basic setting parameters (No. PA □ □) mainly.

As necessary, set the gain filter parameters (No. PB □ □), extension setting parameters (No. PC □ □) and I/O setting parameters (No. PD □ □).

Parameter Group	Main Description
Basic setting parameter (No. PA □ □)	<p>Set the basic setting parameters first. Generally, operation can be performed by merely setting this parameter group.</p> <p>In this parameter group, set the following items.</p> <ul style="list-style-type: none"> Control mode selection (select the position control mode) Regenerative brake option selection Absolute position detection system selection Setting of command input pulses per revolution Electronic gear setting Auto tuning selection and adjustment In-position range setting Torque limit setting Command pulse input form selection Servo motor rotation direction selection Encoder output pulse setting
Gain filter parameter (No. PB □ □)	<p>If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute in-depth gain adjustment using this parameter group.</p> <p>This parameter group must also be set when the gain switching function is used.</p>
Extension setting parameter (No. PC □ □)	<p>This parameter group must be set when multiple electronic gears, analog monitor outputs or analog inputs are used.</p>
(Note) I/O setting parameter (No. PD □ □)	<p>Used when changing the I/O devices of the servo amplifier.</p>

Note. The parameter No. PA19 setting must be changed when this parameter group is used.

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

▪ Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

▪ Using the optional MR Configurator, you can refer to unrotated servo motor reasons, etc.

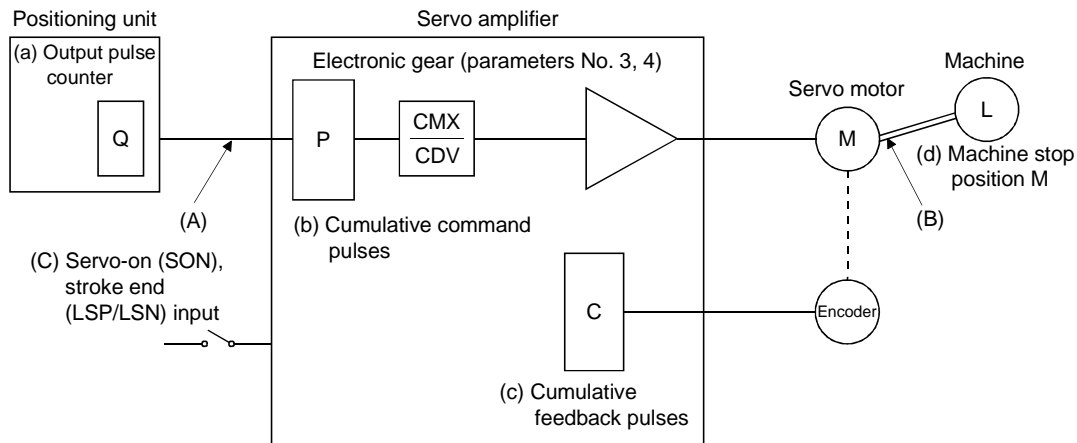
The following faults may occur at start-up. If any of such faults occurs, take the corresponding action.

(1) Troubleshooting

No.	Start-up sequence	Fault	Investigation	Possible cause	Reference
1	Power on	<ul style="list-style-type: none"> • LED is not lit. • LED flickers. 	Not improved if connectors CN1, CN2 and CN3 are disconnected.	1. Power supply voltage fault 2. Servo amplifier is faulty.	
			Improved when connectors CN1 is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when connector CN2 is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is faulty.	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to Chapter 9 and remove cause.		Chapter 9
2	Switch on servo-on (SON).	Alarm occurs.	Refer to Chapter 9 and remove cause.		Chapter 9
		Servo motor shaft is not servo-locked (is free).	1. Check the display to see if the servo amplifier is ready to operate. 2. Check the external I/O signal indication (Section 6.7) to see if the servo-on (SON) is ON.	1. Servo-on (SON) is not input. (Wiring mistake) 2. External 24VDC power is not supplied to DICOM.	Section 6.7
3	Enter input command. (Test operation)	Servo motor does not rotate.	Check cumulative command pulses for the status display (Section 6.3).	1. Wiring mistake (a) For open collector pulse train input, 24VDC power is not supplied to OPC. (b) LSP and LSN are not on. 2. No pulses is input.	Section 6.3
		Servo motor run in reverse direction.		1. Mistake in wiring to controller. 2. Mistake in setting of parameter No. 54.	Chapter 5
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 several times to complete auto tuning.	Gain adjustment fault	Chapter 7
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be run with safety, repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 7
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) in this section

4. STARTUP

(2) How to find the cause of position shift



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

(A), (B) and (C) indicate position shift causes. For example, (A) indicates that noise entered the wiring between positioning unit and servo amplifier, causing pulses to be mis-counted.

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

- 1) $Q = P$ (positioning unit's output counter = servo amplifier's cumulative command pulses)
- 2) When using the electronic gear

$$P \cdot \frac{\text{CMX (parameter No. PA06)}}{\text{CDV (parameter No. PA07)}} = C$$
 (cumulative command pulses \times electronic gear = cumulative feedback pulses)
- 3) When using parameter No. PA05 to set the number of pulses per servo motor revolution parameter No. PA05

$$P \cdot \frac{262144}{\text{FBP (parameter No. PA05)}} = C$$
- 4) $C \cdot \Delta \ell = M$ (cumulative feedback pulses \times travel per pulse = machine position)

Check for a position shift in the following sequence:

- 1) When $Q \neq P$

Noise entered the pulse train signal wiring between positioning unit and servo amplifier, causing pulses to be miss-counted. (Cause A)

Make the following check or take the following measures:

 - Check how the shielding is done.
 - Change the open collector system to the differential line driver system.
 - Run wiring away from the power circuit.
 - Install a data line filter. (Refer to (2)(a) Section 12.12.)
- 2) When $P \cdot \frac{\text{CMX}}{\text{CDV}} \neq C$

During operation, the servo-on (SON) or forward/reverse rotation stroke end was switched off or the clear (CR) and the reset (RES) switched on. (Cause C)

If a malfunction may occur due to much noise, increase the input filter setting (parameter No. PD19).
- 3) When $C \cdot \Delta \ell \neq M$

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

4. STARTUP

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 the servo-on (SON).
- 2) Make sure that the Forward rotation start (ST1) and Reverse rotation start (ST2) are off.
- 3) Switch on the main circuit power supply and control circuit power supply.

At power-on, "88888" appears instantaneously, but it is not an error.

When main circuit power/control circuit power is switched on, the display shows "r (servo motor speed)", and in two second later, shows data.



(2) Power-off

- 1) Switch off the Forward rotation start (ST1) or Reverse rotation start (ST2).
- 2) Switch off the Servo-on (SON).
- 3) Switch off the main circuit power supply and control circuit power supply.

4.3.2 Stop

In any of the following statuses, the servo amplifier interrupts and stops the operation of the servo motor:
Refer to Section 13.11.13 for the servo motor equipped with electromagnetic brake.

(a) Servo-on (SON) OFF

The base circuit is shut off and the servo motor coasts.

(b) Alarm occurrence

When an alarm occurs, the base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.

(c) Emergency stop (EMG) OFF

The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.
Alarm AL.E6 occurs.

(d) Stroke end (LSP/LSN) OFF

The servo motor is brought to a sudden stop and servo-locked. The motor may be run in the opposite direction.

(e) Simultaneous ON or simultaneous OFF of forward rotation start (ST1) and reverse rotation start (ST2)

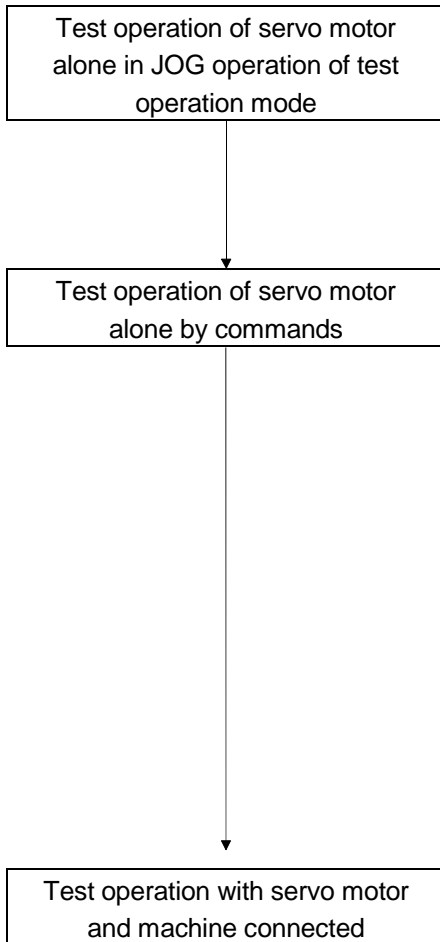
The servo motor is decelerated to a stop.

POINT
▪ A sudden stop indicates deceleration to a stop at the deceleration time constant of zero.

4. STARTUP

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 the power on and off methods of the servo amplifier.



In this step, confirm that the servo amplifier and servo motor operate normally.

With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor rotates correctly. Refer to Section 6.9 for the test operation mode.

In this step, confirm that the servo motor rotates correctly under the commands from the command device.

Make sure that the servo motor rotates in the following procedure.

- 1) Switch on the Emergency stop (EMG) and Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When the analog speed command (VC) is input from the command device and the Forward rotation start (ST1) or Reverse rotation start (ST2) is switched on, the servo motor starts rotating. Give a low speed command at first and check the rotation direction, etc. of the servo motor. If the servo motor does not operate in the intended direction, check the input signal.

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.

Make sure that the servo motor rotates in the following procedure.

- 1) Switch on the Emergency stop (EMG) and Servo-on (SON). When the servo amplifier is put in a servo-on status, the Ready (RD) switches on.
- 2) Switch on the Forward rotation stroke end (LSP) or Reverse rotation stroke end (LSN).
- 3) When the analog speed command (VC) is input from the command device and the Forward rotation start (ST1) or Reverse rotation start (ST2) is switched on, the servo motor starts rotating. Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display, check for any problems of the servo motor speed, load ratio, etc.
- 4) Then, check automatic operation with the program of the command device.

4. STARTUP

4.3.4 Parameter setting

POINT									
	<ul style="list-style-type: none">The encoder cable MR-EKCBL□M-L/H for the HF-KP series servo motor requires the parameter No. PC22 setting to be changed depending on its length. Check whether the parameter is set correctly. If it is not set correctly, the encoder error 1 (AL. 16) will occur at power-on.								
	<table><tr><th>Encoder Cable</th><th>Parameter No. PC22 Setting</th></tr><tr><td>MR-EKCBL20M-L/H</td><td>0 □ □ □ (initial value)</td></tr><tr><td>MR-EKCBL30M-H</td><td rowspan="3">1 □ □ □</td></tr><tr><td>MR-EKCBL40M-H</td></tr><tr><td>MR-EKCBL50M-H</td></tr></table>	Encoder Cable	Parameter No. PC22 Setting	MR-EKCBL20M-L/H	0 □ □ □ (initial value)	MR-EKCBL30M-H	1 □ □ □	MR-EKCBL40M-H	MR-EKCBL50M-H
Encoder Cable	Parameter No. PC22 Setting								
MR-EKCBL20M-L/H	0 □ □ □ (initial value)								
MR-EKCBL30M-H	1 □ □ □								
MR-EKCBL40M-H									
MR-EKCBL50M-H									

When using this servo in the speed control mode, change the parameter No. 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 (No. PA □ □) and extension setting parameters (No. PC □ □) mainly.

As necessary, set the gain filter parameters (No. PB □ □) and I/O setting parameters (No. PD □ □).

Parameter Group	Main Description
Basic setting parameter (No. PA □ □)	Set the basic setting parameters first. In this parameter group, set the following items. Control mode selection (select the speed control mode) Regenerative brake option selection Auto tuning selection and adjustment Torque limit setting Encoder output pulse setting
Gain filter parameter (No. PB □ □)	If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute in-depth gain adjustment using this parameter group. This parameter group must also be set when the gain switching function is used.
Extension setting parameter (No. PC □ □)	In this parameter group, set the following items. Acceleration/deceleration time constant S-pattern acceleration/deceleration time constant Internal speed command Analog speed command maximum speed Analog speed command offset In addition, this parameter group must be set when analog monitor output, torque limit, etc. are used.
(Note) I/O setting parameter (No. PD □ □)	Used when changing the I/O devices of the servo amplifier.

Note. The parameter No. PA19 setting must be changed when this parameter group is used.

4.3.5 Actual operation

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

4. STARTUP

4.3.6 Trouble at start-up



CAUTION

▪ Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

▪ Using the optional servo configuration software, you can refer to unrotated servo motor reasons, 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">• LED is not lit.• LED flickers.	Not improved if connectors CN1, CN2 and CN3 are disconnected.	1. Power supply voltage fault 2. Servo amplifier is faulty.	
			Improved when connectors CN1 is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when connector CN2 is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is faulty.	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to Chapter 9 and remove cause.		
2	Switch on servo-on (SON).	Alarm occurs.	Refer to Chapter 9 and remove cause.		Chapter 9
		Servo motor shaft is not servo-locked (is free).	1. Check the display to see if the servo amplifier is ready to operate. 2. Check the external I/O signal indication (Section 6.7) to see if the servo-on (SON) is ON.	1. Servo-on (SON) is not input. (Wiring mistake) 2. External 24VDC power is not supplied to DICOM.	Section 6.7
3	Switch on forward rotation start (ST1) or reverse rotation start (ST2).	Servo motor does not rotate.	Call the status display and check the input voltage of the analog speed command (VC).	Analog speed command is 0V.	Section 6.3
			Call the external I/O signal display (Section 6.3) and check the ON/OFF status of the input signal.	LSP, LSN, ST1 or ST2 is off.	Section 6.6
			Check the internal speed commands 1 to 7 (parameters No. PC05 to PC11).	Set value is 0.	Section 5.1.9
			Check the forward torque limit (Parameter no. PA11) or reverse torque limit (Parameter no. PA12)	Torque limit level is too low as compared to the load torque.	
			When the analog torque limit (TLA) is usable, check the input voltage on the status display.	Torque limit level is too low as compared to the load torque.	
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 several times to complete auto tuning.	Gain adjustment fault	Chapter 7
		Large load inertia moment causes the servo motor shaft to oscillate side to side.	If the servo motor may be run with safety, repeat acceleration and deceleration several times to complete auto tuning.	Gain adjustment fault	Chapter 7

4. STARTUP

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 the servo-on (SON).
- 2) Make sure that the Forward rotation selection (RS1) and Reverse rotation selection (RS2) are off.
- 3) Switch on the main circuit power supply and control circuit power supply.

At power-on, "88888" appears instantaneously, but it is not an error.

When main circuit power/control circuit power is switched on, the display shows "U (torque command voltage)", and in two second later, shows data.



(2) Power-off

- 1) Switch off the Forward rotation selection (RS1) or Reverse rotation selection (RS2).
- 2) Switch off the Servo-on (SON).
- 3) Switch off the main circuit power supply and control circuit power supply.

4.4.2 Stop

In any of the following statuses, the servo amplifier interrupts and stops the operation of the servo motor:
Refer to Section 13.11.13 for the servo motor equipped with electromagnetic brake.

(a) Servo-on (SON) OFF

The base circuit is shut off and the servo motor coasts.

(b) Alarm occurrence

When an alarm occurs, the base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.

(c) Emergency stop (EMG) OFF

The base circuit is shut off and the dynamic brake is operated to bring the servo motor to a sudden stop.
Alarm AL.E6 occurs.

(d) Simultaneous ON or simultaneous OFF of forward rotation selection (RS1) and reverse rotation selection (RS2)

The servo motor coasts.

POINT
▪ A sudden stop indicates deceleration to a stop at the deceleration time constant of zero.

4. STARTUP

4.4.3 Trouble at start-up



CAUTION

- Excessive adjustment or change of parameter setting must not be made as it will make operation instable.

POINT

- Using the optional servo configuration software, you can refer to unrotated servo motor reasons, 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"> ▪ LED is not lit. ▪ LED flickers. 	Not improved if connectors CN1, CN2 and CN3 are disconnected.	1. Power supply voltage fault 2. Servo amplifier is faulty.	
			Improved when connectors CN1 is disconnected.	Power supply of CN1 cabling is shorted.	
			Improved when connector CN2 is disconnected.	1. Power supply of encoder cabling is shorted. 2. Encoder is faulty.	
			Improved when connector CN3 is disconnected.	Power supply of CN3 cabling is shorted.	
		Alarm occurs.	Refer to Chapter 9 and remove cause.		Chapter 9
2	Switch on servo-on (SON).	Alarm occurs.	Refer to Chapter 9 and remove cause.		Chapter 9
		Servo motor shaft is free.	Call the external I/O signal display (Section 6.7) and check the ON/OFF status of the input signal.	1. Servo-on (SON) is not input. (Wiring mistake) 2. External 24VDC power is not supplied to DICOM.	Section 6.7
3	Switch on forward rotation start (RS1) or reverse rotation start (RS2).	Servo motor does not rotate.	Call the status display (Section 6.3) and check the analog torque command (TC).	Analog torque command is 0V.	Section 6.3
			Call the external I/O signal display and check the ON/OFF status of the input signal.	RS1 or RS2 is off.	Section 6.6
			Check the internal speed limits 1 to 7 (parameters No. PC05 to PC11).	Set value is 0.	Section 5.1.9
			Check the analog torque command maximum output (parameter No. 26) value.	Torque command level is too low as compared to the load torque.	
			Check the internal torque limit 1 (parameter No. PC13).	Set value is 0.	

4. STARTUP

4.4.4 Parameter setting

POINT									
	<ul style="list-style-type: none">The encoder cable MR-EKCBL□M-L/H for the HF-KP series servo motor requires the parameter No. PC22 setting to be changed depending on its length. Check whether the parameter is set correctly. If it is not set correctly, the encoder error 1 (AL. 16) will occur at power-on.								
	<table><tr><th>Encoder Cable</th><th>Parameter No. PC22 Setting</th></tr><tr><td>MR-EKCBL20M-L/H</td><td>0 □ □ □ (initial value)</td></tr><tr><td>MR-EKCBL30M-H</td><td rowspan="3">1 □ □ □</td></tr><tr><td>MR-EKCBL40M-H</td></tr><tr><td>MR-EKCBL50M-H</td></tr></table>	Encoder Cable	Parameter No. PC22 Setting	MR-EKCBL20M-L/H	0 □ □ □ (initial value)	MR-EKCBL30M-H	1 □ □ □	MR-EKCBL40M-H	MR-EKCBL50M-H
Encoder Cable	Parameter No. PC22 Setting								
MR-EKCBL20M-L/H	0 □ □ □ (initial value)								
MR-EKCBL30M-H	1 □ □ □								
MR-EKCBL40M-H									
MR-EKCBL50M-H									

When using this servo in the torque control mode, change the parameter No. 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 (No. PA □ □) and extension setting parameters (No. PC □ □) mainly.

As necessary, set the I/O setting parameters (No. PD □ □).

Parameter Group	Main Description
Basic setting parameter (No. PA □ □)	Set the basic setting parameters first. In this parameter group, set the following items. Control mode selection (select the torque control mode) Regenerative brake option selection Torque limit setting Encoder output pulse setting
Gain filter parameter (No. PB □ □)	If satisfactory operation cannot be achieved by the gain adjustment made by auto tuning, execute in-depth gain adjustment using this parameter group. This parameter group must also be set when the gain switching function is used.
Extension setting parameter (No. PC □ □)	In this parameter group, set the following items. Acceleration/deceleration time constant S-pattern acceleration/deceleration time constant Internal torque command Analog torque command maximum speed Analog torque command offset In addition, this parameter group must be set when analog monitor output, speed limit, etc. are used.
(Note) I/O setting parameter (No. PD □ □)	Used when changing the I/O devices of the servo amplifier.

Note. The parameter No. PA19 setting must be changed when this parameter group is used.

4.4.5 Actual operation

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

[illegible]

5. PARAMETERS

5. PARAMETERS



CAUTION

▪ Never adjust or change the parameter values extremely as it will make operation instable.

In the MR-J3-A servo amplifier, the parameters are classified into the following groups on a function basis.

Parameter Group	Main Description
Basic setting parameters (No. PA □□)	When using this servo amplifier in the position control mode, make basic setting with these parameters.
Gain/filter parameters (No. PB □□)	Use these parameters when making gain adjustment manually.
Extension setting parameters (No. PC □□)	When using this servo amplifier in the speed control mode or torque control mode, mainly use these parameters.
I/O setting parameters (No. PD □□)	Use these parameters when changing the I/O signals of the servo amplifier.

When using this servo in the position control mode, mainly setting the basic setting parameters (No. PA□□) allows the setting of the basic parameters at the time of introduction.

5.1 Basic Setting Parameters (No.PA□□)

POINT

▪ For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

5.1.1 Parameter list

No.	Symbol	Name	Initial Value	Unit	Control Mode		
					Position	Speed	Torque
PA01	*STY	Control mode	0000h		○	○	○
PA02	*REG	Regenerative brake option	0000h		○	○	○
PA03	*ABS	Absolute position detection system	0000h		○		
PA04	*AOP1	Function selection A-1	0000h		○	○	○
PA05	*FBP		0		○		
PA06	CMX	Electronic gear numerator (Command pulse multiplying factor numerator)	1		○		
PA07	CDV	Electronic gear denominator (Command pulse multiplying factor denominator)	1		○		
PA08	ATU	Auto tuning	0001h		○	○	
PA09	RSP	Auto tuning response	12		○	○	
PA10	INP	Control mode, regenerative brake option selection	100	pulse	○		
PA11	TLP	Forward torque limit	100.0	%	○	○	○
PA12	TLN	Reverse torque limit	100.0	%	○	○	○
PA13	*PLSS	Selection of servo motor stop pattern at LSP/LSN signal off	0000h		○		
PA14	*POL	Rotation direction selection	0		○		
PA15	*ENR	Encoder output pulses	4000	pulse/rev	○	○	○
PA16		For manufacturer setting					
PA17							
PA18							
PA19	*BLK	Parameter block	000Bh		○	○	○

5. PARAMETERS

5.1.2 Parameter block

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA19	*BLK	Parameter block	000Bh		Refer to the text.	○	○	○

POINT

- This parameter is made valid when power is switched off, then on after setting.

In the factory setting, this servo amplifier allows changes to the basic setting parameter, gain/filter parameter and extension setting parameter settings. With the setting of parameter No. PA19, write can be disabled to prevent accidental changes.

The following table indicates the parameters which are enabled for reference and write by the setting of parameter No. PA19. Operation can be performed for the parameters marked ○.

Parameter No. PA19 Setting	Setting Operation	Basic Setting Parameters No. PA □□	Gain/Filter Parameters No. PB □□	Extension Setting Parameters No. PC □□	I/O Setting Parameters No. PD □□
0000h	Reference	○			
	Write	○			
000Bh (initial value)	Reference	○	○	○	
	Write	○	○	○	
000Ch	Reference	○	○	○	○
	Write	○	○	○	○
100Bh	Reference	○			
	Write	Parameter No. PA19 only			
100Ch	Reference	○	○	○	○
	Write	Parameter No. PA19 only			

5. PARAMETERS

5.1.3 Selection of control mode

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA01	*STY	Control mode	0000h		Refer to the text.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

POINT

- This parameter is made valid when power is switched off, then on after setting.

Select the control mode of the servo amplifier.

Parameter No. PA01

0	0	0	
---	---	---	--

Selection of 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

5.1.4 Selection of regenerative brake option

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA02	*REG	Regenerative brake option	0000h		Refer to the text.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

POINT

- This parameter is made valid when power is switched off, then on after setting.
- Wrong setting may cause the regenerative brake option to burn.
- If the regenerative brake option selected is not for use with the servo amplifier, parameter error (AL.37) occurs.

Set this parameter when using the regenerative brake option.

Parameter No. PA02

0	0		
---	---	--	--

Selection of regenerative brake option

- 00: Regenerative brake option is not used
 - For MR-J3-10A, regenerative brake resistor is not used.
 - For MR-J3-20A or more, built-in regenerative brake resistor is used.
- 02: MR-RB032
- 03: MR-RB12
- 04: MR-RB32
- 05: MR-RB30
- 06: MR-RB50

5. PARAMETERS

5.1.5 Using absolute position detection system

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA03	*ABS	Absolute position detection system	0000h		Refer to the text.	○		

POINT

- This parameter is made valid when power is switched off, then on after setting.

Set this parameter when using the absolute position detection system in the position control mode.

Parameter No. PA03

0	0	0	
---	---	---	--

- Selection of absolute position detection system (refer to Chapter 14)
- 0: Used in incremental system
 - 1: Used in absolute position detection system
ABS transfer by DI0
 - 2: Used in absolute position detection system
ABS transfer by communication

5.1.6 Using electromagnetic brake interlock (MBR)

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA04	*AOP1	Function selection A-1	0000h		Refer to the text.	○	○	○

POINT

- This parameter is made valid when power is switched off, then on after setting.

Set this parameter when assigning the electromagnetic brake to the CN1-23 pin.

Parameter No. PA04

0	0	0	
---	---	---	--

- CN1-23 pin function selection
- 0: Output device assigned with parameter No. PD14
 - 1: Electromagnetic brake interlock (MBR)

5. PARAMETERS

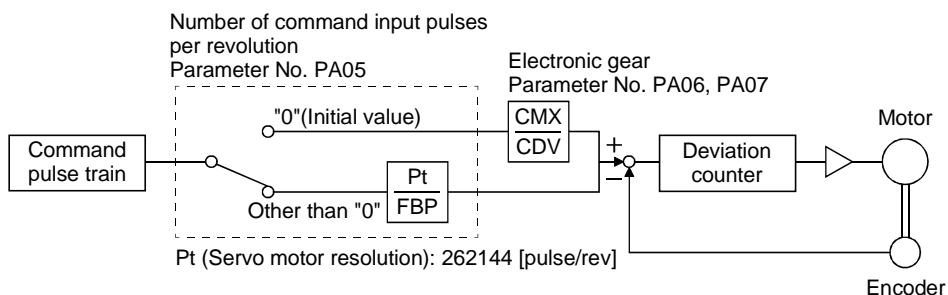
5.1.7 Number of command input pulses per servo motor revolution

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA05	*FBP	Number of command input pulses per revolution	0		0 · 1000 to 50000	○		

POINT

- This parameter is made valid when power is switched off, then on after setting.

When "0" (initial value) is set in parameter No. PA05, the electronic gear (parameter No. PA06, No. PA07) is made valid. When the setting is other than "0", that value is used as the command input pulses necessary to rotate the servo motor one turn. At this time, the electronic gear is made invalid.



Parameter No. PA05 Setting	Description
0	Electronic gear (parameter No. PA06, No. PA07) is made valid.
1000 to 50000	Number of command input pulses necessary to rotate the servo motor one turn [pulse]

5. PARAMETERS

5.1.8 Electronic gear

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA06	CMX	Electronic gear numerator (command pulse multiplying factor numerator)	1		1 to 1048576	○		
PA07	CDV	Electronic gear denominator (command pulse multiplying factor denominator)	1		1 to 1048576	○		



CAUTION

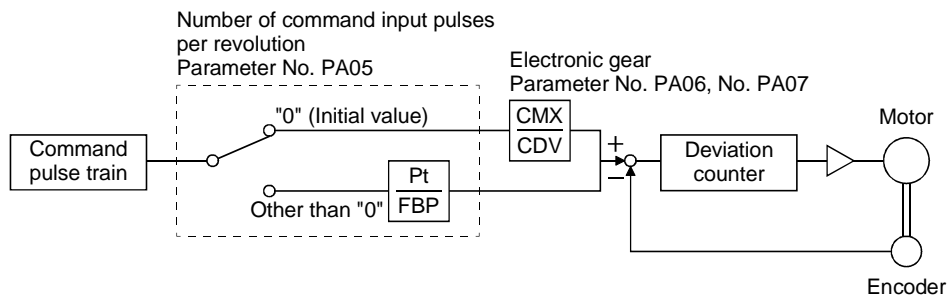
▪ Wrong setting can lead to unexpected fast rotation, causing injury.

POINT

- The guideline of the electronic gear setting range is $\frac{1}{10} < \frac{\text{CMX}}{\text{CDV}} < 2000$.
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.
- The following specification symbols are required to calculate the electronic gear.

(1) Concept of electronic gear

The machine can be moved at any multiplication factor to input pulses.



$$\frac{\text{CMX}}{\text{CDV}} = \frac{\text{Parameter No. PA06}}{\text{Parameter No. PA07}}$$

The following setting examples are used to explain how to calculate the electronic gear:

POINT

- The following specification symbols are required to calculate the electronic gear
- Pb : Ballscrew lead [mm]
n : Reduction ratio
Pt : Servo motor resolution [pulses/rev]
 $\Delta \ell_0$: Travel per command pulse [mm/pulse]
 ΔS : Travel per servo motor revolution [mm/rev]
 $\Delta \theta^\circ$: Angle per pulse [$^\circ$ /pulse]
 $\Delta \theta$: Angle per revolution [$^\circ$ /rev]

5. PARAMETERS

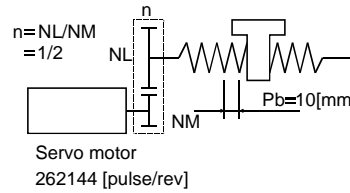
(a) For motion in increments of 10 μ m per pulse

Machine specifications

Ballscrew lead Pb = 10 [mm]

Reduction ratio: n = 1/2

Servo motor resolution: Pt = 262144 [pulses/rev]



$$\frac{CMX}{CDV} = \Delta \ell_0 \cdot \frac{Pt}{\Delta S} = \Delta \ell_0 \cdot \frac{Pt}{n \cdot Pb} = 10 \times 10^{-3} \cdot \frac{262144}{1/2 \cdot 10} = \frac{524288}{1000} = \frac{65536}{125}$$

Hence, set 65536 to CMX and 125 to CDV.

(b) Conveyor setting example

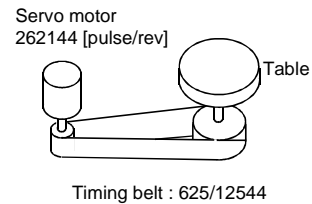
For rotation in increments of 0.01° per pulse

Machine specifications

Table : 360° /rev

Reduction ratio: n = 625/12544

Servo motor resolution: Pt = 262144 [pulses/rev]



$$\frac{CMX}{CDV} = \Delta \theta^\circ \cdot \frac{Pt}{\Delta \theta} = 0.01 \cdot \frac{262144}{625/12544 \cdot 360} = \frac{102760448}{703125} \dots\dots\dots (5.1)$$

Since CMX is not within the setting range in this status, it must be reduced to the lowest term.

When CMX has been reduced to a value within the setting range, round off the value to the nearest unit.

$$\frac{CMX}{CDV} = \frac{102760448}{703125} = \frac{822083.6}{5625} \cong \frac{822084}{5625}$$

Hence, set 822084 to CMX and 5625 to CDV.

POINT
For unlimited one-way rotation, e.g. an index table, indexing positions will be missed due to cumulative error produced by rounding off. For example, entering a command of 36000 pulses in the above example causes the table to rotate only: $36000 \cdot \frac{822084}{5625} \cdot \frac{1}{262144} \cdot \frac{625}{12544} \cdot 360^\circ = 360.00018^\circ$ Therefore, indexing cannot be done in the same position on the table.

5. PARAMETERS

(2) Instructions for reduction

The calculated value before reduction must be as near as possible to the calculated value after reduction. In the case of (1), (b) in this section, an error will be smaller if reduction is made to provide no fraction for CDV. The fraction of Expression (5.1) before reduction is calculated as follows.

$$\frac{CMX}{CDV} = \frac{102760488}{7023125} = 146.1481927 \dots\dots\dots (5.2)$$

The result of reduction to provide no fraction for CMX is as follows.

$$\frac{CMX}{CDV} = \frac{102760488}{7023125} = \frac{917504}{6277.9} \div \frac{917504}{62778} = 146.1459063 \dots\dots\dots (5.3)$$

The result of reduction to provide no fraction for CDV is as follows.

$$\frac{CMX}{CDV} = \frac{102760488}{7023125} = \frac{822083.6}{5625} \div \frac{822084}{5625} = 146.1482667 \dots\dots\dots (5.4)$$

As a result, it is understood that the value nearer to the calculation result of Expression (5.2) is the result of Expression (5.4). Accordingly, the set values of (1), (b) in this section are CMX=822084, CDV=5625.

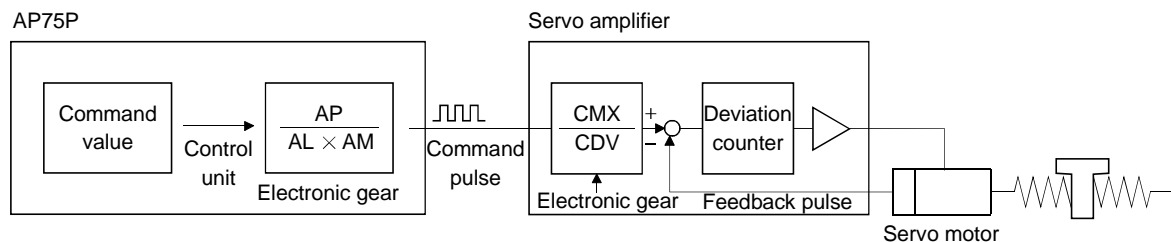
(3) Setting for use of QD75

The QD75 also has the following electronic gear parameters. Normally, the servo amplifier side electronic gear must also be set due to the restriction on the command pulse frequency (differential 1Mpulse/s, open collector 200kpulse/s).

AP: Number of pulses per motor revolution

AL: Moving distance per motor revolution

AM: Unit scale factor



The resolution of the servo motor is 262144 pulses/rev. For example, the pulse command needed to rotate the servo motor is as follows

Servo motor speed [r/min]	Required pulse command
2000	$262144 \times 2000 / 60 = 8738133 \text{ pulse/s}$
3000	$262144 \times 3000 / 60 = 13107200 \text{ pulse/s}$

Use the electronic gear of the servo amplifier to run the servo motor under the maximum output pulse command of the QD75.

5. PARAMETERS

To rotate the servo motor at 3000r/min in the open collector system (200kpulse/s), set the electronic gear as follows

$$f \cdot \frac{CMX}{CDV} = \frac{N_0}{60} \cdot pt$$

f : Input pulses [pulse/s]

N₀ : Servo motor speed [r/min]

Pt : Servo motor resolution [pulse/rev]

$$200 \cdot 10^3 \cdot \frac{CMX}{CDV} = \frac{3000}{60} \cdot 262144$$

$$\frac{CMX}{CDV} = \frac{3000}{60} \cdot \frac{262144}{200 \cdot 10^3} = \frac{3000 \cdot 262144}{60 \cdot 200000} = \frac{8192}{125}$$

The following table indicates the electronic gear setting example (ballscrew lead = 10mm) when the QD75 is used in this way.

Rated servo motor speed				3000r/min		2000r/min	
Servo amplifier	Input system			Open collector	Differential line driver	Open collector	Differential line driver
	Max. input pulse frequency [pulse/s]			200k	1M	200k	1M
	Feedback pulse/revolution [pulse/rev]			262144		262144	
	Electronic gear (CMX/CDV)			8192/125	8192/625	16384/375	16384/1875
AD75P	Command pulse frequency [kpulse/s] (Note)			200k	1M	200k	1M
	Number of pulses per servo motor revolution as viewed from QD75[pulse/rev]			4000	20000	6000	30000
	Electronic gear	Minimum command unit 1pulse	AP	1	1	1	1
			AL	1	1	1	1
			AM	1	1	1	1
	Electronic gear	Minimum command unit 0.1μm	AP	4000	20000	6000	30000
			AL	100.0[μm]	100.0[μm]	100.0[μm]	100.0[μm]
			AM	10	10	10	10

Note. Command pulse frequency at rated speed

POINT
<ul style="list-style-type: none"> In addition to the setting method using the electronic gear given here, the number of pulses per servo motor revolution can also be set directly using parameter No. PA05. In this case, parameter No. PA05 is the "Number of pulses per servo motor revolution as viewed from QWD75".

5. PARAMETERS

5.1.9 Auto tuning

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA08	ATU	Auto tuning mode	0001h		Refer to the text.	<input type="radio"/>	<input type="radio"/>	
PA09	RSP	Auto tuning response	12		1 to 32	<input type="radio"/>	<input type="radio"/>	

Make gain adjustment using auto tuning. Refer to Section 7.2 for details.

(1) Auto tuning mode (parameter No. PA08)

Select the gain adjustment mode.

Parameter No. PA08

0	0	0	
---	---	---	--

Gain adjustment mode setting

Setting	Gain adjustment mode	Automatically set parameter No. (Note)
0	Interpolation mode	PB06 · PB08 · PB09 · PB10
1	Auto tuning mode 1	PB06 · PB07 · PB08 · PB09 · PB10
2	Auto tuning mode 2	PB07 · PB08 · PB09 · PB10
3	Manual mode	

Note. The parameters have the following names.

Parameter No.	Name
PB06	Ratio of load inertia moment to servo motor inertia moment
PB07	Model loop gain
PB08	Position loop gain
PB09	Speed loop gain
PB10	Speed integral compensation

5. PARAMETERS

(2) Auto tuning response (parameter No. PA09)

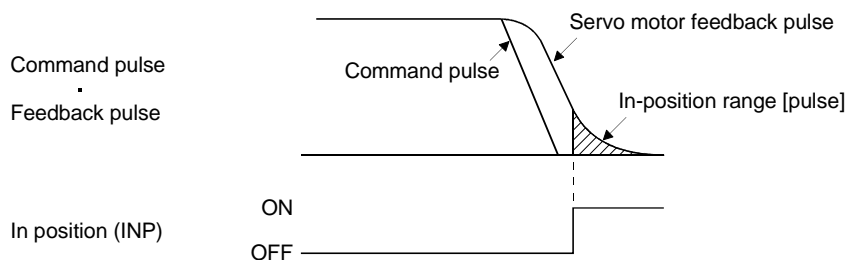
If the machine hunts or generates large gear sound, decrease the set value. To improve performance, e.g. shorten the settling time, increase the set value.

Setting	Response	Guideline for Machine Resonance Frequency [Hz]	Setting	Response	Guideline for Machine Resonance Frequency [Hz]
1	Low response ↑	10.0	17	Low response ↑	67.1
2		11.3	18		75.6
3		12.7	19		85.2
4		14.3	20		95.9
5		16.1	21		108.0
6		18.1	22		121.7
7		20.4	23		137.1
8		23.0	24		154.4
9		25.9	25		173.9
10		29.2	26		195.9
11		32.9	27		220.6
12		37.0	28		248.5
13		41.7	29		279.9
14		47.0	30		315.3
15		52.9	31		355.1
16	Middle response	59.6	32	Middle response	400.0

5.1.10 In-position range

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA10	INP	In-position range	100	pulse	0 to 10000	○		

Set the range, where In position (INP) is output, in the command pulse unit before calculation of the electronic gear. With the setting of parameter No. PC24, the range can be changed to the encoder output pulse unit.



5. PARAMETERS

5.1.11 Torque limit

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA11	TLP	Forward rotation torque limit	100.0	%	0 to 1000	○	○	○
PA12	TLN	Reverse rotation torque limit	100.0	%	0 to 1000	○	○	○

The torque generated by the servo motor can be limited. Refer to Section 3.6.1 (5) and use these parameters.

(1) Forward rotation torque limit (parameter No. PA11)

Set this parameter on the assumption that the maximum torque is 100[%]. Set this parameter when limiting the torque of the servo motor in the CCW driving mode or CW regeneration mode. Set this parameter to "0.0" to generate no torque.

When torque is output with the analog monitor output, the smaller torque of the values in this parameter and parameter No. PA12 (reverse rotation torque limit) is the maximum output voltage (+8V).

(2) Reverse rotation torque limit (parameter No. PA12)

Set this parameter on the assumption that the maximum torque is 100[%]. Set this parameter when limiting the torque of the servo motor in the CW driving mode or CCW regeneration mode. Set this parameter to "0.0" to generate no torque.

5. PARAMETERS



5.1.12 Selection of command pulse input form

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA13	*PLSS	Command pulse input form	0000h		Refer to the text.	○		

POINT

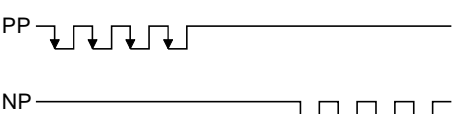
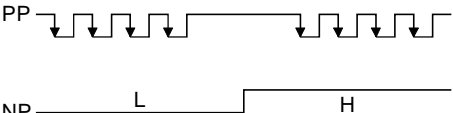
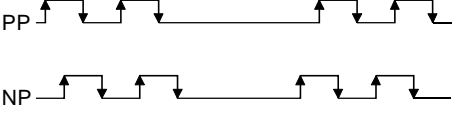
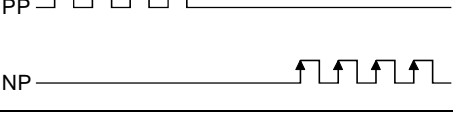
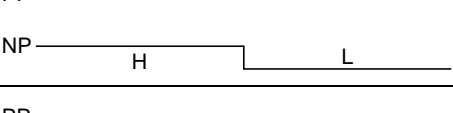
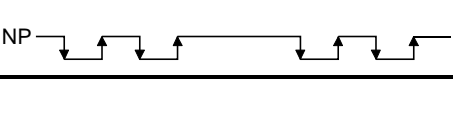
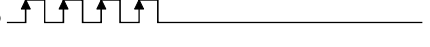

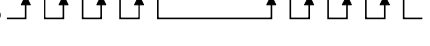
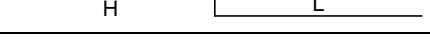


- This parameter is made valid when power is switched off, then on after setting.

Select the input form of the pulse train input signal. Command pulses may be input in any of three different forms, for which positive or negative logic can be chosen.

Arrow  or  in the table indicates the timing of importing a pulse train.

A- and B-phase pulse trains are imported after they have been multiplied by 4.

Selection of command pulse input form

Setting	Pulse train form		Forward rotation command	Reverse rotation command
0010h	Negative logic	Forward rotation pulse train Reverse rotation pulse train	PP  NP 	
0011h		Pulse train + sign	PP  NP 	
0012h		A-phase pulse train B-phase pulse train	PP  NP 	
0000h	Positive logic	Forward rotation pulse train Reverse rotation pulse train	PP  NP 	
0001h		Pulse train + sign	PP  NP 	
0002h		A-phase pulse train B-phase pulse train	PP  NP 	

5. PARAMETERS

5.1.13 Selection of servo motor rotation direction

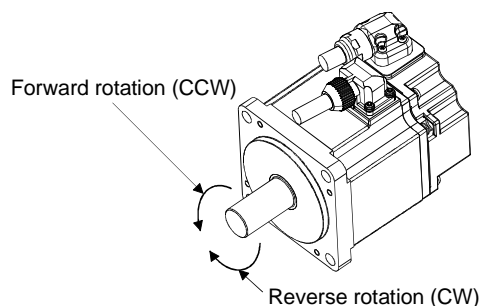
Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA14	*POL	Rotation direction selection	0		0 ~ 1	○		

POINT

- This parameter is made valid when power is switched off, then on after setting.

Select servo motor rotation direction relative to the input pulse train.

Parameter No. PA14 Setting	Servo Motor Rotation Direction	
	When forward rotation pulse is input (Note)	When reverse rotation pulse is input (Note)
0	CCW	CW
1	CW	CCW



5.1.14 Encoder output pulse

Parameter			Initial Value	Unit	Setting Range	Control Mode		
No.	Symbol	Name				Position	Speed	Torque
PA15	*ENR	Encoder output pulse	4000	pulse/rev	1 to 100000	○	○	○

POINT

- This parameter is made valid when power is switched off, then on after setting.

Used to set the encoder pulses (A-phase, B-phase) output by the servo amplifier.

Set the value 4 times greater than the A-phase or B-phase pulses.

You can use parameter No. PC19 to choose the output pulse setting or output division ratio setting.

The number of A/B-phase pulses actually output is 1/4 times greater than the preset number of pulses.

The maximum output frequency is 4.6Mpps (after multiplication by 4). Use this parameter within this range.

5. PARAMETERS

(1) For output pulse designation

Set "□□ 0 □" (initial value) in parameter No. PC19.

Set the number of pulses per servo motor revolution.

Output pulse = set value [pulses/rev]

For instance, set "5600" to Parameter No. pa15, the actually output A/B-phase pulses are as indicated below:

$$\text{A} \cdot \text{B-phase output pulses} = \frac{5600}{4} = 1400[\text{pulse}]$$

(2) For output division ratio setting

Set "□□ 1 □" in parameter No. PC19.

The number of pulses per servo motor revolution is divided by the set value.

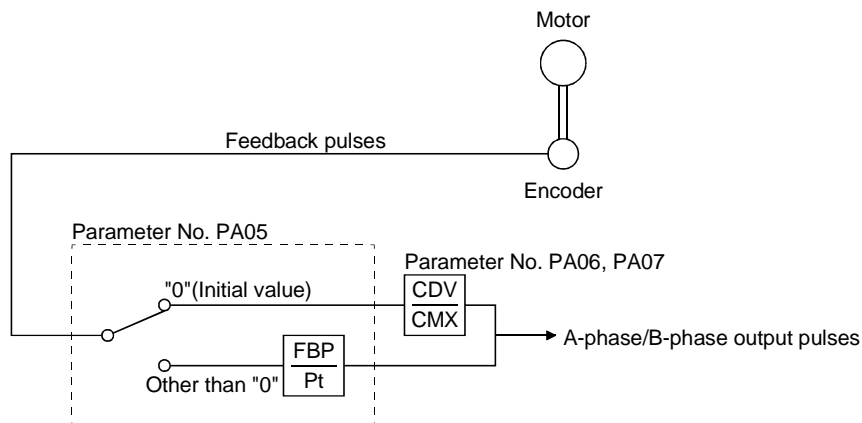
$$\text{Output pulse} = \frac{\text{Resolution per servo motor revolution}}{\text{Set value}} [\text{pulses/rev}]$$

For instance, set "8" to Parameter No. pa15, the actually output A/B-phase pulses are as indicated below:

$$\text{A} \cdot \text{B-phase output pulses} = \frac{262144}{8} \cdot \frac{1}{4} = 8192[\text{pulse}]$$

(3) When outputting pulse train similar to command pulses

Set parameter No. PC19 to "□□ 2 □". The feedback pulses from the servo motor encoder are processed and output as shown below. The feedback pulses can be output in the same pulse unit as the command pulses.



5. PARAMETERS

5.2 Gain/Filter Parameters (No. PB□□)

POINT

- For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

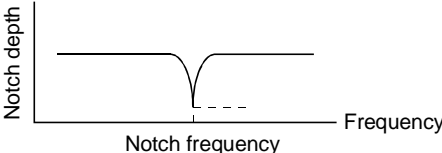
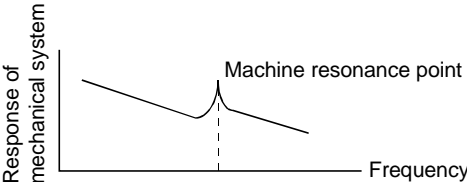
5.2.1 Parameter list

No.	Symbol	Name	Initial Value	Unit	Control Mode		
					Position	Speed	Torque
PB01	FILT	Adaptive tuning mode (Adaptive filter II)	0000h		○	○	
PB02	VRFT	Vibration suppression control filter tuning mode (Advanced vibration suppression control)	0000h		○		
PB03	PST	Position command acceleration/deceleration time constant (Position smoothing)	0	ms	○		
PB04	FFC	Feed forward gain	0	%	○		
PB05		For manufacturer setting	500				
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	7.0	times	○	○	
PB07	PG1	Model loop gain	24	rad/s	○		
PB08	PG2	Position loop gain	37	rad/s	○		
PB09	VG2	Speed loop gain	823	rad/s	○	○	
PB10	VIC	Speed integral compensation	33.7	ms	○	○	
PB11	VDC	Speed differential compensation	980		○	○	
PB12		For manufacturer setting	0				
PB13	NH1	Machine resonance suppression filter 1	4500	Hz	○	○	
PB14	NHQ1	Notch form selection 1	0000h		○		
PB15	NH2	Machine resonance suppression filter 2	4500	Hz	○		
PB16	NHQ2	Notch form selection 2	0000h		○		
PB17		For manufacturer setting	0000				
PB18	LPF	Low-pass filter	3141	rad/s	○		
PB19	VRF1	Vibration suppression control vibration frequency setting	100.0	Hz	○		
PB20	VRF2	Vibration suppression control resonance frequency setting	100.0	Hz	○		
PB21		For manufacturer setting	0.0				
PB22			0.0				
PB23	VFBF	Low-pass filter selection	0000h		○		
PB24	*MVS	Slight vibration suppression control selection	0000h		○		
PB25	*BOP1	Function selection B-1	0000h		○		
PB26	*CDP	Gain changing selection	0000h		○	○	
PB27	CDL	Gain changing condition	10		○	○	
PB28	CDT	Gain changing time constant	1	ms	○	○	
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	7.0	times	○	○	
PB30	PG2B	Gain changing position loop gain	37	rad/s	○		
PB31	VG2B	Gain changing speed loop gain	823	rad/s	○	○	
PB32	VICB	Gain changing speed integral compensation	33.7	ms	○	○	
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	100.0	Hz	○		
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	100.0	Hz	○		
PB35		For manufacturer setting	0.0				
PB36			0.0				
PB37			100				
PB38			0				
PB39			0				
PB40			0				
PB41			1125				

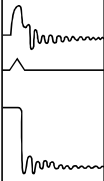
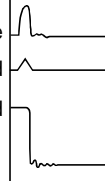
5. PARAMETERS

No.	Symbol	Name	Initial Value	Unit	Control Mode		
					Position	Speed	Torque
PB42		For manufacturer setting	1125				
PB43			0004h				
PB44			0000h				
PB45			0000h				

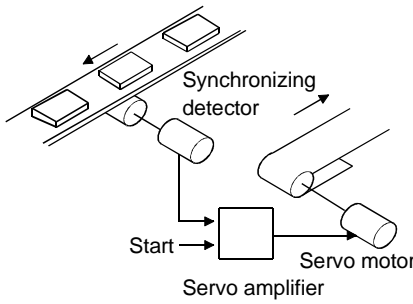
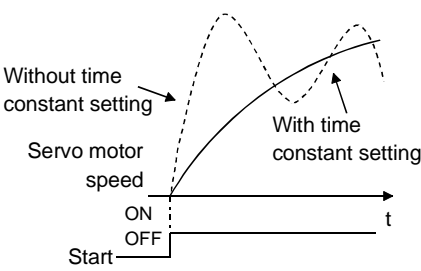
5.2.2 Detail list

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode														
						Position	Speed	Torque												
PB01	FILT	<p>Adaptive tuning mode (adaptive filter II)</p> <p>Select the setting method for filter tuning. Setting this parameter to "□□□1" (filter tuning mode 1) automatically changes the machine resonance suppression filter 1 (parameter No. PB13) and notch shape selection (parameter No. PB14).</p> <div><div><div>000□</div><div>Filter tuning mode selection</div></div><table border="1"><thead><tr><th>Setting</th><th>Filter adjustment mode</th><th>Automatically set parameter</th></tr></thead><tbody><tr><td>0</td><td>Filter OFF</td><td>(Note)</td></tr><tr><td>1</td><td>Filter tuning mode</td><td>Parameter No. PB13 Parameter No. PB14</td></tr><tr><td>2</td><td>Manual mode</td><td></td></tr></tbody></table><p>Note. Parameter No. PB13 and PB14 are fixed to the initial values.</p><p>When this parameter is set to "□□□1", the tuning is completed after positioning is done the predetermined number or times for the predetermined period of time, and the setting changes to "□□□2". When the filter tuning is not necessary, the setting changes to "□□□0". When this parameter is set to "□□□0", the initial values are set to the machine resonance suppression filter 1 and notch shape selection. However, this does not occur when the servo off.</p></div> <td>0000h</td> <td></td> <td></td> <td>○</td> <td>○</td> <td></td>	Setting	Filter adjustment mode	Automatically set parameter	0	Filter OFF	(Note)	1	Filter tuning mode	Parameter No. PB13 Parameter No. PB14	2	Manual mode		0000h			○	○	
Setting	Filter adjustment mode	Automatically set parameter																		
0	Filter OFF	(Note)																		
1	Filter tuning mode	Parameter No. PB13 Parameter No. PB14																		
2	Manual mode																			

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode														
						Position	Speed	Torque												
PB02	VRFT	<p>Vibration suppression control tuning mode (advanced vibration suppression control)</p> <p>The vibration suppression is valid when the parameter No. PA08 (auto tuning) setting is "□□□2" or "□□□3". When PA08 is "□□□1", vibration suppression is always invalid.</p> <p>Select the setting method for vibration suppression control tuning. Setting this parameter to "□□□1" (vibration suppression control tuning mode) automatically changes the vibration suppression control - vibration frequency (parameter No. PB19) and vibration suppression control - resonance frequency (parameter No. PB20) after positioning is done the predetermined number of times.</p> <div><div><p>Drop pulse Command</p><p>Machine end position</p></div><div><p>Automatic adjustment</p><p>→</p></div><div><p>Drop pulse Command</p><p>Machine end position</p></div></div> <div><div><div>0</div><div>0</div><div>0</div><div></div></div><div><p>Vibration suppression control tuning mode</p></div></div> <table><tr><th>Setting</th><th>Vibration suppression control tuning mode</th><th>Automatically set parameter</th></tr><tr><td>0</td><td>Vibration suppression control OFF</td><td>(Note)</td></tr><tr><td>1</td><td>Vibration suppression control tuning mode (Advanced vibration suppression control)</td><td>Parameter No. PB19 Parameter No. PB20</td></tr><tr><td>2</td><td>Manual mode</td><td></td></tr></table> <p>Note. Parameter No. PB19 and PB20 are fixed to the initial values.</p> <p>When this parameter is set to "□□□1", the tuning is completed after positioning is done the predetermined number or times for the predetermined period of time, and the setting changes to "□□□2". When the vibration suppression control tuning is not necessary, the setting changes to "□□□0". When this parameter is set to "□□□0", the initial values are set to the vibration suppression control - vibration frequency and vibration suppression control - resonance frequency.</p>	Setting	Vibration suppression control tuning mode	Automatically set parameter	0	Vibration suppression control OFF	(Note)	1	Vibration suppression control tuning mode (Advanced vibration suppression control)	Parameter No. PB19 Parameter No. PB20	2	Manual mode		0000h			○		
Setting	Vibration suppression control tuning mode	Automatically set parameter																		
0	Vibration suppression control OFF	(Note)																		
1	Vibration suppression control tuning mode (Advanced vibration suppression control)	Parameter No. PB19 Parameter No. PB20																		
2	Manual mode																			

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PB03	PST	<p>Position command acceleration/deceleration time constant (position smoothing)</p> <p>Used to set the time constant of a low pass filter in response to the position command.</p> <p>You can use parameter No. PB25 to choose the primary delay or linear acceleration/deceleration control system. When you choose linear acceleration/deceleration, the setting range is 0 to 10ms. Setting of longer than 10ms is recognized as 10ms.</p> <div style="border: 1px solid black; padding: 5px; margin: 10px 0;"> <p>POINT</p> <ul style="list-style-type: none"> When you have chosen linear acceleration/deceleration, do not select control selection (parameter No. PA01) and restart after instantaneous power failure (parameter No. PC22). Doing so will cause the servo motor to make a sudden stop at the time of position control switching or restart. </div> <p>Example: When a command is given from a synchronizing detector, synchronous operation can be started smoothly if started during line operation.</p>  	0	ms	0 to 20000	○		
PB04	FFC	<p>Feed forward gain</p> <p>Set the feed forward gain. 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 1s or more as the acceleration/deceleration time constant up to the rated speed.</p>	0	%	0 to 100	○		
PB05		<p>For manufacturer setting</p> <p>Never change this setting.</p>	500					
PB06	GD2	<p>Ratio of load inertia moment to servo motor inertia moment</p> <p>Used to set the ratio of the load inertia moment to the servo motor shaft inertia moment. When auto tuning mode 1 and interpolation mode is selected, the result of auto tuning is automatically used. (Refer to section 7.1.1)</p> <p>In this case, it varies between 0 and 100.0.</p>	7.0	times	0 to 300.0	○	○	

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PB07	PG1	Model loop gain Set the response gain up to the target position. Increase the gain to improve trackability in response to the position command. When auto turning mode 1,2 is selected, the result of auto turning is automatically used.	24	rad/s	4 to 2000	○		
PB08	PG2	Position loop gain Used to set the gain of the position loop. Set this parameter to increase the position response to level load disturbance. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 and interpolation mode is selected, the result of auto tuning is automatically used.	37	rad/s	1 to 1000	○		
PB09	VG2	Speed loop gain Normally this parameter setting need not be changed. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1 • 2, manual mode and interpolation mode is selected, the result of auto tuning is automatically used. Note. The setting range of 50000 applies to the servo amplifier whose software version is A3 or later. The setting range of the servo amplifier whose software version is older than A3 is 20 to 20000. When the software version of MR Configurator is A3 or earlier, 20001 or more cannot be set. Use the display/operation section of the servo amplifier to set 20001 or more.	823	rad/s	20 to 50000 (Note)	○	○	
PB10	VIC	Speed integral compensation Used to set the integral time constant of the speed loop. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1 • 2 and interpolation mode is selected, the result of auto tuning is automatically used.	33.7	ms	0.1 to 1000.0	○	○	
PB11	VDC	Speed differential compensation Used to set the differential compensation. Made valid when the proportion control (PC) is switched on.	980		0 to 1000	○	○	
PB12		For manufacturer setting Never change this setting.	0					
PB13	NH1	Machine resonance suppression filter 1 Set the notch frequency of the machine resonance suppression filter 1. Setting parameter No. PB01 (filter tuning mode 1) to "□□□1" automatically changes this parameter. When the parameter No. PB01 setting is "□□□0", the setting of this parameter is ignored.	4500	Hz	100 to 4500	○	○	

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																												
						Position	Speed	Torque																										
PB14	NHQ1	<p>Notch shape selection 1</p> <p>Used to selection the machine resonance suppression filter 1.</p> <div><div><div>0</div><div></div><div></div><div>0</div></div><div><div>Notch depth selection</div><table><tr><th>Setting value</th><th>Depth</th><th>Gain</th></tr><tr><td>0</td><td rowspan="3">Deep to</td><td>-40dB</td></tr><tr><td>1</td><td>-14dB</td></tr><tr><td>2</td><td>-8dB</td></tr><tr><td>3</td><td>Shallow</td><td>-4dB</td></tr></table></div><div><div>Notch width</div><table><tr><th>Setting value</th><th>Width</th><th>α</th></tr><tr><td>0</td><td rowspan="3">Standard to</td><td>2</td></tr><tr><td>1</td><td>3</td></tr><tr><td>2</td><td>4</td></tr><tr><td>3</td><td>Wide</td><td>5</td></tr></table></div></div> <p>Setting parameter No. PB01 (filter tuning mode 1) to "□□□1" automatically changes this parameter.</p> <p>When the parameter No. PB01 setting is "□□□0", the setting of this parameter is ignored.</p>	Setting value	Depth	Gain	0	Deep to	-40dB	1	-14dB	2	-8dB	3	Shallow	-4dB	Setting value	Width	α	0	Standard to	2	1	3	2	4	3	Wide	5	0000h		Refer to Name and function column.	○		
Setting value	Depth	Gain																																
0	Deep to	-40dB																																
1		-14dB																																
2		-8dB																																
3	Shallow	-4dB																																
Setting value	Width	α																																
0	Standard to	2																																
1		3																																
2		4																																
3	Wide	5																																
PB15	NH2	<p>Machine resonance suppression filter 2</p> <p>Set the notch frequency of the machine resonance suppression filter 2.</p> <p>Set parameter No. PB16 (notch shape selection 2) to "□□□1" to make this parameter valid.</p>	4500	Hz	100 to 4500	○																												
PB16	NHQ2	<p>Notch shape selection 2</p> <p>Select the shape of the machine resonance suppression filter 2.</p> <div><div><div>0</div><div></div><div></div><div></div></div><div><div>Machine resonance suppression filter 2 selection</div><div>0: Invalid</div><div>1: Valid</div></div><div><div>Notch depth selection</div><table><tr><th>Setting value</th><th>Depth</th><th>Gain</th></tr><tr><td>0</td><td rowspan="3">Deep to</td><td>-40dB</td></tr><tr><td>1</td><td>-14dB</td></tr><tr><td>2</td><td>-8dB</td></tr><tr><td>3</td><td>Shallow</td><td>-4dB</td></tr></table></div><div><div>Notch width</div><table><tr><th>Setting value</th><th>Width</th><th>α</th></tr><tr><td>0</td><td rowspan="3">Standard to</td><td>2</td></tr><tr><td>1</td><td>3</td></tr><tr><td>2</td><td>4</td></tr><tr><td>3</td><td>Wide</td><td>5</td></tr></table></div></div>	Setting value	Depth	Gain	0	Deep to	-40dB	1	-14dB	2	-8dB	3	Shallow	-4dB	Setting value	Width	α	0	Standard to	2	1	3	2	4	3	Wide	5	0000h		Refer to Name and function column.	○		
Setting value	Depth	Gain																																
0	Deep to	-40dB																																
1		-14dB																																
2		-8dB																																
3	Shallow	-4dB																																
Setting value	Width	α																																
0	Standard to	2																																
1		3																																
2		4																																
3	Wide	5																																
PB17		<p>For manufacturer setting</p> <p>Never change this setting.</p>	0000																															

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PB18	LPF	Low pass filter setting Set the low pass filter. Setting parameter No. PB23 (low pass filter selection) to "□□0□" automatically changes this parameter. When parameter No. PB23 is set to "□□1□", this parameter can be set manually.	3141	rad/s	100 to 18000	○		
PB19	VRF1	Vibration suppression control - vibration frequency setting Set the vibration frequency for vibration suppression control to suppress low-frequency machine vibration, such as enclosure vibration. Setting parameter No. PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No. PB02 is set to "□□□2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0	○		
PB20	VRF2	Vibration suppression control - resonance frequency setting Set the resonance frequency for vibration suppression control to suppress low-frequency machine vibration, such as enclosure vibration. Setting parameter No. PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No. PB02 is set to "□□□2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0	○		
PB21		For manufacturer setting	0.0					
PB22		Never change this setting.	0.0					
PB23	VFBF	Low pass filter selection Select the low pass filter. <div><div>00□0</div><div>Low pass filter selection 0: Automatic setting 1: Manual setting (parameter No. PB18 setting)</div></div> When automatic setting has been selected, select the filter that has $\frac{VG2 \cdot 10}{1 + GD2}$ [rad/s] the band width close to the one calculated with	0000h		Refer to Name and function column.	○		
PB24	*MVS	Slight vibration suppression control selection Select the slight vibration suppression control. When parameter No. PA08 (auto tuning mode) is set to "□□□3", this parameter is made valid. In the speed control mode, set parameter No. PC23 to "□□□1" to make "servo lock at speed control mode stop" valid to use this parameter. <div><div>000□</div><div>Slight vibration suppression control selection 0: Invalid 1: Valid</div></div>	0000h		Refer to Name and function column.	○		

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PB25	*BOP1	Function selection B-1 Select the control systems for position command acceleration/deceleration time constant (parameter No. PB03). <div style="display: flex; align-items: center; margin-top: 10px;"> <div style="border: 1px solid black; padding: 2px 5px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px 5px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px 5px; margin-right: 5px;">0</div> </div> <div style="margin-left: 20px;"> Control of position command acceleration/deceleration time constant 0: Primary delay 1: Linear acceleration/deceleration When linear acceleration/deceleration has been selected, do not execute control switching after instantaneous power failure. The servo motor will make a hard stop at control switching or automatic restart. </div>	0000h		Refer to Name and function column.	○		
PB26	*CDP	Gain changing selection Select the gain changing condition. (Refer to Section 8.6.) <div style="display: flex; align-items: center; margin-top: 10px;"> <div style="border: 1px solid black; padding: 2px 5px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px 5px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px 5px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px 5px;"></div> </div> <div style="margin-left: 20px;"> Gain changing selection Under any of the following conditions, the gains change on the basis of the parameter No. PB29 to PB32 settings. 0: Invalid 1: Gain changing (CDP) is ON 2: Command frequency is parameter No. PB27 setting 3: Droop pulse value is parameter No. PB27 setting 4: Servo motor speed is parameter No. PB27 setting Gain changing condition 0: Valid at more than condition 1: Valid at less than condition </div>	0000h		Refer to Name and function column.	○	○	
PB27	CDL	Gain changing condition Used to set the value of gain changing condition (command frequency, droop pulses, servo motor speed) selected in parameter No. PB26. The set value unit changes with the changing condition item. (Refer to Section 8.6.)	10	kpps pulse r/min	0 to 9999	○	○	
PB28	CDT	Gain changing time constant Used to set the time constant at which the gains will change in response to the conditions set in parameters No. PB26 and PB27. (Refer to Section 8.6.)	1	ms	0 to 100	○	○	
PB29	GD2B	Gain changing - ratio of load inertia moment to servo motor inertia moment Used to set the ratio of load inertia moment to servo motor inertia moment when gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	7.0	times	0 to 300.0	○	○	
PB30	PG2B	Gain changing - position loop gain Set the position loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	37	rad/s	1 to 2000	○		

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PB31	VG2B	Gain changing - speed loop gain Set the speed loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3). Note. The setting range of 50000 applies to the servo amplifier whose software version is A3 or later. The setting range of the servo amplifier whose software version is older than A3 is 20 to 20000. When the software version of MR Configurator is A3 or earlier, 20001 or more cannot be set. Use the display/operation section of the servo amplifier to set 20001 or more.	823	rad/s	20 to 20000	○	○	
PB32	VICB	Gain changing - speed integral compensation Set the speed integral compensation when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: □□□3).	33.7	ms	0.1 to 5000.0	○	○	
PB33	VRF1B	Gain changing - vibration suppression control - vibration frequency setting Set the vibration frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No. PB02 setting is "□□□2" and the parameter No. PB26 setting is "□□□1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0	○		
PB34	VRF2B	Gain changing - vibration suppression control - resonance frequency setting Set the resonance frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No. PB02 setting is "□□□2" and the parameter No. PB26 setting is "□□□1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0	○		
PB35		For manufacturer setting	0.0					
PB36		Never change this setting.	0.0					
PB37			100					
PB38			0					
PB39			0					
PB40			0					
PB41			1125					
PB42			1125					
PB43			0004h					
PB44			0000h					
PB45			0000h					

5. PARAMETERS

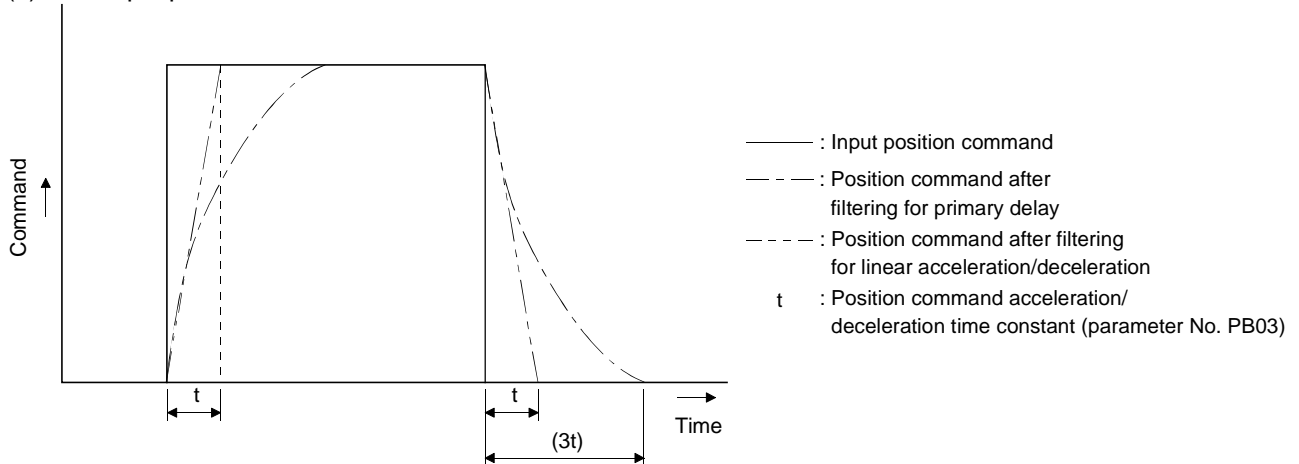
5.2.3 Position smoothing

By setting the position command acceleration/deceleration time constant (parameter No. PB03), you can run the servo motor smoothly in response to a sudden position command.

The following diagrams show the operation patterns of the servo motor in response to a position command when you have set the position command acceleration/deceleration time constant.

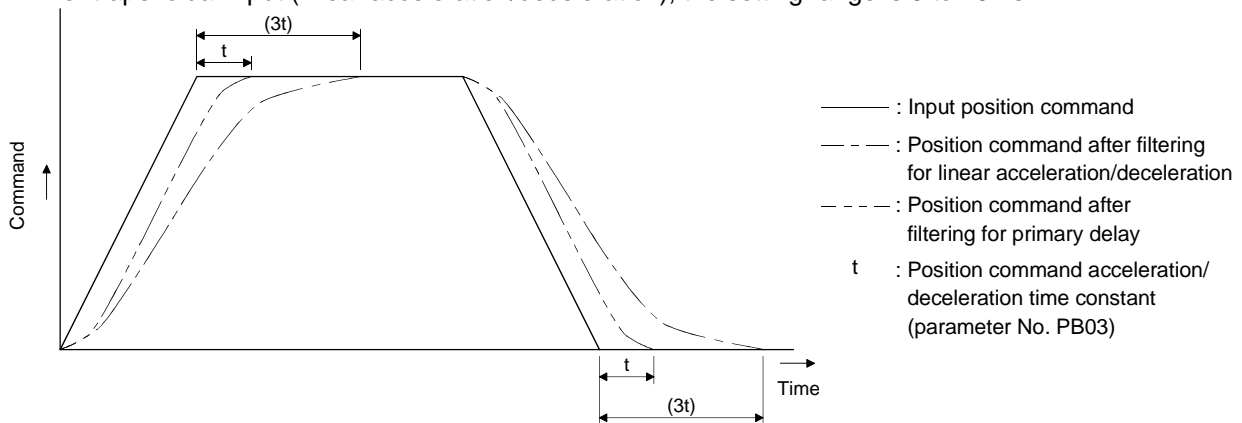
Choose the primary delay or linear acceleration/deceleration in parameter No. PB25 according to the machine used.

(1) For step input



(2) For trapezoidal input

For trapezoidal input (linear acceleration/deceleration), the setting range is 0 to 10ms.



5. PARAMETERS

5.3 Extension Setting Parameters (No. PC□□)

POINT

- For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

5.3.1 Parameter list

No.	Symbol	Name	Initial Value	Unit	Control Mode		
					Position	Speed	Torque
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 output 1	0000h		○	○	○
PC15	MOD2	Analog monitor output 2	0001h		○	○	○
PC16	MBR	Electromagnetic brake sequence output	100	ms	○	○	○
PC17	ZSP	Zero speed	50	r/min	○	○	○
PC18	*BPS	Alarm history clear	0000h		○	○	○
PC19	*ENRS	Encoder output pulses selection	0000h		○	○	○
PC20	*SNO	Parameter block	0	station	○	○	○
PC21	*SOP	communication function selection	0000h		○	○	○
PC22	*COP1	Function selection C-1	0000h		○	○	○
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		For manufacturer setting	0000h				
PC28			0000h				
PC29			0000h				
PC30	STA2	Acceleration time constant 2	0	ms		○	○
PC31	STB2	Deceleration time constant 2	0	ms		○	○
PC32	CMX2	Command pulse multiplying factor numerator 2	1		○		
PC33	CMX3	Command pulse multiplying factor numerator 3	1		○		

5. PARAMETERS

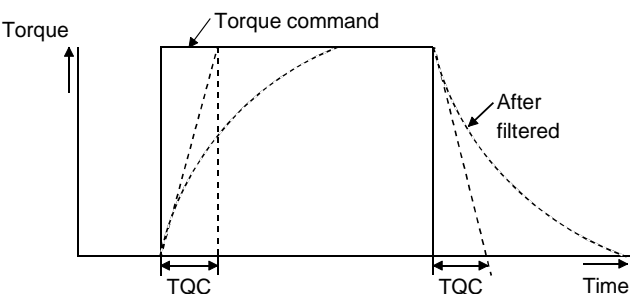
No.	Symbol	Name	Initial Value	Unit	Control Mode		
					Position	Speed	Torque
PC34	CMX4	Command pulse multiplying factor numerator 4	1		○		
PC35	TL2	For manufacturer setting	100.0	%	○	○	○
PC36	*DMD	Status display selection	0000h		○	○	○
PC37	VCO	Analog speed command offset	0	mV		○	
		Analog speed limit 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			0				
PC44			0				
PC45			0				
PC46			0				
PC47			0				
PC48			0				
PC49			0				
PC50			0				

5. PARAMETERS

5.3.2 List of details

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PC01	STA	<p>Acceleration time constant</p> <p>Used to set the acceleration time required to reach the rated speed from 0r/min in response to the analog speed command and internal speed commands 1 to 7.</p> <p>For example for the servo motor of 3000r/min rated speed, set 3000 (3s) to increase speed from 0r/min to 1000r/min in 1 second.</p>	0	ms	0 to 50000		<input type="radio"/>	<input type="radio"/>
PC02	STB	<p>Deceleration time constant</p> <p>Used to set the deceleration time required to reach 0r/min from the rated speed in response to the analog speed command and internal speed commands 1 to 7.</p>	0	ms	0 to 50000		<input type="radio"/>	<input type="radio"/>
PC03	STC	<p>S-pattern acceleration/deceleration time constant</p> <p>Used to smooth start/stop of the servo motor.</p> <p>Set the time of the arc part for S-pattern acceleration/deceleration.</p> <p>STA: Acceleration time constant (parameter No. PC01) STB: Deceleration time constant (parameter No. PC02) STC: S-pattern acceleration/deceleration time constant (parameter No. 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.</p> <p>The upper limit value of the actual arc part time is limited by $\frac{2000000}{STA}$ for acceleration or by $\frac{2000000}{STB}$ for deceleration.</p> <p>(Example) At the setting of STA=20000, STB=5000 and STC=200, the actual arc part times are as follows:</p> <p>During acceleration: 100[ms] $\left\{ \begin{array}{l} \text{Limited to 100[ms] since} \\ \frac{2000000}{20000} = 100[\text{ms}] < 200[\text{ms}]. \end{array} \right.$</p> <p>During deceleration: 200[ms] $\left\{ \begin{array}{l} 200[\text{ms}] \text{ as set since} \\ \frac{2000000}{5000} = 400[\text{ms}] > 200[\text{ms}]. \end{array} \right.$</p>	0	ms	0 to 1000		<input type="radio"/>	<input type="radio"/>

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PC04	TQC	<p>Torque command time constant</p> <p>Used to set the constant of a low pass filter in response to the torque command.</p>  <p>TQC: Torque command time constant</p>	0	ms	0 to 20000			○
PC05	SC1	Internal speed command 1 Used to set speed 1 of internal speed commands.	100	r/min	0 to instantaneous permissible speed		○	
		Internal speed limit 1 Used to set speed 1 of internal speed limits.						○
PC06	SC2	Internal speed command 2 Used to set speed 2 of internal speed commands.	500	r/min	0 to instantaneous permissible speed		○	
		Internal speed limit 2 Used to set speed 2 of internal speed limits.						○
PC07	SC3	Internal speed command 3 Used to set speed 3 of internal speed commands.	1000	r/min	0 to instantaneous permissible speed		○	
		Internal speed limit 3 Used to set speed 3 of internal speed limits.						○
PC08	SC4	Internal speed command 4 Used to set speed 4 of internal speed commands.	200	r/min	0 to instantaneous permissible speed		○	
		Internal speed limit 4 Used to set speed 4 of internal speed limits.						○
PC09	SC5	Internal speed command 5 Used to set speed 5 of internal speed commands.	300	r/min	0 to instantaneous permissible speed		○	
		Internal speed limit 5 Used to set speed 5 of internal speed limits.						○
PC10	SC6	Internal speed command 6 Used to set speed 6 of internal speed commands.	500	r/min	0 to instantaneous permissible speed		○	
		Internal speed limit 6 Used to set speed 6 of internal speed limits.						○

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																																				
						Position	Speed	Torque																																		
PC11	SC7	Internal speed command 7 Used to set speed 7 of internal speed commands.	800	r/min	0 to instantaneous permissible speed		○																																			
							○																																			
PC12	VCM	Analog speed command maximum speed Used to set the speed at the maximum input voltage (10V) of the analog speed command (VC). Set "0" to select the rated speed of the servo motor connected. The speed is as indicated below for motorless operation of test operation. <table><tr><td></td><td>MR-J3-10A to 70A</td></tr><tr><td>Speed</td><td>3000r/min</td></tr></table>		MR-J3-10A to 70A	Speed	3000r/min	0		0		○																															
			MR-J3-10A to 70A																																							
Speed	3000r/min																																									
				r/min	1 to 50000																																					
		Analog speed limit maximum speed Used to set the speed at the maximum input voltage (10V) of the analog speed limit (VLA). Set "0" to select the rated speed of the servo motor connected.	0		0			○																																		
			r/min	1 to 50000																																						
PC13	TLC	Analog torque command maximum output Used to set the output torque at the analog torque command voltage (TC = ±8V) of +8V on the assumption that the maximum torque is 100[%]. For example, set 50 to output (maximum torque × 50/100) at the TC of +8V.	100.0	%	0 to 1000.0			○																																		
PC14	MOD1	Analog monitor 1 output Used to selection the signal provided to the analog monitor 1 (MO1) output. (Refer to Section 5.3.3) <table><tr><td>0</td><td>0</td><td>0</td><td></td></tr></table> <div>└ Analog monitor 1 (MO1) output selection</div> <table><tr><th>Setting</th><th>Item</th></tr><tr><td>0</td><td>Servo motor speed (±8V/max. speed)</td></tr><tr><td>1</td><td>Torque (±8V/max. torque)</td></tr><tr><td>2</td><td>Servo motor speed (+8V/max. speed)</td></tr><tr><td>3</td><td>Torque (+8V/max. torque)</td></tr><tr><td>4</td><td>Current command (±8V/max. current command)</td></tr><tr><td>5</td><td>Command pulse frequency (±10V/1Mpps)</td></tr><tr><td>6</td><td>Droop pulses (±10V/100 pulses) (Note)</td></tr><tr><td>7</td><td>Droop pulses (±10V/1000 pulses) (Note)</td></tr><tr><td>8</td><td>Droop pulses (±10V/10000 pulses) (Note)</td></tr><tr><td>9</td><td>Droop pulses (±10V/100000 pulses) (Note)</td></tr><tr><td>A</td><td>Feedback position (±10V/1 Mpulses) (Note)</td></tr><tr><td>B</td><td>Feedback position (±10V/10 Mpulses) (Note)</td></tr><tr><td>C</td><td>Feedback position (±10V/100 Mpulses) (Note)</td></tr><tr><td>D</td><td>Bus voltage (±8V/400V)</td></tr></table> <div>Note. Encoder pulse unit.</div>	0	0	0		Setting	Item	0	Servo motor speed (±8V/max. speed)	1	Torque (±8V/max. torque)	2	Servo motor speed (+8V/max. speed)	3	Torque (+8V/max. torque)	4	Current command (±8V/max. current command)	5	Command pulse frequency (±10V/1Mpps)	6	Droop pulses (±10V/100 pulses) (Note)	7	Droop pulses (±10V/1000 pulses) (Note)	8	Droop pulses (±10V/10000 pulses) (Note)	9	Droop pulses (±10V/100000 pulses) (Note)	A	Feedback position (±10V/1 Mpulses) (Note)	B	Feedback position (±10V/10 Mpulses) (Note)	C	Feedback position (±10V/100 Mpulses) (Note)	D	Bus voltage (±8V/400V)	0000h		Refer to the Name and Function field.	○	○	○
0	0	0																																								
Setting	Item																																									
0	Servo motor speed (±8V/max. speed)																																									
1	Torque (±8V/max. torque)																																									
2	Servo motor speed (+8V/max. speed)																																									
3	Torque (+8V/max. torque)																																									
4	Current command (±8V/max. current command)																																									
5	Command pulse frequency (±10V/1Mpps)																																									
6	Droop pulses (±10V/100 pulses) (Note)																																									
7	Droop pulses (±10V/1000 pulses) (Note)																																									
8	Droop pulses (±10V/10000 pulses) (Note)																																									
9	Droop pulses (±10V/100000 pulses) (Note)																																									
A	Feedback position (±10V/1 Mpulses) (Note)																																									
B	Feedback position (±10V/10 Mpulses) (Note)																																									
C	Feedback position (±10V/100 Mpulses) (Note)																																									
D	Bus voltage (±8V/400V)																																									

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No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																																
						Position	Speed	Torque																														
PC15	MOD2	<div>Analog monitor 2 output Used to selection the signal provided to the analog monitor 2 (MO2) output. (Refer to Section 5.3.3)</div> <div><div><div>0</div><div>0</div><div>0</div><div></div></div><div>└ Analog monitor 2 (MO2) output selection</div><table><tr><th>Setting</th><th>Item</th></tr><tr><td>0</td><td>Servo motor speed (±8V/max. speed)</td></tr><tr><td>1</td><td>Torque (±8V/max. torque)</td></tr><tr><td>2</td><td>Servo motor speed (+8V/max. speed)</td></tr><tr><td>3</td><td>Torque (+8V/max. torque)</td></tr><tr><td>4</td><td>Current command (±8V/max. current command)</td></tr><tr><td>5</td><td>Command pulse frequency (±10V/1Mpps)</td></tr><tr><td>6</td><td>Droop pulses (±10V/100 pulses) (Note)</td></tr><tr><td>7</td><td>Droop pulses (±10V/1000 pulses) (Note)</td></tr><tr><td>8</td><td>Droop pulses (±10V/10000 pulses) (Note)</td></tr><tr><td>9</td><td>Droop pulses (±10V/100000 pulses) (Note)</td></tr><tr><td>A</td><td>Feedback position (±10V/1 Mpulses) (Note)</td></tr><tr><td>B</td><td>Feedback position (±10V/10 Mpulses) (Note)</td></tr><tr><td>C</td><td>Feedback position (±10V/100 Mpulses) (Note)</td></tr><tr><td>D</td><td>Bus voltage (±8V/400V)</td></tr></table><div>Note. Encoder pulse unit.</div></div>	Setting	Item	0	Servo motor speed (±8V/max. speed)	1	Torque (±8V/max. torque)	2	Servo motor speed (+8V/max. speed)	3	Torque (+8V/max. torque)	4	Current command (±8V/max. current command)	5	Command pulse frequency (±10V/1Mpps)	6	Droop pulses (±10V/100 pulses) (Note)	7	Droop pulses (±10V/1000 pulses) (Note)	8	Droop pulses (±10V/10000 pulses) (Note)	9	Droop pulses (±10V/100000 pulses) (Note)	A	Feedback position (±10V/1 Mpulses) (Note)	B	Feedback position (±10V/10 Mpulses) (Note)	C	Feedback position (±10V/100 Mpulses) (Note)	D	Bus voltage (±8V/400V)	0001h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
Setting	Item																																					
0	Servo motor speed (±8V/max. speed)																																					
1	Torque (±8V/max. torque)																																					
2	Servo motor speed (+8V/max. speed)																																					
3	Torque (+8V/max. torque)																																					
4	Current command (±8V/max. current command)																																					
5	Command pulse frequency (±10V/1Mpps)																																					
6	Droop pulses (±10V/100 pulses) (Note)																																					
7	Droop pulses (±10V/1000 pulses) (Note)																																					
8	Droop pulses (±10V/10000 pulses) (Note)																																					
9	Droop pulses (±10V/100000 pulses) (Note)																																					
A	Feedback position (±10V/1 Mpulses) (Note)																																					
B	Feedback position (±10V/10 Mpulses) (Note)																																					
C	Feedback position (±10V/100 Mpulses) (Note)																																					
D	Bus voltage (±8V/400V)																																					
PC16	MBR	<div>Electromagnetic brake sequence output Used to set the delay time (Tb) between electronic brake interlock (MBR) and the base drive circuit is shut-off.</div>	100	ms	0 to 1000	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>																														
PC17	ZSP	<div>Zero speed Used to set the output range of the zero speed (ZSP).</div>	50	r/min	0 to 10000	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>																														
PC18	*BPS	<div>Alarm history clear Used to clear the alarm history.</div> <div><div><div>0</div><div>0</div><div>0</div><div></div></div><div>└ Alarm history clear 0: Invalid 1: Valid When alarm history clear is made valid, the alarm history is cleared at next power-on. After the alarm history is cleared, the setting is automatically made invalid (reset to 0).</div></div>	0000h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>																														

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																	
						Position	Speed	Torque															
PC19	*ENRS	<div>Encoder output pulse selection</div> <div>Use to select the, encoder output pulse direction and encoder pulse output setting.</div> <div><div><div>0</div><div>0</div><div></div><div></div></div><div>Encoder pulse output phase changing Changes the phases of A, B-phase encoder pulses output .</div><table><tr><th rowspan="2">Set value</th><th colspan="2">Servo motor rotation direction</th></tr><tr><th>CCW</th><th>CW</th></tr><tr><td rowspan="2">0</td><td>A phase </td><td>A phase </td></tr><tr><td>B phase </td><td>B phase </td></tr><tr><td rowspan="2">1</td><td>A phase </td><td>A phase </td></tr><tr><td>B phase </td><td>B phase </td></tr></table><div>Encoder output pulse setting selection (refer to parameter No. PA15)</div><div>0: Output pulse designation</div><div>1: Division ratio setting</div><div>2: Ratio is automatically set to command pulse unit</div><div>Setting "2" makes the parameter No. PA15 (encoder output pulse) setting invalid.</div></div>	Set value	Servo motor rotation direction		CCW	CW	0	A phase	A phase	B phase	B phase	1	A phase	A phase	B phase	B phase	0000h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
Set value	Servo motor rotation direction																						
	CCW	CW																					
0	A phase	A phase																					
	B phase	B phase																					
1	A phase	A phase																					
	B phase	B phase																					
PC20	*SNO	<div>Station number setting</div> <div>Used to specify the station number for serial communication.</div> <div>Always set one station to one axis of servo amplifier. If one station number is set to two or more stations, normal communication cannot be made.</div>	0	station	0 to 31	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>															
PC21	*SOP	<div>Communication function selection</div> <div>Select the communication I/F and select the RS-422 communication conditions.</div> <div><div><div>0</div><div></div><div></div><div>0</div></div><div>RS-422 communication baudrate selection</div><div>0: 9600 [bps]</div><div>1: 19200 [bps]</div><div>2: 38400 [bps]</div><div>3: 57600 [bps]</div><div>4: 115200[bps]</div><div>RS-422 communication response delay time</div><div>0: Invalid</div><div>1: Valid, reply sent after delay time of 800 μs or more</div></div>	0000h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>															

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode															
						Position	Speed	Torque													
PC22	*COP1	<p>Function selection C-1</p> <p>Select the execution of automatic restart after instantaneous power failure.</p> <div><div><div>0</div><div>0</div></div><div><p>Restart after instantaneous power failure</p><p>If the power supply voltage has returned to normal after an undervoltage status caused by the reduction of the input power supply voltage in the speed control mode, the servo motor can be restarted by merely turning on the start signal without resetting the alarm.</p><p>0: Invalid (Undervoltage alarm (AL.10) occurs.)</p><p>1: Valid</p></div><div><p>Encoder cable communication system selection</p><p>0: Two-wire type</p><p>1: Four-wire type</p><p>The following encoder cables are of 4-wire type.</p><p>MR-EKCBL30M-L</p><p>MR-EKCBL30M-H</p><p>MR-EKCBL40M-H</p><p>MR-EKCBL50M-H</p><p>The other encoder cables are all of 2-wire type.</p><p>Incorrect setting will result in an encoder alarm 1 (AL. 16) or encoder alarm 2 (AL. 20).</p></div></div> <td>0000h</td> <td></td> <td>Refer to the Name and Function field.</td> <td></td> <td><div><div></div><div></div><div></div></div></td>	0000h		Refer to the Name and Function field.		<div><div></div><div></div><div></div></div>														
PC23	*COP2	<p>Function selection C-2</p> <p>Select the servo lock at speed control mode stop, the VC-VLA voltage averaging, and the speed limit in torque control mode.</p> <div><div><div></div><div></div><div>0</div></div><div><p>Selection of servo lock at speed control mode stop</p><p>0: Valid</p><p>1: Invalid</p></div><div><p>VC/VLA voltage averaging</p><p>Used to set the filtering time when the analog speed command (VC) voltage or analog speed limit (VLA) is imported.</p><p>Set 0 to vary the speed to voltage fluctuation in real time. Increase the set value to vary the speed slower to voltage fluctuation.</p><table><tr><th>Set value</th><th>Filtering time [ms]</th></tr><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></table></div><div><p>Selection of speed limit for torque control</p><p>0: Valid</p><p>1: Invalid</p><p>Do not use this function except when configuring a speed loop externally.</p><p>If the speed limit is invalid, the following parameters can be used.</p><p>Parameter No. PB01 (filter tuning mode)</p><p>Parameter No. PB13 (machine resonance suppression filter 1)</p><p>Parameter No. PB14 (notch shape selection 1)</p><p>Parameter No. PB15 (machine resonance suppression filter 2)</p><p>Parameter No. PB01 (notch shape selection 2)</p></div></div> <td>0000h</td> <td></td> <td>Refer to the Name and Function field.</td> <td></td> <td><div><div></div><div></div><div></div></div></td>	Set value	Filtering time [ms]	0	0	1	0.444	2	0.888	3	1.777	4	3.555	5	7.111	0000h		Refer to the Name and Function field.		<div><div></div><div></div><div></div></div>
Set value	Filtering time [ms]																				
0	0																				
1	0.444																				
2	0.888																				
3	1.777																				
4	3.555																				
5	7.111																				

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PC24	*COP3	Function selection C-3 Select the unit of the in-position range. <div style="border: 1px solid black; display: inline-block; padding: 2px; margin: 5px 0;">0 0 0</div> In-position range unit selection 0: Command input pulse unit 1: Servo motor encoder pulse unit	0000h		Refer to the Name and Function field.	○	○	○
PC25		For manufacturer setting Never change this setting.	0000h					
PC26	*COP5	Function selection C-5 Select the stroke limit warning (AL. 99). <div style="border: 1px solid black; display: inline-block; padding: 2px; margin: 5px 0;">0 0 0</div> Stroke limit warning (AL. 99) selection 0: Valid 1: Invalid When this parameter is set to "1", AL. 99 will not occur if the forward rotation stroke end (LSP) or reverse rotation stroke end (LSN) turns OFF.	0000h		Refer to the Name and Function field.	○	○	
PC27		For manufacturer setting	0000h					
PC28		Never change this setting.	0000h					
PC29			0000h					
PC30	STA2	Acceleration time constant 2 This parameter is made valid when the acceleration/deceleration selection (STAB2) is turned ON. Used to set the acceleration time required to reach the rated speed from Or/min in response to the analog speed command and internal speed commands 1 to 7.	0	ms	0 to 50000		○	○
PC31	STB2	Deceleration time constant 2 This parameter is made valid when the acceleration/deceleration selection (STAB2) is turned ON. Used to set the deceleration time required to reach Or/min from the rated speed in response to the analog speed command and internal speed commands 1 to 7.	0	ms	0 to 50000		○	○
PC32	CMX2	Command pulse multiplying factor numerator 2 Used to set the multiplier for the command pulse. Setting "0" automatically sets the connected motor resolution.	1		1 to 65535	○		
PC33	CMX3	Command pulse multiplying factor numerator 3 Used to set the multiplier for the command pulse. Setting "0" automatically sets the connected motor resolution.	1		1 to 65535	○		
PC34	CMX4	Command pulse multiplying factor numerator 4 Used to set the multiplier for the command pulse. Setting "0" automatically sets the connected motor resolution.	1		1 to 65535	○		
PC35	TL2	Internal torque limit 2 Set this parameter to limit servo motor torque on the assumption that the maximum torque is 100[%]. When 0 is set, torque is not produced. When torque is output in analog monitor output, this set value is the maximum output voltage (8V). (Refer to Section 3.6.1, (5))	100.0	%	0 to 100.0	○	○	○

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																
						Position	Speed	Torque														
PC36	*DMD	<div>Status display selection</div> <div>Select the status display to be provided at power-on.</div> <div><div><div>0</div><div></div><div></div><div></div></div><div><div>Selection of status display at power-on</div><div>0: Cumulative feedback pulse</div><div>1: Servo motor speed</div><div>2: Droop pulse</div><div>3: Cumulative command pulses</div><div>4: Command pulse frequency</div><div>5: Analog speed command voltage (Note 1)</div><div>6: Analog torque command voltage (Note 2)</div><div>7: Regenerative load ratio</div><div>8: Effective load ratio</div><div>9: Peak load ratio</div><div>A: Instantaneous torque</div><div>B: Within one-revolution position (1 pulse unit)</div><div>C: Within one-revolution position (100 pulse unit)</div><div>D: ABS counter</div><div>E: Load inertia moment ratio</div><div>F: Bus voltage</div></div><div>Note 1. In speed control mode. Analog speed limit voltage in torque control mode.</div><div>2. In torque control mode. Analog torque limit voltage in speed or position control mode.</div><div>Status display at power-on in corresponding control mode</div><div>0: Depends on the control mode.</div><table><tr><td>Control Mode</td><td>Status display at power-on</td></tr><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></table><div>1: Depends on the first digit setting of this parameter.</div></div>	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	0000h		Refer to the Name and Function field.	<div><div></div></div>	<div><div></div></div>	<div><div></div></div>
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																					
PC37	VCO	<div>Analog speed command offset</div> <div>Used to set the offset voltage of the analog speed command (VC). For example, if CCW rotation is provided by switching on forward rotation start (ST1) with 0V applied to VC, set a negative value. When automatic VC offset is used, the automatically offset value is set to this parameter. (Refer to Section6.4.)</div> <div>The initial value is the value provided by the automatic VC offset function before shipment at the VC-LG voltage of 0V.</div> <div>Analog speed limit offset</div> <div>Used to set the offset voltage of the analog speed limit (VLA). For example, if CCW rotation is provided by switching on forward rotation selection (RS1) with 0V applied to VLA, set a negative value. When automatic VC offset is used, the automatically offset value is set to this parameter. (Refer to Section6.4.)</div> <div>The initial value is the value provided by the automatic VC offset function before shipment at the VLA-LG voltage of 0V.</div>	Depen ding on servo amplifi er	mV	—999 to 999	<div><div></div></div>	<div><div></div></div>	<div><div></div></div>														

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PC38	TPO	Analog torque command offset Used to set the offset voltage of the analog torque command (TC).	0	mV	-999 to 999			○
		Analog torque limit offset Used to set the offset voltage of the analog torque limit (TLA).					○	
PC39	MO1	Analog monitor 1 offset Used to set the offset voltage of the analog monitor (MO1).	0	mV	-999 to 999	○	○	○
PC40	MO2	Analog monitor 2 offset Used to set the offset voltage of the analog monitor (MO2).	0	mV	-999 to 999	○	○	○
PC41		For manufacturer setting Never change this setting.	0					
PC42			0					
PC43			0					
PC44			0					
PC45			0					
PC46			0					
PC47			0					
PC48			0					
PC49			0					
PC50			0					

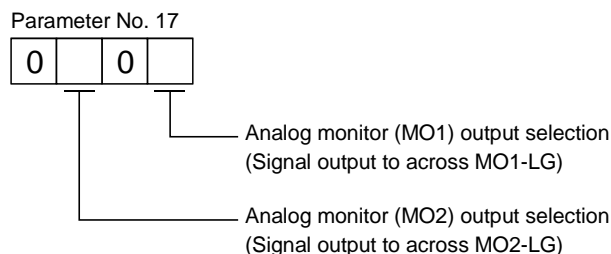
5. PARAMETERS

5.3.3 Analog monitor

The servo status can be output to two channels in terms of voltage. Use this function when using an ammeter to monitor the servo status or synchronizing the torque/speed with the other servo.

(1) Setting

Change the following digits of parameter No. PC14, PC15:



Parameters No. PC39 and PC40 can be used to set the offset voltages to the analog output voltages. The setting range is between -999 and 999mV .

Parameter No.	Description	Setting range [mV]
PC39	Used to set the offset voltage for the analog monitor 1 (MO1).	-999 to 999
PC40	Used to set the offset voltage for the analog monitor 2 (MO2).	

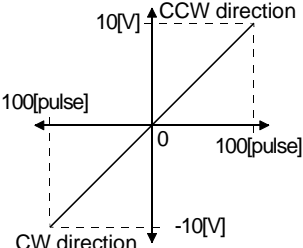
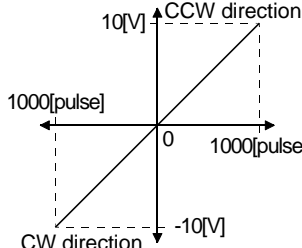
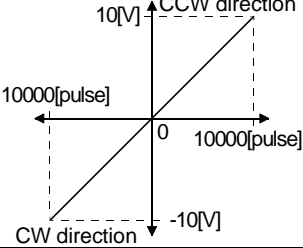
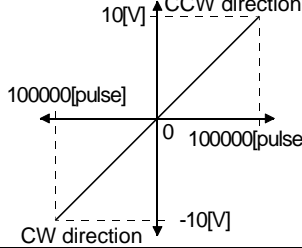
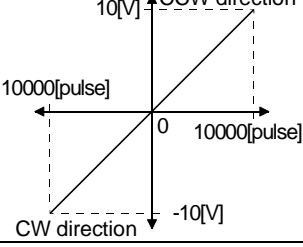
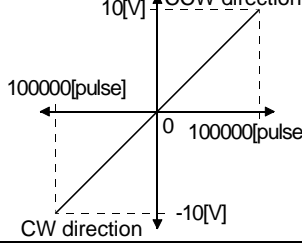
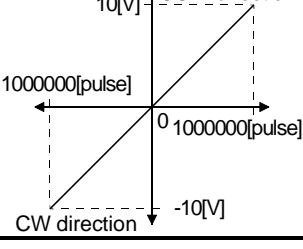
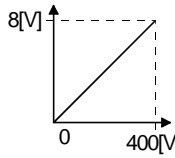
(2) Set content

The servo amplifier is factory-set to output the servo motor speed to analog monitor 1 (MO1) and the torque to analog monitor (MO2). The setting can be changed as listed below by changing the parameter No. PC14 and PC15 value:

Refer to (3) for the measurement point.

Setting	Output item	Description	Setting	Output item	Description
0	Servo motor speed		1	Torque	
2	Servo motor speed		3	Torque	
4	Current command		5	Command pulse frequency	

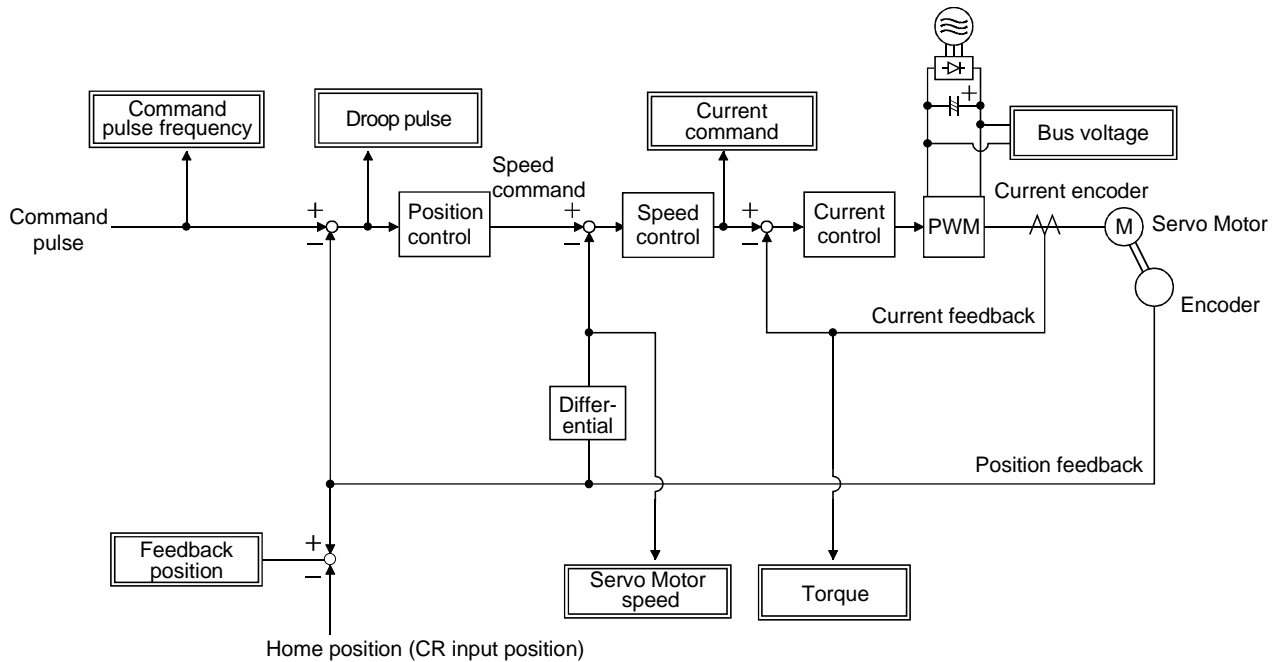
5. PARAMETERS

Setting	Output item	Description	Setting	Output item	Description
6	Droop pulses (Note) ($\pm 10\text{V}/100$ pulses)		7	Droop pulses (Note) ($\pm 10\text{V}/1000$ pulses)	
8	Droop pulses (Note) ($\pm 10\text{V}/10000$ pulses)		9	Droop pulses (Note) ($\pm 10\text{V}/100000$ pulses)	
A	Feedback position (Note) ($\pm 10\text{V}/1$ Mpulses)		B	Feedback position (Note) ($\pm 10\text{V}/10$ Mpulses)	
C	Feedback position (Note) ($\pm 10\text{V}/100$ Mpulses)		D	Bus voltage	

Note. Encoder pulse unit.

5. PARAMETERS

(3) Analog monitor block diagram



5.3.4 Alarm history clear

The servo amplifier stores one current alarm and five past alarms from when its power is switched on first. To control alarms which will occur during operation, clear the alarm history using parameter No. PC18 before starting operation.

Clearing the alarm history automatically returns to "□□□0".

After setting, this parameter is made valid by switch power from OFF to ON.

Parameter No. PC18

--	--	--	--

Alarm history clear
 0: Invalid (not cleared)
 1: Valid (cleared)

5. PARAMETERS

5.4 I/O Setting Parameters (No. PD□□)

POINT

- For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

5.4.1 Parameter list

No.	Symbol	Name	Initial Value	Unit	Control Mode		
					Position	Speed	Torque
PD01	*DIA1	Input signal automatic ON selection 1	0000h		○	○	○
PD02		For manufacturer setting	0000h				
PD03	*DI1	Input signal device selection 1 (CN1-15)	00020202h		○	○	○
PD04	*DI2	Input signal device selection 2 (CN1-16)	00212100h		○	○	○
PD05	*DI3	Input signal device selection 3 (CN1-17)	00070704h		○	○	○
PD06	*DI4	Input signal device selection 4 (CN1-18)	00080805h		○	○	○
PD07	*DI5	Input signal device selection 5 (CN1-19)	00030303h		○	○	○
PD08	*DI6	Input signal device selection 6 (CN1-41)	00202006h		○	○	○
PD09		For manufacturer setting	00000000h				
PD10	*DI8	Input signal device selection 8 (CN1-43)	00000A0Ah		○	○	○
PD11	*DI9	Input signal device selection 9 (CN1-44)	00000B0Bh		○	○	○
PD12	*DI10	Input signal device selection 10 (CN1-45)	00232323h		○	○	○
PD13	*DO1	Output signal device selection 1 (CN1-22)	0004h		○	○	○
PD14	*DO2	Output signal device selection 2 (CN1-23)	000Ch		○	○	○
PD15	*DO3	Output signal device selection 3 (CN1-24)	0004h		○	○	○
PD16	*DO4	Output signal device selection 4 (CN1-25)	0007h		○	○	○
PD17		For manufacturer setting	0003h				
PD18	*DO6	Output signal device selection 6 (CN1-49)	0002h		○	○	○
PD19	*DIF	Response level setting	0002h		○	○	○
PD20	*DOP1	Function selection D-1	0000h		○	○	○
PD21		For manufacturer setting	0000h				
PD22	*DOP3	Function selection D-2	0000h		○		
PD23		For manufacturer setting	0000h				
PD24	*DOP5	Function selection D-4	0000h		○	○	○
PD25		For manufacturer setting	0				
PD26			0				
PD27			0				
PD28			0				
PD29			0				
PD30			0				

5. PARAMETERS

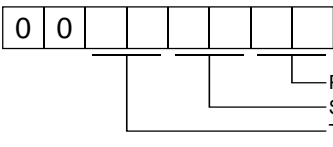
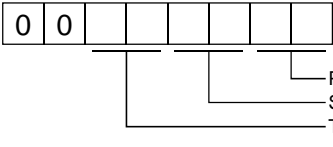
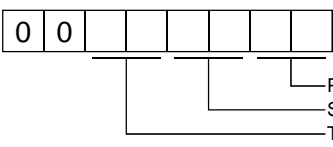
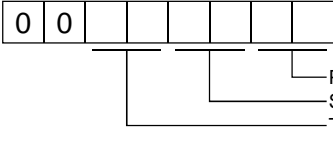
5.4.2 List of details

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																																															
						Position	Speed	Torque																																													
PD01	*DIA1	<div>Input signal automatic ON selection 1</div> <div>Select the input devices to be automatically turned ON.</div> <div><div><div>0</div><div></div><div></div><div></div></div><div><div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div></div></div><div><table><tr><th>Signal name</th><th colspan="2">Initial value</th></tr><tr><td></td><th>BIN</th><th>HEX</th></tr><tr><td></td><td>0</td><td rowspan="4">0</td></tr><tr><td></td><td>0</td></tr><tr><td>Servo-on (SON)</td><td>0</td></tr><tr><td></td><td>0</td></tr></table><table><tr><th>Signal name</th><th colspan="2">Initial value</th></tr><tr><td></td><th>BIN</th><th>HEX</th></tr><tr><td>Proportion control (PC)</td><td>0</td><td rowspan="4">0</td></tr><tr><td>External torque limit (TL)</td><td>0</td></tr><tr><td></td><td>0</td></tr><tr><td></td><td>0</td></tr></table><table><tr><th>Signal name</th><th colspan="2">Initial value</th></tr><tr><td></td><th>BIN</th><th>HEX</th></tr><tr><td></td><td>0</td><td rowspan="4">0</td></tr><tr><td></td><td>0</td></tr><tr><td>Forward rotation stroke end (LSP)</td><td>0</td></tr><tr><td>Reverse rotation stroke end (LSN)</td><td>0</td></tr></table><div>BIN 0: Used as external input signal BIN 1: Automatic ON</div><div>For example, to turn ON SON, the setting is "□□□4".</div></div></div>	Signal name	Initial value			BIN	HEX		0	0		0	Servo-on (SON)	0		0	Signal name	Initial value			BIN	HEX	Proportion control (PC)	0	0	External torque limit (TL)	0		0		0	Signal name	Initial value			BIN	HEX		0	0		0	Forward rotation stroke end (LSP)	0	Reverse rotation stroke end (LSN)	0	0000h		Refer to the Name and Function field.	○	○	○
Signal name	Initial value																																																				
	BIN	HEX																																																			
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Signal name	Initial value																																																				
	BIN	HEX																																																			
	0	0																																																			
	0																																																				
Forward rotation stroke end (LSP)	0																																																				
Reverse rotation stroke end (LSN)	0																																																				
PD02		<div>For manufacturer setting</div> <div>Never change this setting.</div>	0000h		Refer to the Name and Function field.																																																

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PD03	*DI1	<p>Input signal device selection 1 (CN1-15)</p> <p>Any input signal can be assigned to the CN1-15 pin.</p> <p>Note that the setting digits and the signal that can be assigned change depending on the control mode.</p> <div><div><div>0</div><div>0</div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div></div><div></div></div><div><div></div><div></div><div></div><div></div><div></div><div>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5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PD05	*DI3	<p>Input signal device selection 3 (CN1-17)</p> <p>Any input signal can be assigned to the CN1-17 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p>  <p>When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No. PA03, the CN1-17 pin is set to the ABS transfer mode (ABSM). (Refer to Section 14.5.)</p>	0007 0704h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PD06	*DI4	<p>Input signal device selection 4 (CN1-18)</p> <p>Any input signal can be assigned to the CN1-18 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p>  <p>When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No. PA03, the CN1-18 pin is set to the ABS transfer request (ABSR). (Refer to Section 14.5.)</p>	0008 0805h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PD07	*DI5	<p>Input signal device selection 5 (CN1-19)</p> <p>Any input signal can be assigned to the CN1-19 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p> 	0003 0303h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PD08	*DI6	<p>Input signal device selection 6 (CN1-41)</p> <p>Any input signal can be assigned to the CN1-41 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p> 	0020 2006h		Refer to the Name and Function field.	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
PD09		<p>For manufacturer setting</p> <p>Never change this setting.</p>	0000 0000h					

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PD10	*DI8	<p>Input signal device selection 8 (CN1-43)</p> <p>Any input signal can be assigned to the CN1-43 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p> <div style="display: flex; align-items: center;"> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px;"></div> </div> <div style="margin-left: 100px;"> <p>Position control mode</p> <p>Speed control mode</p> <p>Torque control mode</p> </div> <div style="margin-left: 150px;"> <p>Select the input device of the CN1-43 pin.</p> </div>	0000 0A0Ah		Refer to the Name and Function field.	○	○	○
PD11	*DI9	<p>Input signal device selection 9 (CN1-44)</p> <p>Any input signal can be assigned to the CN1-44 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p> <div style="display: flex; align-items: center;"> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px;"></div> </div> <div style="margin-left: 100px;"> <p>Position control mode</p> <p>Speed control mode</p> <p>Torque control mode</p> </div> <div style="margin-left: 150px;"> <p>Select the input device of the CN1-44 pin.</p> </div>	0000 0B0Bh		Refer to the Name and Function field.	○	○	○
PD12	*DI10	<p>Input signal device selection 10 (CN1-45)</p> <p>Any input signal can be assigned to the CN1-45 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD03.</p> <div style="display: flex; align-items: center;"> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;">0</div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px; margin-right: 5px;"></div> <div style="border: 1px solid black; padding: 2px;"></div> </div> <div style="margin-left: 100px;"> <p>Position control mode</p> <p>Speed control mode</p> <p>Torque control mode</p> </div> <div style="margin-left: 150px;"> <p>Select the input device of the CN1-45 pin.</p> </div>	0023 2323h		Refer to the Name and Function field.	○	○	○

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																																																																																					
						Position	Speed	Torque																																																																																			
PD13	*DO1	<p>Output signal device selection 1 (CN1-22)</p> <p>Any output signal can be assigned to the CN1-22 pin.</p> <p>Note that the device that can be assigned changes depending on the control mode.</p> <div><div>000</div><div></div><p>Select the output device of the CN1-22 pin.</p></div> <p>The devices that can be assigned in each control mode are those that have the symbols indicated in the following table. If any other device is set, it is invalid.</p> <table><tr><th rowspan="2">Setting</th><th colspan="3">Control Modes (Note 1)</th></tr><tr><th>P</th><th>S</th><th>T</th></tr><tr><td>00</td><td>Always OFF</td><td>Always OFF</td><td>Always OFF</td></tr><tr><td>01</td><td colspan="3">For manufacturer setting (Note 2)</td></tr><tr><td>02</td><td>RD</td><td>RD</td><td>RD</td></tr><tr><td>03</td><td>ALM</td><td>ALM</td><td>ALM</td></tr><tr><td>04</td><td>INP</td><td>SA</td><td>Always OFF</td></tr><tr><td>05</td><td>MBR</td><td>MBR</td><td>MBR</td></tr><tr><td>06</td><td colspan="3">For manufacturer setting (Note 2)</td></tr><tr><td>07</td><td>TLC</td><td>TLC</td><td>VLC</td></tr><tr><td>08</td><td>WNG</td><td>WNG</td><td>WNG</td></tr><tr><td>09</td><td>BWNG</td><td>Always OFF</td><td>Always OFF</td></tr><tr><td>0A</td><td>Always OFF</td><td>SA</td><td>SA</td></tr><tr><td>0B</td><td>Always OFF</td><td>Always OFF</td><td>VLC</td></tr><tr><td>0C</td><td>ZSP</td><td>ZSP</td><td>ZSP</td></tr><tr><td>0D</td><td colspan="3">For manufacturer setting (Note 2)</td></tr><tr><td>0E</td><td colspan="3">For manufacturer setting (Note 2)</td></tr><tr><td>0F</td><td>CHGS</td><td>Always OFF</td><td>Always OFF</td></tr><tr><td>10</td><td colspan="3">For manufacturer setting (Note 2)</td></tr><tr><td>11</td><td>ABSV</td><td>Always OFF</td><td>Always OFF</td></tr><tr><td>12 to 3F</td><td colspan="3">For manufacturer setting (Note 2)</td></tr></table> <p>Note 1. P: Position control mode S: Speed control mode T: Torque control mode</p> <p>2. For manufacturer setting. Never set this value.</p> <p>When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No. PA03, the CN1-22 pin is set to the ABS transmission data bit 0 (ABSB0) in the ABS transfer mode only. (Refer to Section 14.5.)</p>	Setting	Control Modes (Note 1)			P	S	T	00	Always OFF	Always OFF	Always OFF	01	For manufacturer setting (Note 2)			02	RD	RD	RD	03	ALM	ALM	ALM	04	INP	SA	Always OFF	05	MBR	MBR	MBR	06	For manufacturer setting (Note 2)			07	TLC	TLC	VLC	08	WNG	WNG	WNG	09	BWNG	Always OFF	Always OFF	0A	Always OFF	SA	SA	0B	Always OFF	Always OFF	VLC	0C	ZSP	ZSP	ZSP	0D	For manufacturer setting (Note 2)			0E	For manufacturer setting (Note 2)			0F	CHGS	Always OFF	Always OFF	10	For manufacturer setting (Note 2)			11	ABSV	Always OFF	Always OFF	12 to 3F	For manufacturer setting (Note 2)			0004h		Refer to the Name and Function field.	○	○	○
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10	For manufacturer setting (Note 2)																																																																																										
11	ABSV	Always OFF	Always OFF																																																																																								
12 to 3F	For manufacturer setting (Note 2)																																																																																										
PD14	*DO2	<p>Output signal device selection 2 (CN1-23)</p> <p>Any output signal can be assigned to the CN1-23 pin.</p> <p>The devices that can be assigned and the setting method are the same as in parameter No. PD13.</p> <div><div>000</div><div></div><p>Select the output device of the CN1-23 pin.</p></div> <p>When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No. PA03, the CN1-23 pin is set to the ABS transmission data bit 1 (ABSB1) in the ABS transfer mode only. (Refer to Section 14.5.)</p>	000Ch		Refer to the Name and Function field.	○	○	○																																																																																			

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PD15	*DO3	Output signal device selection 3 (CN1-24) Any output signal can be assigned to the CN1-24 pin. The devices that can be assigned and the setting method are the same as in parameter No. PD13. <div> <div>000</div> <div>□</div> </div> Select the output device of the CN1-24 pin.	0004h		Refer to the Name and Function field.	○	○	○
PD16	*DO4	Output signal device selection 4 (CN1-25) Any output signal can be assigned to the CN1-25 pin. The devices that can be assigned and the setting method are the same as in parameter No. PD13. <div> <div>000</div> <div>□</div> </div> Select the output device of the CN1-25 pin. When "Valid (ABS transfer by DI0)" has been selected for the absolute position detection system in parameter No. PA03, the CN1-25 pin is set to the ABS transmission data ready (ABST) in the ABS transfer mode only. (Refer to Section 14.5.)	0007h		Refer to the Name and Function field.	○	○	○
PD17		For manufacturer setting Never change this setting.	0003h					
PD18	*DO6	Output signal device selection 6 (CN1-49) Any output signal can be assigned to the CN1-49 pin. The devices that can be assigned and the setting method are the same as in parameter No. PD13. <div> <div>000</div> <div>□</div> </div> Select the output device of the CN1-49 pin.	0002h		Refer to the Name and Function field.	○	○	○
PD19	*DIF	Input filter setting Select the input filter. <div> <div>000</div> <div>□</div> </div> Input signal filter If external input signal causes chattering due to noise, etc., input filter is used to suppress it. 0: None 1: 1.777[ms] 2: 3.555[ms] 3: 5.333[ms]	0002h		Refer to the Name and Function field.	○	○	○

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PD20	*DOP1	<p>Function selection D-1</p> <p>Select the stop processing at forward rotation stroke end (LSP)/reverse rotation stroke end (LSN) OFF and the base circuit status at reset (RES) ON.</p> <div style="display: flex; align-items: center;"> <div style="border: 1px solid black; padding: 2px; margin-right: 10px;">0 0</div> <div> <p>How to make a stop when forward rotation stroke end (LSP) • reverse rotation stroke end (LSN) is valid. (Refer to Section 5.4.2.)</p> <p>0: Sudden stop 1: Slow stop</p> <p>Selection of base circuit status at reset (RES) ON</p> <p>0: Base circuit not switched off 1: Base circuit switched off</p> </div> </div>	0000h		Refer to the Name and Function field.			
PD21		For manufacturer setting Never change this setting.	0000h					
PD22	*DOP3	<p>Function selection D-3</p> <p>Set the clear (CR).</p> <div style="display: flex; align-items: center;"> <div style="border: 1px solid black; padding: 2px; margin-right: 10px;">0 0 0</div> <div> <p>Clear (CR) selection</p> <p>0: Droop pulses are cleared on the leading edge. 1: While on, droop pulses are always cleared.</p> </div> </div>	0000h		Refer to the Name and Function field.	○		
PD23		For manufacturer setting Never change this setting.	0000h					

5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode																																																																																																								
						Position	Speed	Torque																																																																																																						
PD24	*DOP5	<div>Function selection D-5</div> <div>Select the alarm code and warning (WNG) outputs.</div> <div><div><div>0</div><div>0</div><div></div><div></div></div><div>Setting of alarm code output</div><table><tr><th rowspan="2">Set value</th><th colspan="3">Connector pins of CN1</th></tr><tr><th>22</th><th>23</th><th>24</th></tr><tr><td>0</td><td colspan="3">Alarm code is not output.</td></tr><tr><td>1</td><td colspan="3">Alarm code is output at alarm occurrence.</td></tr></table><div><div>(Note) Alarm code</div><table><tr><th>CN1 pin 22</th><th>CN1 pin 23</th><th>CN1 pin 24</th><th>Alarm display</th><th>Name</th></tr><tr><td rowspan="9">0</td><td rowspan="9">0</td><td rowspan="9">0</td><td>88888</td><td>Watchdog</td></tr><tr><td>AL.12</td><td>Memory error 1</td></tr><tr><td>AL.13</td><td>Clock error</td></tr><tr><td>AL.15</td><td>Memory error 2</td></tr><tr><td>AL.17</td><td>Board error 2</td></tr><tr><td>AL.19</td><td>Memory error 3</td></tr><tr><td>AL.37</td><td>Parameter error</td></tr><tr><td>AL.8A</td><td>Serial communication time-out error</td></tr><tr><td>AL.8E</td><td>Serial communication error</td></tr><tr><td rowspan="2">0</td><td rowspan="2">0</td><td>1</td><td>AL.30</td><td>Regenerative error</td></tr><tr><td>1</td><td>AL.33</td><td>Overvoltage</td></tr><tr><td rowspan="1">0</td><td rowspan="1">1</td><td rowspan="1">0</td><td>AL.10</td><td>Undervoltage</td></tr><tr><td rowspan="5">0</td><td rowspan="5">1</td><td rowspan="5">1</td><td>AL.45</td><td>Main circuit device overheat</td></tr><tr><td>AL.46</td><td>Servo motor overheat</td></tr><tr><td>AL.47</td><td>Cooling fan alarm</td></tr><tr><td>AL.50</td><td>Overload 1</td></tr><tr><td>AL.51</td><td>Overload 2</td></tr><tr><td rowspan="2">1</td><td rowspan="2">0</td><td rowspan="2">0</td><td>AL.24</td><td>Main circuit</td></tr><tr><td>AL.32</td><td>Overcurrent</td></tr><tr><td rowspan="3">1</td><td rowspan="3">0</td><td rowspan="3">1</td><td>AL.31</td><td>Overspeed</td></tr><tr><td>AL.35</td><td>Command pulse frequency error</td></tr><tr><td>AL.52</td><td>Error excessive</td></tr><tr><td rowspan="4">1</td><td rowspan="4">1</td><td rowspan="4">0</td><td>AL.16</td><td>Encoder error 1</td></tr><tr><td>AL.1A</td><td>Motor combination error</td></tr><tr><td>AL.20</td><td>Encoder error 2</td></tr><tr><td>AL.25</td><td>Absolute position erase</td></tr></table></div><div>Note. 0: off 1: on</div><div>A parameter alarm (AL. 37) occurs if the alarm code output is selected with parameter No. PA03 set to "□□□1" and the DI0-based absolute value detection system selected.</div><div>Selection of output device at warning occurrence</div><div>Select the warning (WNG) and trouble (ALM) output status at warning occurrence.</div><div><table><tr><th>Setting</th><th>(Note) Device status</th></tr><tr><td rowspan="4">0</td><td>WNG 1 0 ALM 1 0</td></tr><tr><td><div>Warning occurrence</div></td></tr><tr><td>WNG 1 0 ALM 1 0</td></tr><tr><td><div>Warning occurrence</div></td></tr></table></div><div>Note. 0: off 1: on</div></div>	Set value	Connector pins of CN1			22	23	24	0	Alarm code is not output.			1	Alarm code is output at alarm occurrence.			CN1 pin 22	CN1 pin 23	CN1 pin 24	Alarm display	Name	0	0	0	88888	Watchdog	AL.12	Memory error 1	AL.13	Clock error	AL.15	Memory error 2	AL.17	Board error 2	AL.19	Memory error 3	AL.37	Parameter error	AL.8A	Serial communication time-out error	AL.8E	Serial communication error	0	0	1	AL.30	Regenerative error	1	AL.33	Overvoltage	0	1	0	AL.10	Undervoltage	0	1	1	AL.45	Main circuit device overheat	AL.46	Servo motor overheat	AL.47	Cooling fan alarm	AL.50	Overload 1	AL.51	Overload 2	1	0	0	AL.24	Main circuit	AL.32	Overcurrent	1	0	1	AL.31	Overspeed	AL.35	Command pulse frequency error	AL.52	Error excessive	1	1	0	AL.16	Encoder error 1	AL.1A	Motor combination error	AL.20	Encoder error 2	AL.25	Absolute position erase	Setting	(Note) Device status	0	WNG 1 0 ALM 1 0	<div>Warning occurrence</div>	WNG 1 0 ALM 1 0	<div>Warning occurrence</div>	0000h				○	○	○
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0	1	0	AL.10	Undervoltage																																																																																																										
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1	0	1	AL.31	Overspeed																																																																																																										
			AL.35	Command pulse frequency error																																																																																																										
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			AL.1A	Motor combination error																																																																																																										
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5. PARAMETERS

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range	Control Mode		
						Position	Speed	Torque
PD25		For manufacturer setting	0					
PD26		Never change this setting.	0					
PD27			0					
PD28			0					
PD29			0					
PD30			0					

5.4.3 Using forward/reverse rotation stroke end to change the stopping pattern

The stopping pattern is factory-set to make a sudden stop when the forward/reverse rotation stroke end is made valid. A slow stop can be made by changing the parameter No. PD20 value.

Parameter No. PD20 Setting	Stopping method
<div>□□□0</div> <div>(initial value)</div>	Sudden stop Position control mode : Motor stops with droop pulses cleared. Speed control mode : Motor stops at deceleration time constant of zero.
<div>□□□1</div>	Slow stop Position control mode : The motor is decelerated to a stop in accordance with the parameter No. PB03 value. Speed control mode : The motor is decelerated to a stop in accordance with the parameter No. PC02 value.

[illegible]

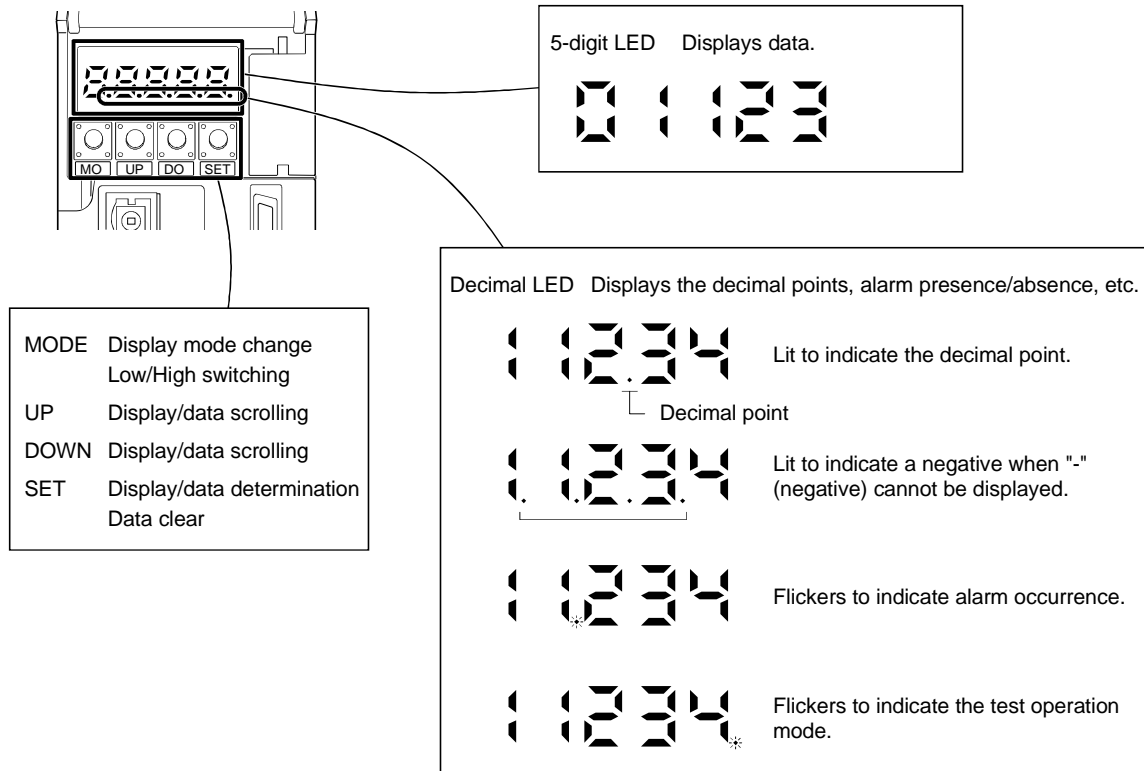
6. DISPLAY AND OPERATION SECTIONS

6. DISPLAY AND OPERATION SECTIONS

6.1 Overview

The MR-J3-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.

The operation section and display data are described below.



6. DISPLAY AND OPERATION SECTIONS

6.2 Display Sequence

Press the "MODE" button once to shift to the next display mode. Refer to Section 6.3 and later for the description of the corresponding display mode.

To refer to or set the gain filter parameters, extension setting parameters and I/O setting parameters, make them valid with parameter No. PA19 (parameter write disable).

Display mode transition	Initial screen	Function	Reference
<pre> graph TD A([Status display]) --> B([Diagnosis]) B --> C([Alarm]) C --> D([Basic setting parameters]) D --> E([Gain/filter parameters]) E --> F([Extension setting parameters]) F --> G([I/O setting parameters]) G -- button MODE --> A </pre>		Servo status display. [C] appears at power-on. (Note)	Section 6.3
		Sequence display, external signal display, output signal (DO), forced output, test operation, software version display, VC automatic offset, motor series ID display, motor type ID display, motor encoder ID display, external encoder ID display, parameter block, next deactivation display.	Section 6.4
		Current alarm display, alarm history display, parameter error No. display, point table error No. display.	Section 6.5
		Display and setting of basic setting parameters.	Section 6.6
		Display and setting of gain filter parameters.	
		Display and setting of extension setting parameters.	
		Display and setting of I/O setting parameters.	

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

6. DISPLAY AND OPERATION SECTIONS

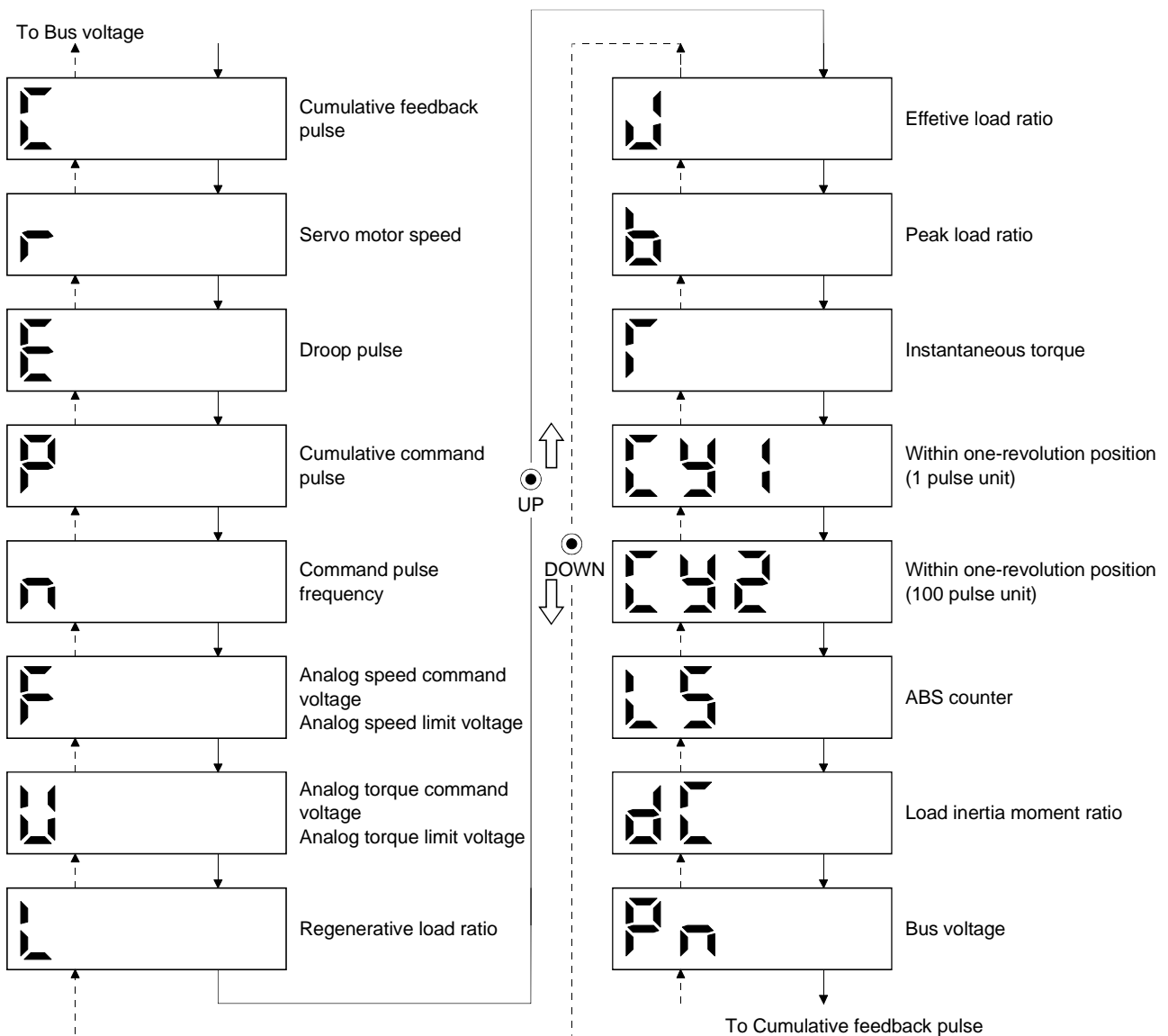
6.3 Status display

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 appears. Press the "SET" button to display its data. At only power-on, however, data appears after the symbol of the status display selected in parameter No. PC36 has been shown for 2[s].

The servo amplifier display shows the lower five digits of 16 data items such as the motor speed.

6.3.1 Display transition



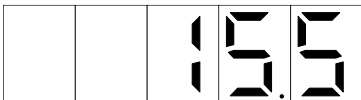

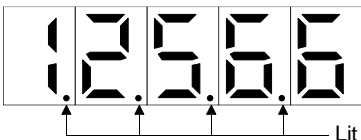
After choosing the status display mode with the "MODE" button, pressing the "UP" or "DOWN" button changes the display as shown below.



6. DISPLAY AND OPERATION SECTIONS

6.3.2 Display examples

The following table lists display examples:

Item	Status	Displayed data
		Servo amplifier display
Servo motor speed	Forward rotation at 3000r/min	
	Reverse rotation at 3000r/min	 Reverse rotation is indicated by "-".
Load inertia moment	15.5 times	
Multi-revolution counter	11252pulse	
	-12566pulse	 Negative value is indicated by the lit decimal points in the upper four digits.

6. DISPLAY AND OPERATION SECTIONS

6.3.3 Status display list

The following table lists the servo statuses that may be shown:
Refer to Appendix 2 for the measurement point.

Name	Symbol	Unit	Description	Display range
Cumulative feedback pulses	C	pulse	Feedback pulses from the servo motor encoder are counted and displayed. The value in excess of ± 99999 is counted, but since the servo amplifier display is five digits, it shows the lower five digits of the actual value. 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.	—99999 to 99999
Servo motor speed	r	r/min	The servo motor speed is displayed. The value rounded off is displayed in $\times 0.1$ r/min.	—7200 to 7200
Droop pulses	E	pulse	The number of droop pulses in the deviation counter is displayed. When the servo motor is rotating in the reverse direction, the decimal points in the upper four digits are lit. The value in excess of ± 99999 is counted. Since the servo amplifier display is five digits, it shows the lower five digits of the actual value. The number of pulses displayed is in the encoder pulse unit.	—99999 to 99999
Cumulative command pulses	P	pulse	The 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 value in excess of ± 99999 is counted, but since the servo amplifier display is five digits, it shows the lower five digits of the actual value. 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.	—99999 to 99999
Command pulse frequency	n	kpps	The frequency of the position command input pulses is displayed. The value displayed is not multiplied by the electronic gear (CMX/CDV).	—1500 to 1500
Analog speed command voltage Analog speed limit voltage	F	V	(1) Torque control mode Analog speed limit (VLA) voltage is displayed.	—10.00 to 10.00
			(2) Speed control mode Analog speed command (VC) voltage is displayed.	
Analog torque command voltage Analog torque limit voltage	U	V	(1) Position control mode, speed control mode Analog torque limit (TLA) voltage is displayed.	0 to 10.00
			(2) Torque control mode Analog torque command (TLA) voltage is displayed.	
Regenerative load ratio	L	%	The ratio of regenerative power to permissible regenerative power is displayed in %.	0 to 100
Effective load ratio	J	%	The continuous effective load current is displayed. The effective value in the past 15 seconds is displayed relative to the rated current of 100%.	0 to 300
Peak load ratio	b	%	The maximum torque generated during acceleration/deceleration, etc. The highest value in the past 15 seconds is displayed relative to the rated torque of 100%.	0 to 400
Instantaneous torque	T	%	Torque that occurred instantaneously is displayed. The value of the torque that occurred is displayed in real time relative to the rated torque of 100%.	0 to 400
Within one-revolution position low	Cy1	pulse	Position within one revolution is displayed in encoder pulses. The value returns to 0 when it exceeds the maximum number of pulses. The value is incremented in the CCW direction of rotation.	0 to 99999

6. DISPLAY AND OPERATION SECTIONS

Name	Symbol	Unit	Description	Display range
Within one-revolution position high	Cy2	100 pulse	The within one-revolution position is displayed in 100 pulse increments of the encoder. The value returns to 0 when it exceeds the maximum number of pulses. The value is incremented in the CCW direction of rotation.	0 to 2621
ABS counter	LS	rev	Travel value from the home position in the absolute position detection systems is displayed in terms of the absolute position detectors counter value.	−32768 to 32767
Load inertia moment ratio	dC	0.1 Times	The estimated ratio of the load inertia moment to the servo motor shaft inertia moment is displayed.	0.0 to 300.0
Bus voltage	Pn	V	The voltage (across P-N) of the main circuit converter is displayed.	0 to 450

6.3.4 Changing the status display screen

The status display item of the servo amplifier display shown at power-on can be changed by changing the parameter No. PC36 settings.

The item displayed in the initial status changes with the control mode as follows:






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

6. DISPLAY AND OPERATION SECTIONS

6.4 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.
External I/O signal display		Refer to section 6.7.	Indicates the ON-OFF states of the external I/O signals. The upper segments correspond to the input signals and the lower segments to the output signals. Lit: ON Extinguished: OFF
Output signal (DO) forced output			The digital output signal can be forced on/off. For more information, refer to section 6.8.
Test operation mode	Jog feed		Jog operation can be performed when there is no command from the external command device. For details, refer to section 6.9.2.
	Positioning operation		The MR configurator (Servo configuration software MRZJW3-SETUP211E) is required for positioning operation. This operation cannot be performed from the operation section of the servo amplifier. Positioning operation can be performed once when there is no command from the external command device. For details, refer to section 6.9.3.
	Motorless operation		Without connection of the servo motor, the servo amplifier provides output signals and displays the status as if the servo motor is running actually in response to the external input signal. For details, refer to section 6.9.4.
	Machine analyzer operation		Merely connecting the servo amplifier allows the resonance point of the mechanical system to be measured. The MR configurator (Servo configuration software MRZJW3-SETUP211E or later) is required for machine analyzer operation.
	Amplifier diagnosis		Simple diagnosis as to correct function of the input/output interface of the servo amplifier can be made. To diagnose the amplifier, the diagnosis cable (MR-J3ACHECK) and MR Configurator (Servo configuration software) MRZJW3-SETUP211 are necessary. For details, refer to section 12.4.
Software version low			Indicates the version of the software.
Software version high			Indicates the system number of the software.
Automatic VC offset			If offset voltages in the analog circuits inside and outside the servo amplifier cause the servo motor to rotate slowly at the analog speed command (VC) or analog speed limit (VLA) of 0V, this function automatically makes zero-adjustment of offset voltages. When using this function, make it valid in the following procedure. Making it valid causes the parameter No. PC37 value to be the automatically adjusted offset voltage. 1) Press "SET" once. 2) Set the number in the first digit to 1 with "UP"/"DOWN". 3) Press "SET". You cannot use this function if the input voltage of VC or VLA is $\pm 0.4V$ or more.






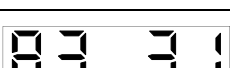
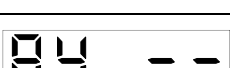
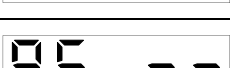
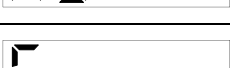
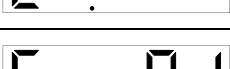
6. DISPLAY AND OPERATION SECTIONS

Name	Display	Description
Motor series		Press the "SET" button to show the motor series ID of the servo motor currently connected. For indication details, refer to the optional MELSERVO Servo Motor Instruction Manual.
Motor type		Press the "SET" button to show the motor type ID of the servo motor currently connected. For indication details, refer to the optional MELSERVO Servo Motor Instruction Manual.
Encoder		Press the "SET" button to show the encoder ID of the servo motor currently connected. For indication details, refer to the optional MELSERVO Servo Motor Instruction Manual.
For manufacturer setting		For manufacturer setting
For manufacturer setting		For manufacturer setting

6. DISPLAY AND OPERATION SECTIONS

6.5 Alarm mode

The current alarm, past alarm history and parameter error are displayed. The lower 2 digits on the display indicate the alarm number that has occurred or the parameter number in error. Display examples are shown below.

Name	Display	Description
Current alarm		Indicates no occurrence of an alarm.
		Indicates the occurrence of overvoltage (AL.33). Flickers at occurrence of the alarm.
Alarm history		Indicates that the last alarm is overload 1 (AL.50).
		Indicates that the second alarm in the past is overvoltage (AL.33).
		Indicates that the third alarm in the past is undervoltage (AL.10).
		Indicates that the fourth alarm in the past is overspeed (AL.31).
		Indicates that there is no fifth alarm in the past.
		Indicates that there is no sixth alarm in the past.
Parameter error No.		Indicates no occurrence of parameter error (AL.37).
		Indicates that the data of parameter No. PA12 is faulty.

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 (for clearable alarms, refer to Section 9.2.1):
 - (a) Switch power OFF, then ON.
 - (b) Press the "SET" button on the current alarm screen.
 - (c) Turn on the alarm reset (RES).
- (4) Use parameter No. PC18 to clear the alarm history.
- (5) Pressing "SET" on the alarm history display screen for 2s or longer shows the following detailed information display screen. Note that this is provided for maintenance by the manufacturer.



- (6) Press "UP" or "DOWN" to move to the next history.

6. DISPLAY AND OPERATION SECTIONS

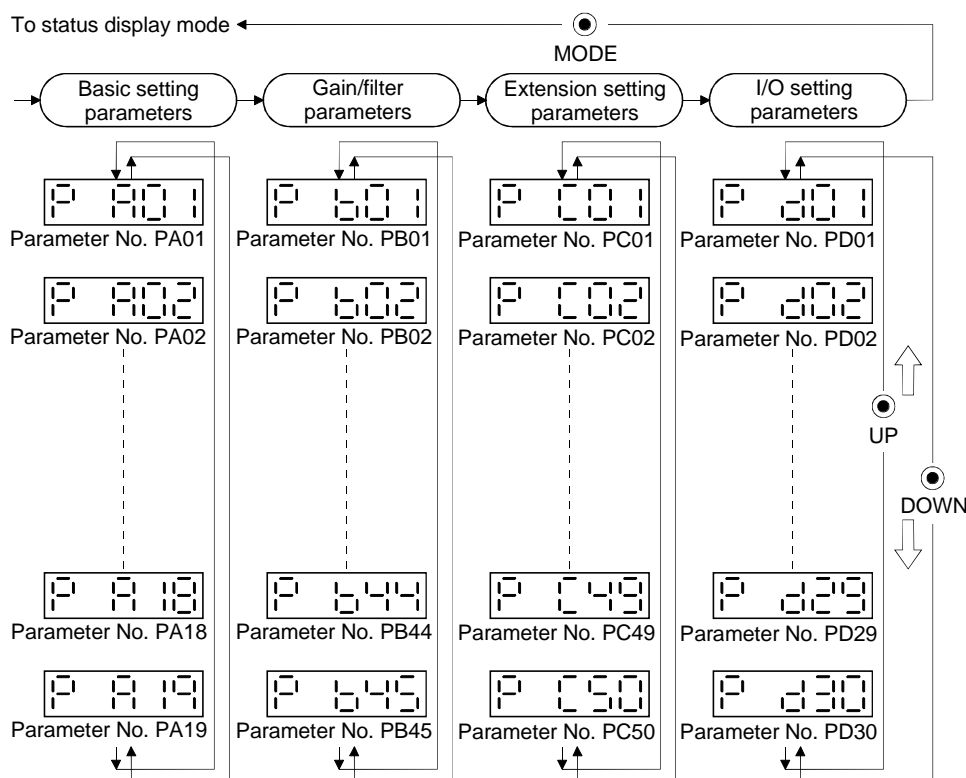
6.6 Parameter mode

POINT

- To use the I/O setting parameters, change the parameter No. PA19 (parameter block) value. (Refer to Section 5.1.1)
- The I/O signal settings can be changed using the I/O setting parameter No. PD03 to PD08, PD10 to PD18.

6.6.1 Parameter mode transition

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

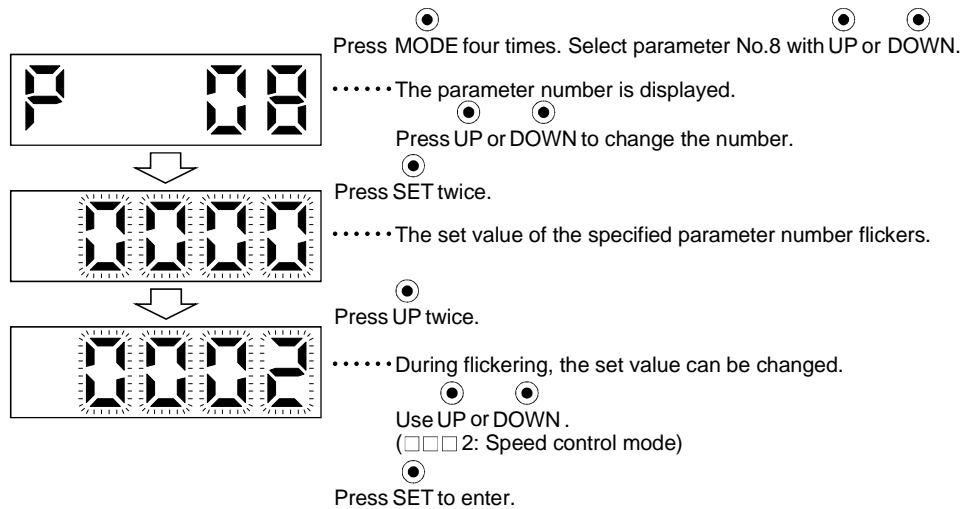


6. DISPLAY AND OPERATION SECTIONS

6.6.2 Operation example

(1) Parameter of 5 or less digits

The following example shows the operation procedure performed after power-on to change the control mode (Parameter No. PA01) into the speed control mode. Press "MODE" to switch to the basic setting parameter screen.



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

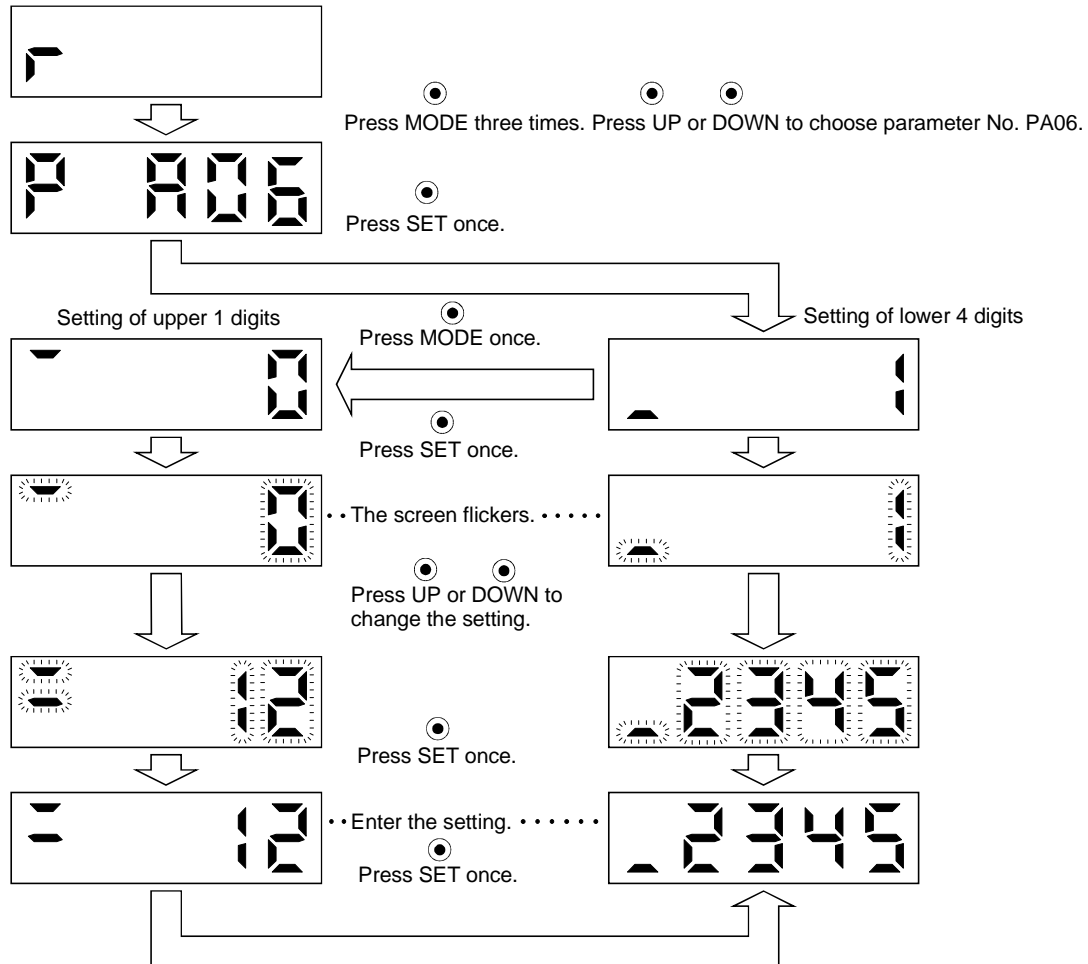
When changing the parameter No. PA01 setting, change its set value, then switch power off once and switch it on again to make the new value valid.

6. DISPLAY AND OPERATION SECTIONS

(2) Signed 6-digit or more parameter

The following example gives the operation procedure to change the electronic gear numerator (parameter No. PA06) to "123456".

(Note)



Note. The example assumes that the status display screen that appears at power-on has been set to the servo motor speed in parameter No. PC36.

6. DISPLAY AND OPERATION SECTIONS

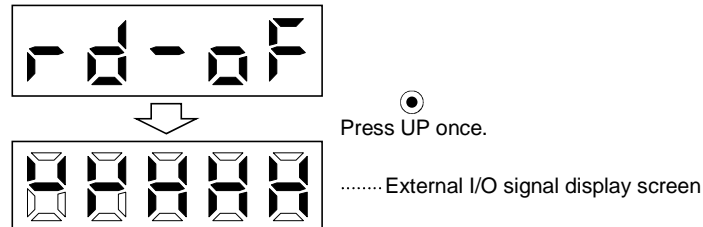
6.7 External I/O signal display

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

(1) Operation

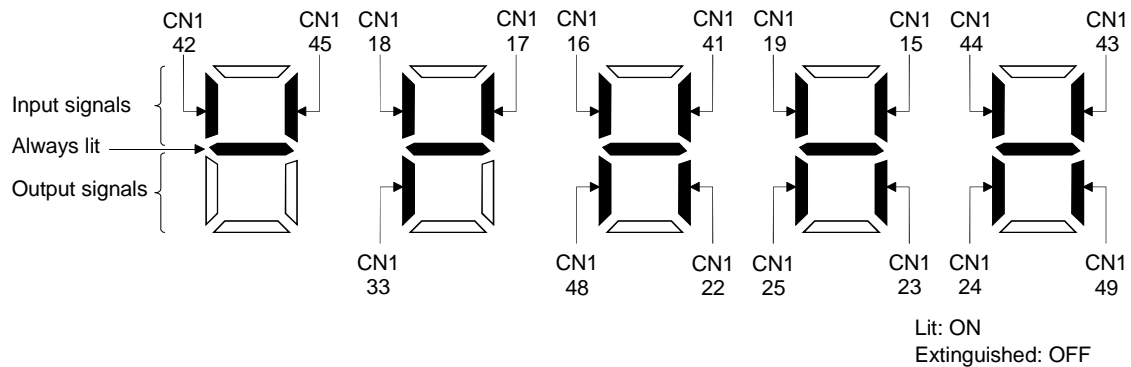
Call the display screen shown after power-on.

Using the "MODE" button, show the diagnostic screen.



(2) Display definition

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



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:

6. DISPLAY AND OPERATION SECTIONS

(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	15	I	SON	SON	SON	SON	SON	SON	No. PD03
	16	I		—/SP2	SP2	SP2/SP2	SP2	SP2/—	No. PD04
	17	I	PC	PC/ST1	ST1	ST1/RS2	RS2	RS2/PC	No. PD05
	18	I	TL	TL/ST2	ST2	ST2/RS1	RS1	RS1/TL	No. PD06
	19	I	RES	RES	RES	RES	RES	RES	No. PD07
	22	O	INP	INP/SA	SA	SA/—		—/INP	No. PD13
	23	O	ZSP	ZSP	ZSP	ZSP	ZSP	ZSP	No. PD14
	24	O	INP	INP/SA	SA	SA/—		—/INP	No. PD15
	25	O	TLC	TLC	TLC	TLC/VLC	VLC	VLC/TLC	No. PD16
	33	O	OP	OP	OP	OP	OP	OP	
	41	I	CR	CR/SP1	SP1	SP1/SP1	SP1	SP1/CR	No. PD08
	42	I	EMG	EMG	EMG	EMG	EMG	EMG	
	43	I	LSP	LSP	LSP	LSP/—		—/LSP	No. PD10
	44	I	LSN	LSN	LSN	LSN/—		—/LSN	No. PD11
	45	I	LOP	LOP	LOP	LOP	LOP	LOP	No. PD12
	48	O	ALM	ALM	ALM	ALM	ALM	ALM	
	49	O	RD	RD	RD	RD	RD	RD	No. PD18

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 change mode, S/T: Speed/torque control change mode, T/P: Torque/position control change mode

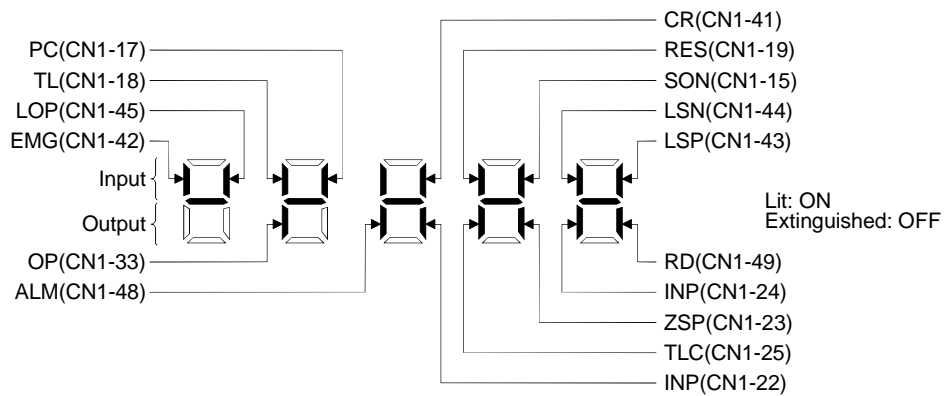
(b) Symbol and signal names

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

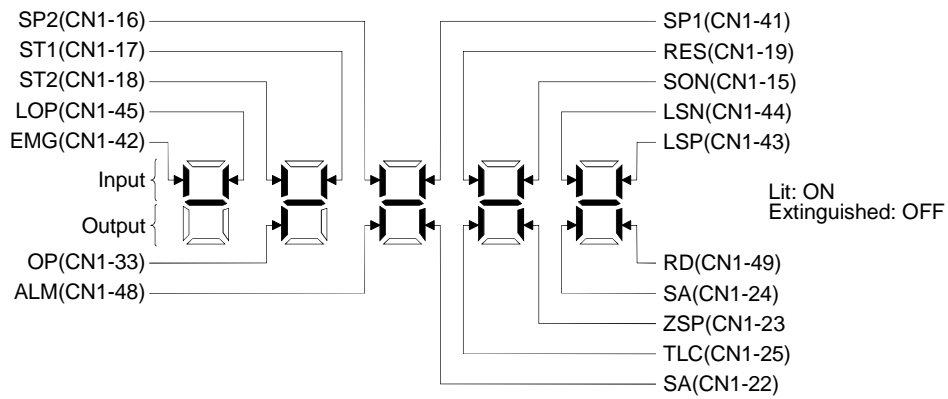
6. DISPLAY AND OPERATION SECTIONS

(3) Display data at initial values

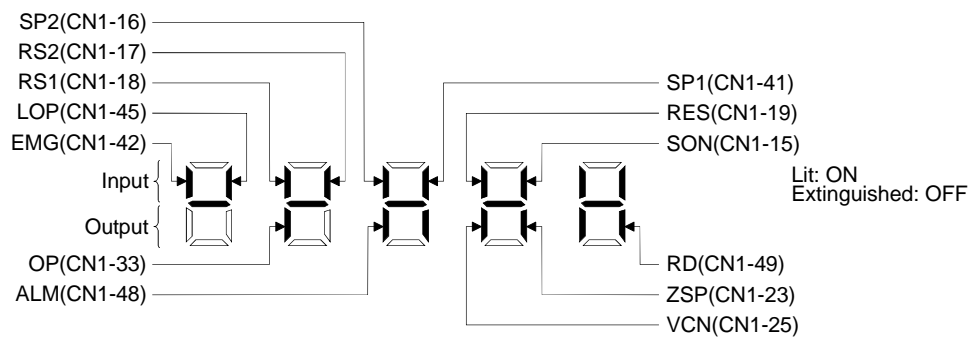
(a) Position control mode



(b) Speed control mode



(c) Torque control mode



6. DISPLAY AND OPERATION SECTIONS

6.8 Output signal (DO) forced output

POINT

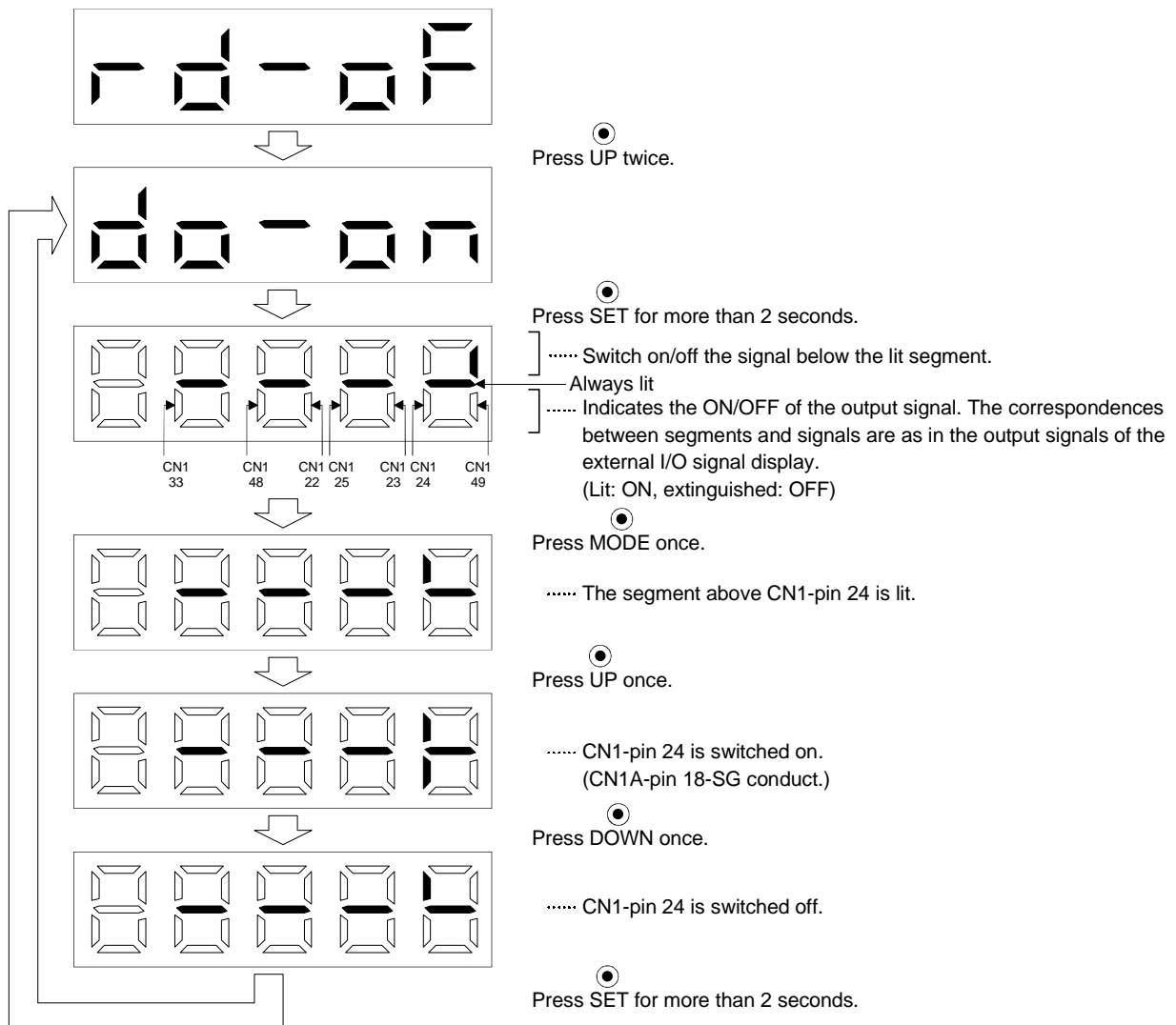
- When the servo system is used in a vertical lift application, turning on the electromagnetic brake interlock (MBR) after assigning it to connector CN1 will release the electromagnetic brake, causing a drop. Take drop preventive measures on the machine side.

The output signal can be forced on/off independently of the servo status. This function is used for output signal wiring check, etc. This operation must be performed in the servo off state servo-on (SON).

Operation

Call the display screen shown after power-on.

Using the "MODE" button, show the diagnostic screen.



6. DISPLAY AND OPERATION SECTIONS

6.9 Test operation mode



CAUTION

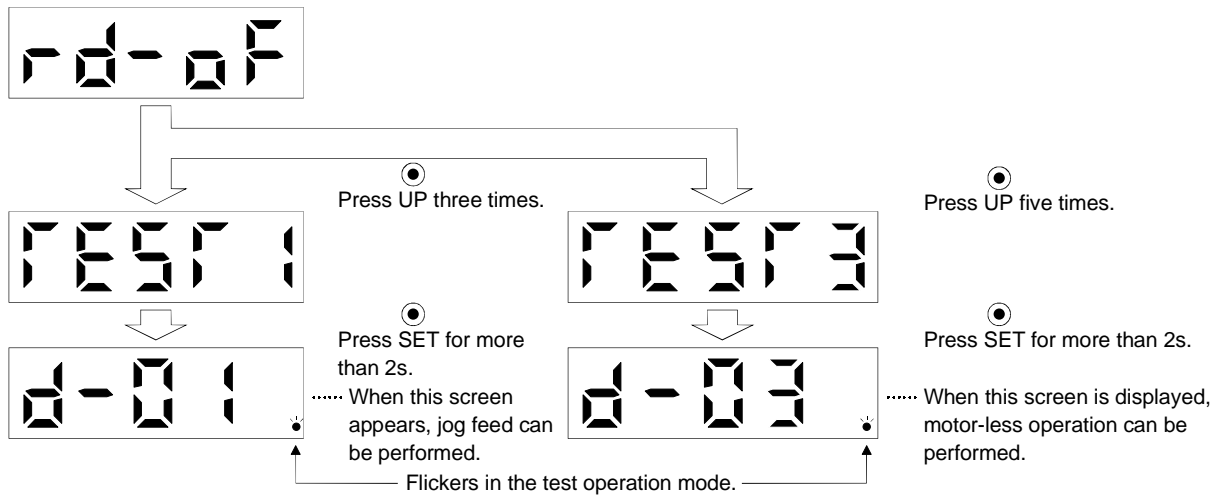
- The test operation mode is designed to confirm servo operation. Do not use it for actual operation.
- If any operational fault has occurred, stop operation using the emergency stop (EMG) signal.

POINT

- The test operation mode cannot be used in the absolute position detection system. Use it after choosing "Incremental system" in parameter No. PA03.
- The servo configuration software is required to perform positioning operation.
- Test operation cannot be performed if the servo-on (SON) is not turned OFF.

6.9.1 Mode change

Call the display screen shown after power-on. Choose jog operation/motor-less operation in the following procedure. Using the "MODE" button, show the diagnostic screen.



6. DISPLAY AND OPERATION SECTIONS

6.9.2 Jog operation

POINT	
▪ When performing jog operation, turn ON EMG, LSP and LSN. LSP and LSN can be set to automatic ON by setting parameter No. PD01 to "□ C □ □".	

Jog operation can be performed when there is no command from the external command device.

(1) Operation

Connect EMG-SG to start jog operation and connect VDD-COM to use the internal power supply.

Hold down the "UP" or "DOWN" button to run the servo motor. Release it to stop. When using the servo configuration software, you can change the operation conditions. The initial conditions and setting ranges for operation are listed below:

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

How to use the buttons is explained below:

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

If the communication cable is disconnected during jog operation performed by using the servo configuration software, the servo motor will be decelerated to a stop.

(2) Status display

You can confirm the servo status during jog operation.

Pressing the "MODE" button in the jog operation-ready status calls the status display screen. With this screen being shown, perform jog operation with the "UP" or "DOWN" button. Every time you press the "MODE" button, the next status display screen appears, and on completion of a screen cycle, pressing that button returns to the jog operation-ready status screen. For full information of the status display, refer to Section 6.3. In the test operation mode, you cannot use the "UP" and "DOWN" buttons to change the status display screen from one to another.

(3) Termination of jog operation

To end the jog operation, switch power off once or press the "MODE" button to switch to the next screen and then hold down the "SET" button for 2 or more seconds.



6. DISPLAY AND OPERATION SECTIONS

6.9.3 Positioning operation

POINT	
	<ul style="list-style-type: none">▪ MR Configurator (Servo Configuration software) is required to perform positioning operation.▪ Turn ON EMG when performing positioning operation.

With no command given from the external command device, positioning operation can be executed once.

(1) Operation

a) Motor speed [r/min]

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

b) Accel/decel time [ms]

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

c) Move distance [pulse]

Enter the moving distance into the "*****" input field.

d) LSP/LSN automatically turned ON

When setting the external stroke signal to automatic ON, click the check box to make it valid. When it is not checked, turn ON LSN/LSP externally.

e) Move till a first Z-phase signal turned ON in the moving direction

Movement is made until the moving distance is reached and the first Z-phase signal in the moving direction turns ON.

f) Pulse move distance unit selection/Command input pulse unit/Encoder pulse unit

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

When the encoder pulse unit is selected, the moving distance is regarded as the value before multiplication of the electronic gear ($\frac{CMX}{CDV}$). When the command pulse unit is selected, the moving distance is regarded as the value after multiplication of the electronic gear.

g) Forward/Reverse

Click the "*****" button to rotate the servo motor in the forward rotation direction.

Click the "*****" button to rotate the servo motor in the reverse rotation direction.

h) Pause

Click the "*****" button during servo motor rotation to temporarily stop the servo motor.

This button is valid during servo motor rotation.

i) Restart

Click the "*****" button during a temporary stop to restart the servo motor rotation.

This button is valid during a temporary stop of the servo motor.

j) Remaining move distance clear

Click the "*****" button during a temporary stop to erase the remaining distance.

This button is valid during a temporary stop of the servo motor.

k) Forced stop

Click the "*****" button during servo motor rotation to make a hard stop.

This button is valid during servo motor rotation.

l) Close

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

(2) Status display

The status display can be monitored during positioning operation.

6. DISPLAY AND OPERATION SECTIONS

6.9.4 Motor-less operation

Without connecting the servo motor, you can provide output signals or monitor the status display as if the servo motor is running in response to external input signals. This operation can be used to check the sequence of a host programmable controller or the like.

(1) Operation

Turn SON off, choose motor-less operation. After that, perform external operation as in ordinary operation.

(2) Status display

You can confirm the servo status during motor-less operation.

Pressing the "MODE" button in the motor-less operation-ready status calls the status display screen. With this screen being shown, perform motor-less operation. Every time you press the "MODE" button, the next status display screen appears, and on completion of a screen cycle, pressing that button returns to the motor-less operation-ready status screen. For full information of the status display, refer to Section 6.3. In the test operation mode, you cannot use the "UP" and "DOWN" buttons to change the status display screen from one to another.

(3) Termination of motor-less operation

To terminate the motor-less operation, switch power off.

7. GENERAL GAIN ADJUSTMENT

7. GENERAL GAIN ADJUSTMENT

POINT	
▪ For use in the torque control mode, you need not make gain adjustment.	

7.1 Different adjustment methods

7.1.1 Adjustment on a single servo amplifier

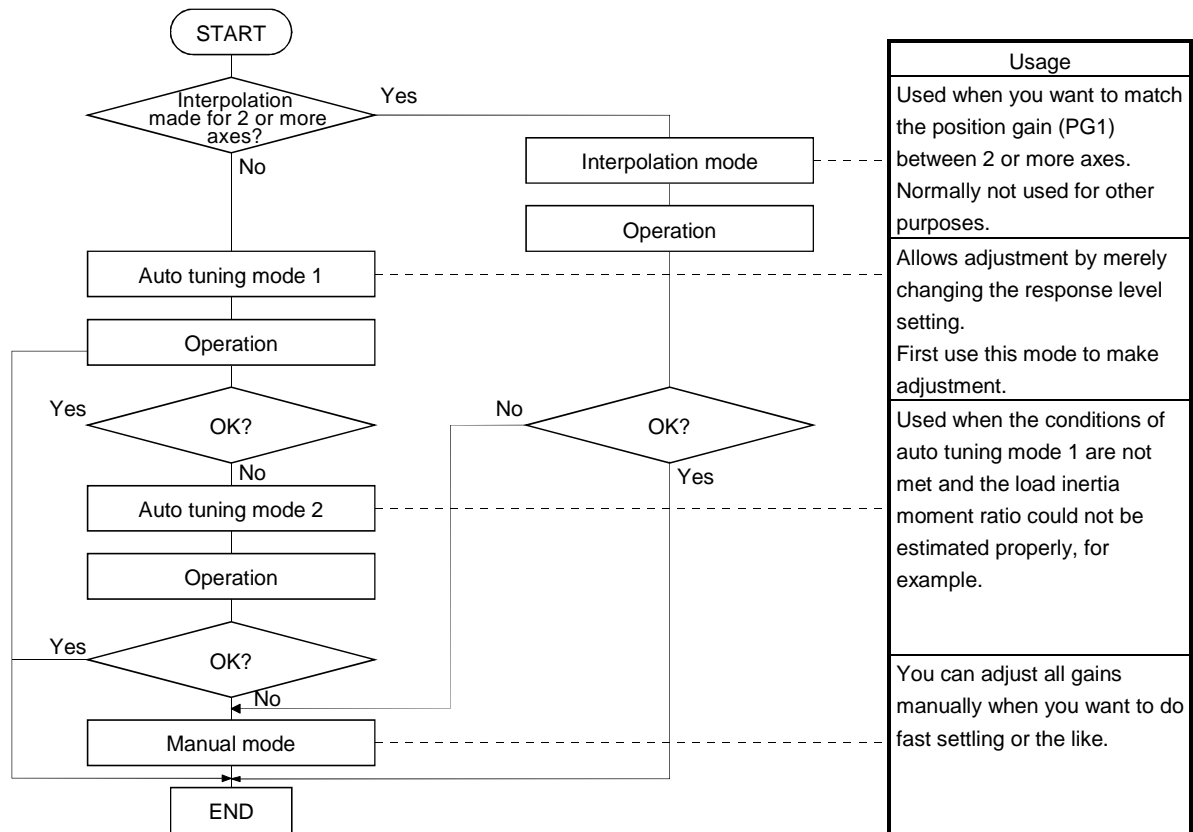
The gain adjustment in this section can be made on a single servo amplifier. For gain adjustment, first execute auto tuning mode 1. If you are not satisfied with the results, execute auto tuning mode 2 and manual mode in this order.

(1) Gain adjustment mode explanation

Gain adjustment mode	Parameter No. PA08 setting	Estimation of load inertia moment ratio	Automatically set parameters	Manually set parameters
Auto tuning mode 1 (initial value)	0001	Always estimated	GD2 (parameter No. PB06) PG2 (parameter No. PB08) PG1 (parameter No. PB07) VG2 (parameter No. PB09) VIC (parameter No. PB10)	Response level setting of parameter No. 2
Auto tuning mode 2	0002	Fixed to parameter No. PB06 value	PG2 (parameter No. PB08) PG1 (parameter No. PB07) VG2 (parameter No. PB09) VIC (parameter No. PB10)	GD2 (parameter No. PB06) Response level setting of parameter No. PA09
Manual mode	0003			PG1 (parameter No. PB07) GD2 (parameter No. PB06) VG2 (parameter No. PB09) VIC (parameter No. PB10)
Interpolation mode	0000	Always estimated	GD2 (parameter No. PB06) PG2 (parameter No. PB08) VG2 (parameter No. PB09) VIC (parameter No. PB10)	PG1 (parameter No. PB07)

7. GENERAL GAIN ADJUSTMENT

(2) Adjustment sequence and mode usage



7.1.2 Adjustment using servo configuration software

This section gives the functions and adjustment that may be performed by using the servo amplifier with the servo configuration software which operates on a personal computer.

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 the personal computer to the servo and measuring the machine response.	<ul style="list-style-type: none"> You can grasp the machine resonance frequency and determine the notch frequency of the machine resonance suppression filter. You can automatically set the optimum gains in response to the machine characteristic. This simple adjustment is suitable for a machine which has large machine resonance and does not require much settling time.
Gain search	Executing gain search under to-and-fro positioning command measures settling characteristic while simultaneously changing gains, and automatically searches for gains which make settling time shortest.	<ul style="list-style-type: none"> You can automatically set gains which make positioning settling time shortest.
Machine simulation	Response at positioning settling of a machine can be simulated from machine analyzer results on personal computer.	<ul style="list-style-type: none"> You can optimize gain adjustment and command pattern on personal computer.

7. GENERAL GAIN ADJUSTMENT

7.2 Auto tuning

7.2.1 Auto tuning mode

The servo amplifier has a real-time auto tuning function which estimates the machine characteristic (load inertia moment 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 inertia moment 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 No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

POINT

- The auto tuning mode 1 may not be performed properly if the following conditions are not satisfied.
 - Time to reach 2000r/min is the acceleration/deceleration time constant of 5s or less.
 - Speed is 150r/min or higher.
 - The ratio of load inertia moment to servo motor inertia moment is 100 times or less.
 - The acceleration/deceleration torque is 10% or more of the rated torque.
- 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.

(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 inertia moment ratio is not estimated in this mode, set the value of a correct load inertia moment ratio (parameter No. PB06).

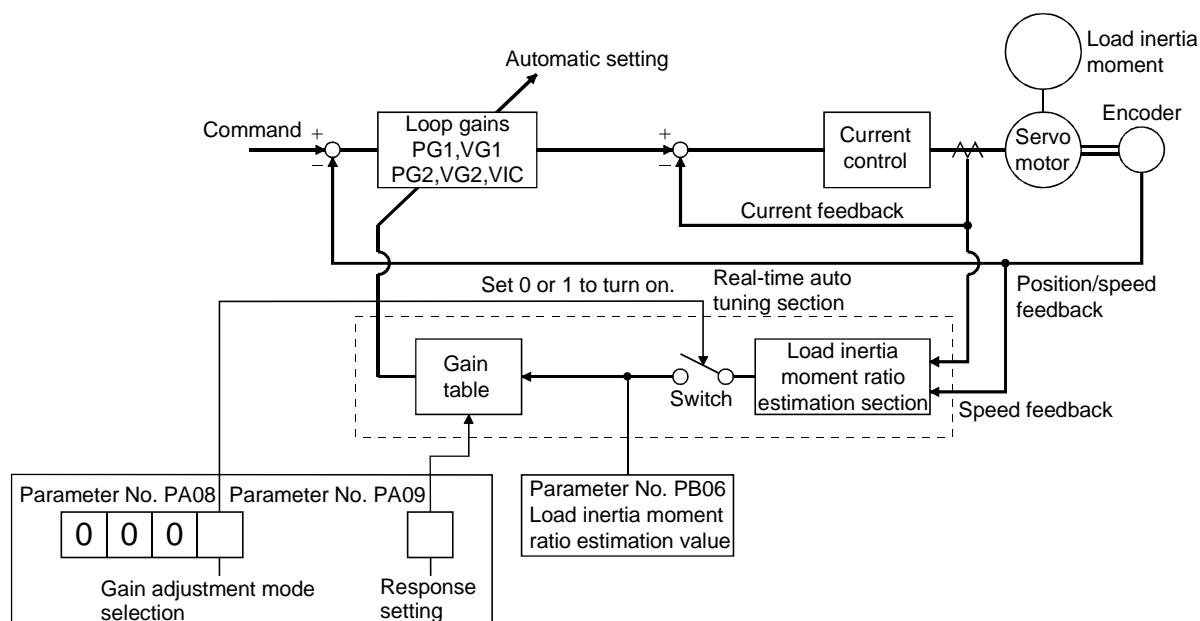
The following parameters are automatically adjusted in the auto tuning mode 2.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

7. GENERAL GAIN ADJUSTMENT

7.2.2 Auto tuning mode operation

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



When a servo motor is accelerated/decelerated, the load inertia moment ratio estimation section always estimates the load inertia moment ratio from the current and speed of the servo motor. The results of estimation are written to parameter No. PB06 (the ratio of load inertia moment to servo motor). These results can be confirmed on the status display screen of the servo configuration software section.

If the value of the load inertia moment ratio is already known or if estimation cannot be made properly, choose the "auto tuning mode 2" (parameter No. PA08: 0002) to stop the estimation of the load inertia moment ratio (Switch in above diagram turned off), and set the load inertia moment ratio (parameter No. 34) manually.

From the preset load inertia moment ratio (parameter No. PB06) value and response level (parameter No. PA09), the optimum loop gains are automatically set on the basis of the internal gain table.

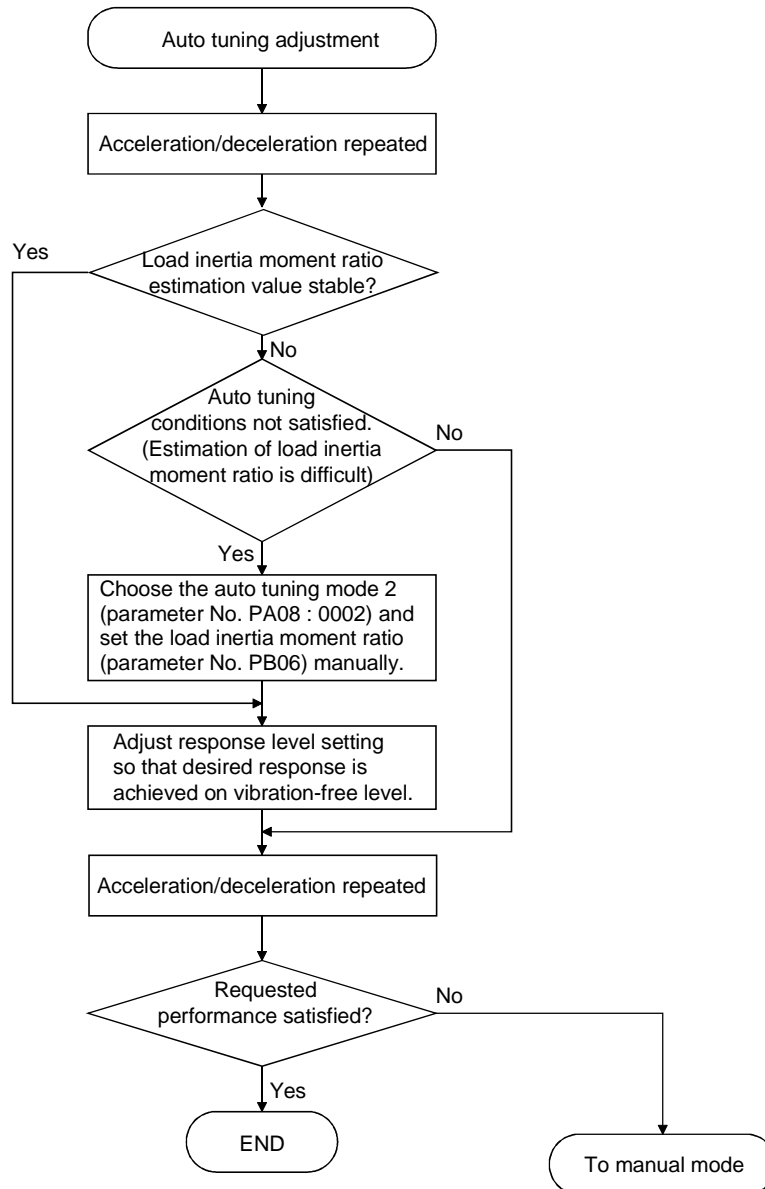
The auto tuning results are saved in the EEP-ROM of the servo amplifier every 60 minutes since power-on. At power-on, auto tuning is performed with the value of each loop gain saved in the EEP-ROM being used as an initial value.

POINT	
	<ul style="list-style-type: none"> If sudden disturbance torque is imposed during operation, the estimation of the inertia moment ratio may malfunction temporarily. In such a case, choose the "auto tuning mode 2" (parameter No. PA08: 0002) and set the correct load inertia moment ratio in parameter No. PB06. 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 inertia moment ratio estimation value are saved in the EEP-ROM.

7. GENERAL GAIN ADJUSTMENT

7.2.3 Adjustment procedure by auto tuning

Since auto tuning is made valid 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.



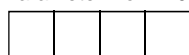
7. GENERAL GAIN ADJUSTMENT

7.2.4 Response level setting in auto tuning mode

Set the response (The first digit of parameter No. PA09) of the whole servo system. As the response level setting is increased, the trackability 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 100Hz, filter tuning mode (parameter No. PB01) or machine resonance suppression filter (parameter No. PB13 to PB16) may be used to suppress machine resonance. Suppressing machine resonance may allow the response level setting to increase. Refer to Section 8.1 for filter tuning mode and machine resonance suppression filter.

Parameter No. PA09



Response level setting
Gain adjustment mode selection

Response level setting	Machine characteristic		
	Machine rigidity	Machine resonance frequency guideline	Guideline of corresponding machine
1	Low ↑	10.0	
2		11.3	
3		12.7	
4		14.3	
5		16.1	
6		18.1	
7		20.4	
8		23.0	
9		25.9	
10		29.2	
11		32.9	
12		37.0	
13		41.7	
14		47.0	
15	Middle ↑	52.9	
16		59.6	
17		67.1	
18		75.6	
19		85.2	
20		95.9	
21		108.0	
22		121.7	
23		137.1	
24		154.4	
25		173.9	
26		195.9	
27		220.6	
28		248.5	
29		279.9	
30		315.3	
31		355.1	
32	High	400.0	

7. GENERAL GAIN ADJUSTMENT

7.3 Manual mode 1 (simple manual adjustment)

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

POINT	
	▪ If machine resonance occurs, filter tuning mode (parameter No. PB01) or machine resonance suppression filter (parameter No. PB13 to PB16) may be used to suppress machine resonance. (Refer to Section 8.1.)

(1) For speed control

(a) Parameters

The following parameters are used for gain adjustment:

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment.	
2	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.
3	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.
4	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 filter tuning mode or machine resonance suppression filter and then executing steps 2 and 3.	Suppression of machine resonance. Refer to Section 8.2, 8.3.
5	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment

7. GENERAL GAIN ADJUSTMENT

(c) Adjustment description

1) Speed loop gain (parameter No. PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression:

$$\text{Speed loop response frequency(Hz)} = \frac{\text{Speed loop gain setting}}{(1 + \text{ratio of load inertia moment to servo motor inertia moment}) \times 2\pi}$$

2) Speed integral compensation (VIC: parameter No. PB10)

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 inertia moment 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:

$$\text{Speed integral compensation setting(ms)} \geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain setting} / (1 + \text{ratio of load inertia moment to servo motor inertia moment setting} \times 0.1)}$$

(2) For position control

(a) Parameters

The following parameters are used for gain adjustment:

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	VG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment.	
2	Set a slightly smaller value to the model loop gain.	
3	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.
4	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.
5	Increase the model loop gain 1.	Increase the position loop gain.
6	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 filter tuning mode or machine resonance suppression filter and then executing steps 3 to 5.	Suppression of machine resonance. Refer to Section 8.1.
7	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment

7. GENERAL GAIN ADJUSTMENT

(c) Adjustment description

1) Model loop gain (parameter No. PB07)

This parameter determines the response level of the model loop. Increasing position loop gain 1 improves trackability to a position command but a too high value will make overshooting liable to occur at the time of settling.

$$\text{Model loop gain guideline} \leq \frac{\text{Speed loop gain 2 setting}}{(1 + \text{ratio of load inertia moment to servo motor inertia moment})} \times \left(\frac{1}{4} \text{ to } \frac{1}{8} \right)$$

2) Speed loop gain (VG2: parameter No. PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression:

$$\text{Speed loop response frequency(Hz)} = \frac{\text{Speed loop gain 2 setting}}{(1 + \text{ratio of load inertia moment to servo motor inertia moment}) \times 2\pi}$$

3) Speed integral compensation (parameter No. PB10)

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 inertia moment 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:

$$\text{Speed integral compensation setting(ms)} \geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain 2 setting} / (1 + \text{ratio of load inertia moment to servo motor inertia moment 2 setting})}$$

7. GENERAL GAIN ADJUSTMENT

7.4 Interpolation mode

The interpolation mode is used 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, the model loop gain and speed loop gain which determine command trackability are set manually and the other parameter for gain adjustment are set automatically.

(1) Parameter

(a) Automatically adjusted parameters

The following parameters are automatically adjusted by auto tuning.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Manually adjusted parameters

The following parameters are adjustable manually.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain

(2) Adjustment procedure

Step	Operation	Description
1	Set to the auto tuning mode.	Select the auto tuning mode 1.
2	During operation, increase the response level setting (parameter No. PA09), and return the setting if vibration occurs.	Adjustment in auto tuning mode 1.
3	Check the values of model loop gain.	Check the upper setting limits.
4	Set the interpolation mode (parameter No. PA08: 0000).	Select the interpolation mode.
5	Using the model loop gain value checked in step 3 as the guideline of the upper limit, set in PG1 the value identical to the position loop gain of the axis to be interpolated.	Set position loop gain.
6	Looking at the interpolation characteristic and rotation status, fine-adjust the gains and response level setting.	Fine adjustment.

(3) Adjustment description

(a) Model loop gain (parameter No. PB07)

This parameter determines the response level of the position control loop. Increasing model loop gain improves trackability to a position command but a too high value will make overshooting liable to occur at the time of settling. The droop pulse value is determined by the following expression.

$$\text{Droop pulse value (pulse)} = \frac{\frac{\text{Rotation speed (r/min)}}{60} \times 262144(\text{pulse})}{\text{Model loop gain setting}}$$

7. GENERAL GAIN ADJUSTMENT

7.5 Differences in auto tuning between MELSERVO-J2 and MELSERVO-J2-Super

To meet higher response demands, the MELSERVO-J3 series has been changed in response level setting range from the MELSERVO-J2S-Super series. The following table lists comparison of the response level setting.

MELSERVO-J2-Super		MELSERVO-J3	
Parameter No. 2 Setting	Guideline for Machine Resonance Frequency [Hz]	Parameter No. PA09 Setting	Guideline for Machine Resonance Frequency [Hz]
		1	10.0
		2	11.3
		3	12.7
□□□ 1	15	4	14.3
		5	16.1
		6	18.1
□□□ 2	20	7	20.4
		8	23.0
		9	25.9
□□□ 3	25	10	29.2
□□□ 4	30	11	32.9
		12	37.0
		13	41.7
□□□ 5	35	14	47.0
□□□ 6	45	15	52.9
□□□ 7	55	16	59.6
		17	67.1
		18	75.6
□□□ 8	70	19	85.2
□□□ 9	85	20	95.9
		21	108.0
		22	121.7
□□□ A	105	23	137.1
□□□ B	130	24	154.4
□□□ C	160	25	173.9
		26	195.9
		27	220.6
□□□ D	200	28	248.5
□□□ E	240	29	279.9
		30	315.3
		31	355.1
□□□ F	300	32	400.0

Note that because of a slight difference in gain adjustment pattern, response may not be the same if the resonance frequency is set to the same value.

[illegible]

8. SPECIAL ADJUSTMENT FUNCTIONS

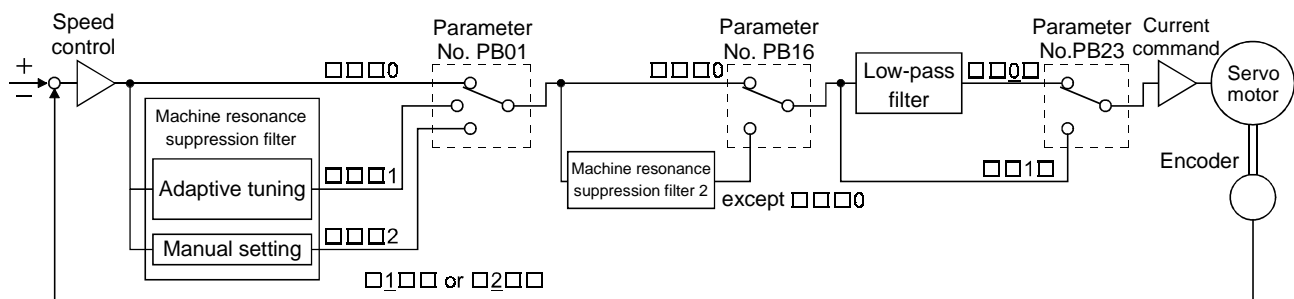
8. SPECIAL ADJUSTMENT FUNCTIONS

POINT

- The functions given in this chapter need not be used generally. Use them if you are not satisfied with the machine status after making adjustment in the methods in Chapter 7.

If a mechanical system has a natural 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.

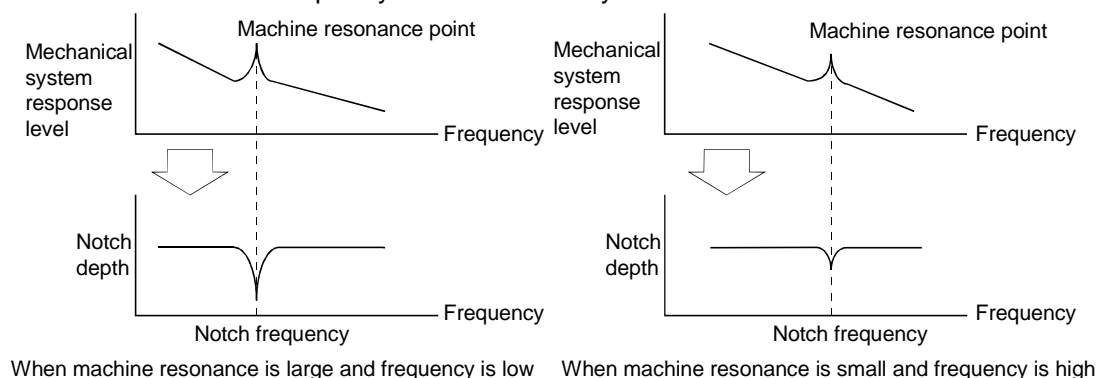
8.1 Function block diagram



8.2 Adaptive filter II

(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.



POINT

- The machine resonance frequency which adaptive tuning mode can respond to is about 100 to 2.25kHz. Adaptive vibration suppression control has no effect on the resonance frequency outside this range.
- Adaptive vibration suppression control may provide no effect on a mechanical system which has complex resonance characteristics.

8. SPECIAL ADJUSTMENT FUNCTIONS

(2) Parameters

The operation of adaptive tuning mode (parameter No. PB01).

Parameter No.60

0	0	0	
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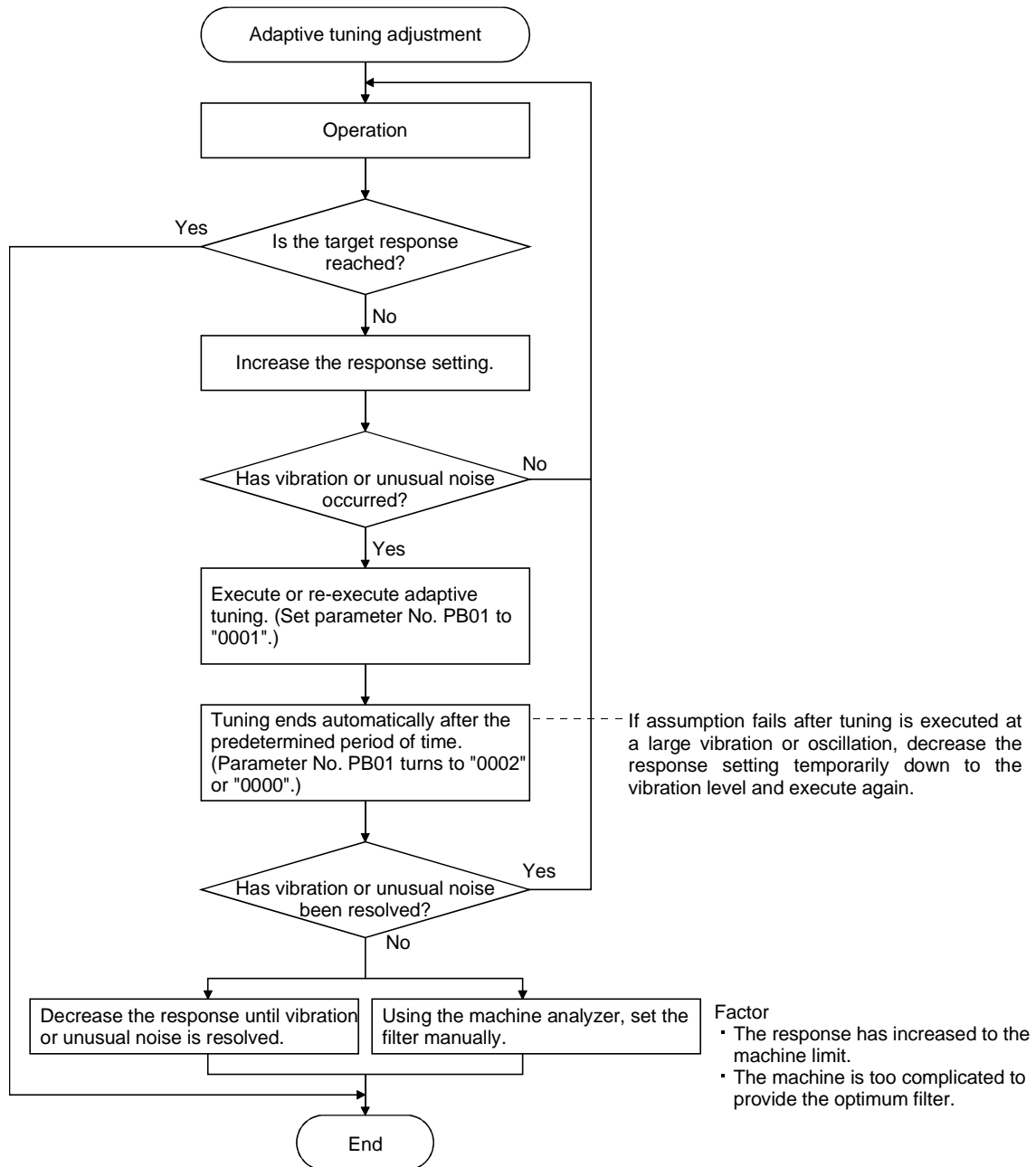
└ Filter tuning mode selection

Setting	Filter adjustment mode	Automatically set parameter
0	Filter OFF	(Note)
1	Filter tuning mode	Parameter No. PB13 Parameter No. PB14
2	Manual mode	

Note. Parameter No. PB19 and PB20 are fixed to the initial values.

8. SPECIAL ADJUSTMENT FUNCTIONS

(3) Adaptive tuning mode procedure



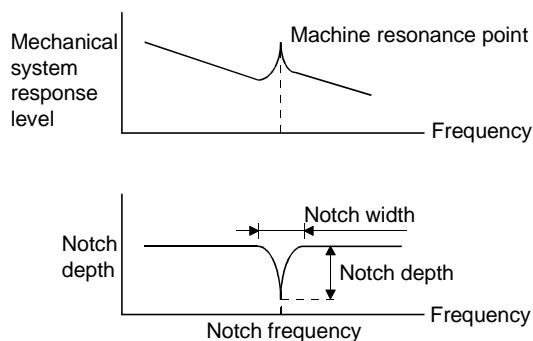
8. SPECIAL ADJUSTMENT FUNCTIONS

POINT
<ul style="list-style-type: none"> ▪ "Filter OFF" enables a return to the factory-set initial value. ▪ When adaptive tuning is executed, vibration sound increases as an excitation signal is forcibly applied for several seconds. ▪ When adaptive tuning is executed, machine resonance is detected for a maximum of 10 seconds and a filter is generated. After filter generation, the adaptive tuning mode automatically shifts to the manual mode. ▪ 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. ▪ During adaptive tuning, a filter having the best notch depth at the set control gain is generated. To allow a filter margin against mechane resonance, increase the notch depth in the manual mode.

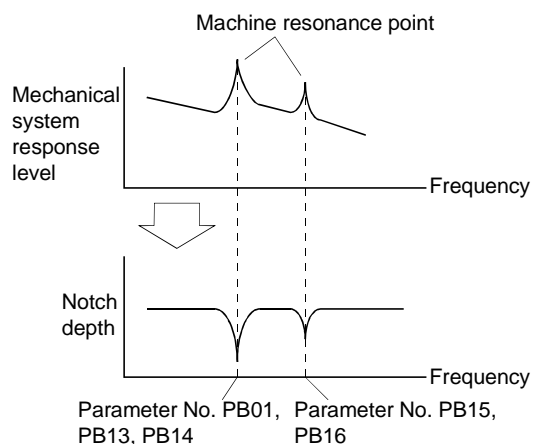
8.3 Machine resonance suppression filter

(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 use the machine resonance suppression filter 1 (parameter No. PB13, PB14) and machine resonance suppression filter 2 (parameter No. PB15, PB16) to suppress the vibration of two resonance frequencies. Execution of adaptive tuning in the filter tuning mode automatically adjusts the machine resonance suppression filter. When adaptive tuning is ON, the adaptive tuning mode shifts to the manual mode after the predetermined period of time. The manual mode enables manual setting using the machine resonance suppression filter 1.



8. SPECIAL ADJUSTMENT FUNCTIONS

(2) Parameters

(a) Machine resonance suppression filter 1 (parameter No. PB13, PB14)

Set the notch frequency, notch depth and notch width of the machine resonance suppression filter 1 (parameter No. PB13, PB14)

When you have made adaptive filter tuning mode (parameter No. PB01) "manual mode", set up the machine resonance suppression filter 1 becomes effective.

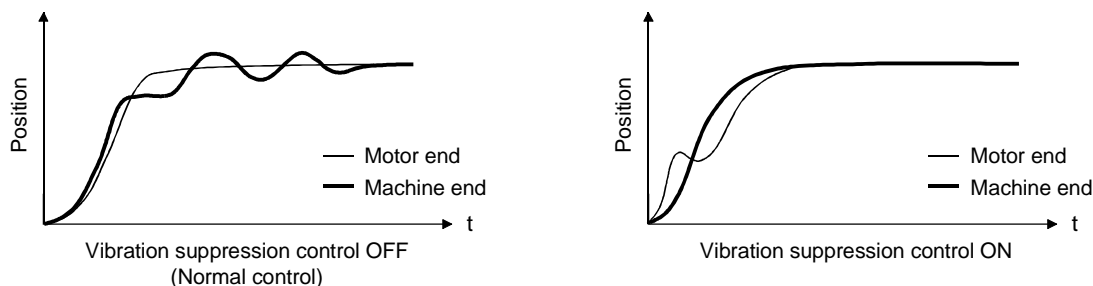
POINT	
	<ul style="list-style-type: none">▪ The machine resonance suppression filter is a delay factor for the servo system. Hence, vibration may increase if you set a wrong resonance frequency or a too deep notch.▪ If the frequency of machine resonance is unknown, decrease the notch frequency from higher to lower ones in order. The optimum notch frequency is set at the point where vibration is minimal.▪ A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.▪ A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.▪ The machine characteristic can be grasped beforehand by the machine analyzer on the MR Configurator (Servo configuration software). This allows the required notch frequency and depth to be determined.

8. SPECIAL ADJUSTMENT FUNCTIONS

8.4 Advanced Vibration Suppression Control

(1) Operation

Vibration suppression control is used to further suppress machine end vibration, such as workpiece end vibration and base shake. The motor side operation is adjusted for positioning so that the machine does not shake.



When the advanced vibration suppression control (vibration suppression control tuning mode parameter No. PB02) is executed, the vibration frequency at machine end can automatically be estimated to suppress machine end vibration.

In the vibration suppression control tuning mode, this mode shifts to the manual mode after operation is performed the predetermined number of times. The manual mode enables manual setting using the vibration suppression control vibration frequency setting (parameter No. PB19) and vibration suppression control resonance frequency setting (parameter No. PB20).

(2) Parameter

Select the operation of the vibration suppression control tuning mode (parameter No. PB02).

Parameter No. PB02

0	0	0	
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Vibration suppression control
tuning mode

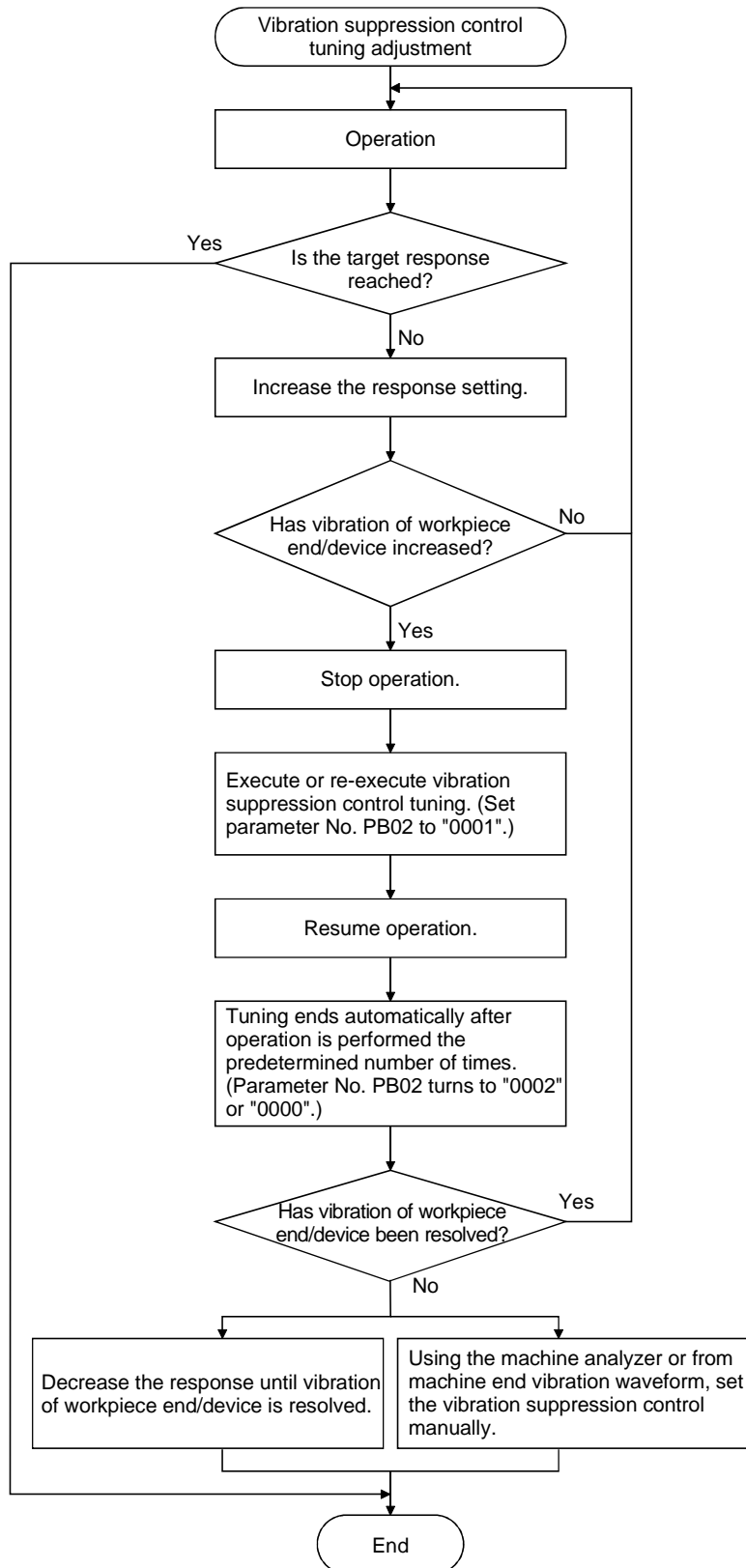
Setting	Vibration Suppression Control Tuning Mode	Automatically Set Parameter
0	Vibration suppression control OFF	(Note)
1	Vibration suppression control tuning mode (Advanced vibration suppression control)	Parameter No. PB19 Parameter No. PB20
2	Manual mode	

Note. Parameter No. PB19 and PB20 are fixed to the initial values.

POINT
<ul style="list-style-type: none"> ▪ The function is made valid when the auto tuning mode (parameter No. PA08) is the auto tuning mode 2 ("0002") or manual mode ("0003"). ▪ The machine resonance frequency supported in the vibration suppression control tuning mode is 1.0Hz to 100.0Hz. The function is not effective for vibration outside this range. ▪ Stop the motor before changing the vibration suppression control-related parameters (parameter No. PB02, PB19, PB20, PB33, PB34). A failure to do so will cause a shock. ▪ For positioning operation during execution of vibration suppression control tuning, provide a stop time to ensure a stop after full vibration damping. ▪ Vibration suppression control tuning may not make normal estimation if the residual vibration at the motor end 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.

8. SPECIAL ADJUSTMENT FUNCTIONS

(3) Vibration suppression control tuning mode procedure



Factor

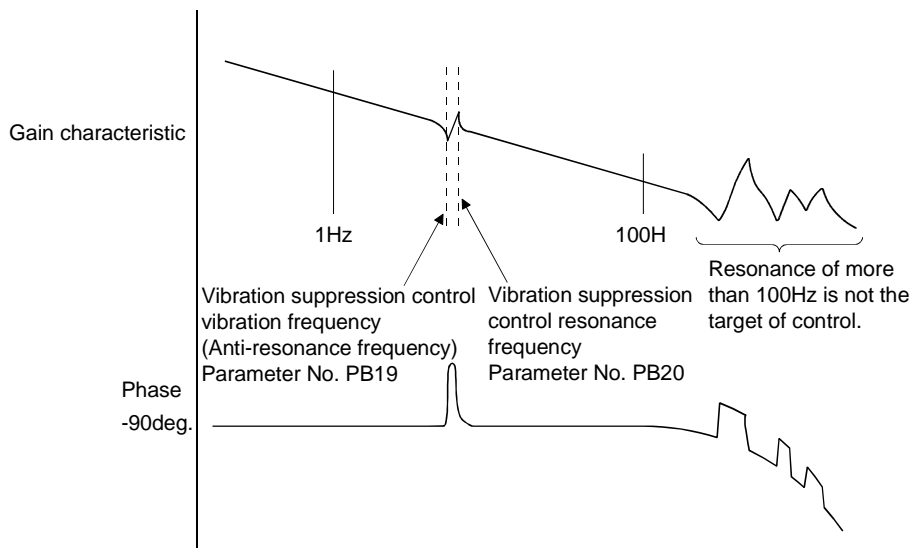
- Estimation cannot be made as machine end vibration has not been transmitted to the motor end.
- The response of the model loop gain has increased to the machine end vibration frequency (vibration suppression control limit).

8. SPECIAL ADJUSTMENT FUNCTIONS

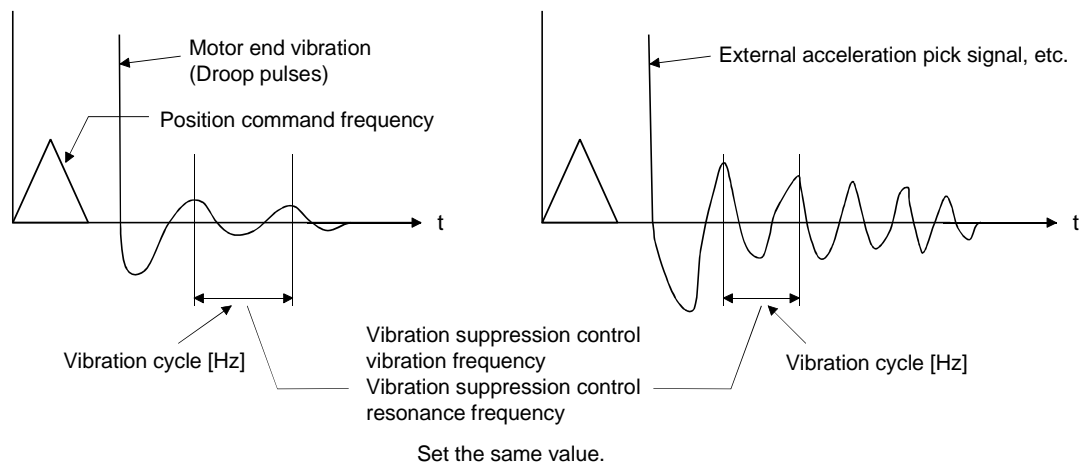
(4) Vibration suppression control manual mode

Measure work end vibration and device shake with the machine analyzer or external measuring instrument, and set the vibration suppression control vibration frequency (parameter No. PB19) and vibration suppression control resonance frequency (parameter No. PB20) to set vibration suppression control manually.

(a) When a vibration peak can be confirmed using MR Configurator, machine analyzer or external FFT equipment



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



8. SPECIAL ADJUSTMENT FUNCTIONS

POINT	
	<ul style="list-style-type: none">▪ When machine end vibration does not show up in motor end vibration, the setting of the motor end vibration frequency does not produce an effect.▪ When the anti-resonance frequency and resonance frequency can be confirmed using the machine analyzer or external FFT device, do not set the same value but set different values to improve the vibration suppression performance.▪ A vibration suppression control effect is not produced if the relationship between the model loop gain (parameter No. PB07) value and vibration frequency is as indicated below. Make setting after decreasing PG1, e.g. reduce the response setting. $\frac{1}{2\pi} (1.5 \times \text{PG1}) > \text{vibration frequency}$

8. SPECIAL ADJUSTMENT FUNCTIONS

8.5 Low-pass filter

(1) Function

When a ballscrew 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 factory-set to be valid for a torque command. The filter frequency of this low-pass filter is automatically adjusted to the value in the following expression:

$$\text{Filter frequency(rad/s)} = \frac{VG2}{1 + GD2} \times 10$$

When parameter No. PB23 is set to " ☐ ☐ 1 ☐ ", manual setting can be made with parameter No. PB18.

(2) Parameter

Set the operation of the low-pass filter selection (parameter No. PB23.)

Parameter No. PB23

<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>
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Low-pass filter selection

0: Automatic setting (initial value)

1: Manual setting (parameter No. PB18 setting)

8.6 Gain changing function

This function can change the gains. You can change between gains during rotation and gains during stop or can use an external signal to change gains during operation.

8.6.1 Applications

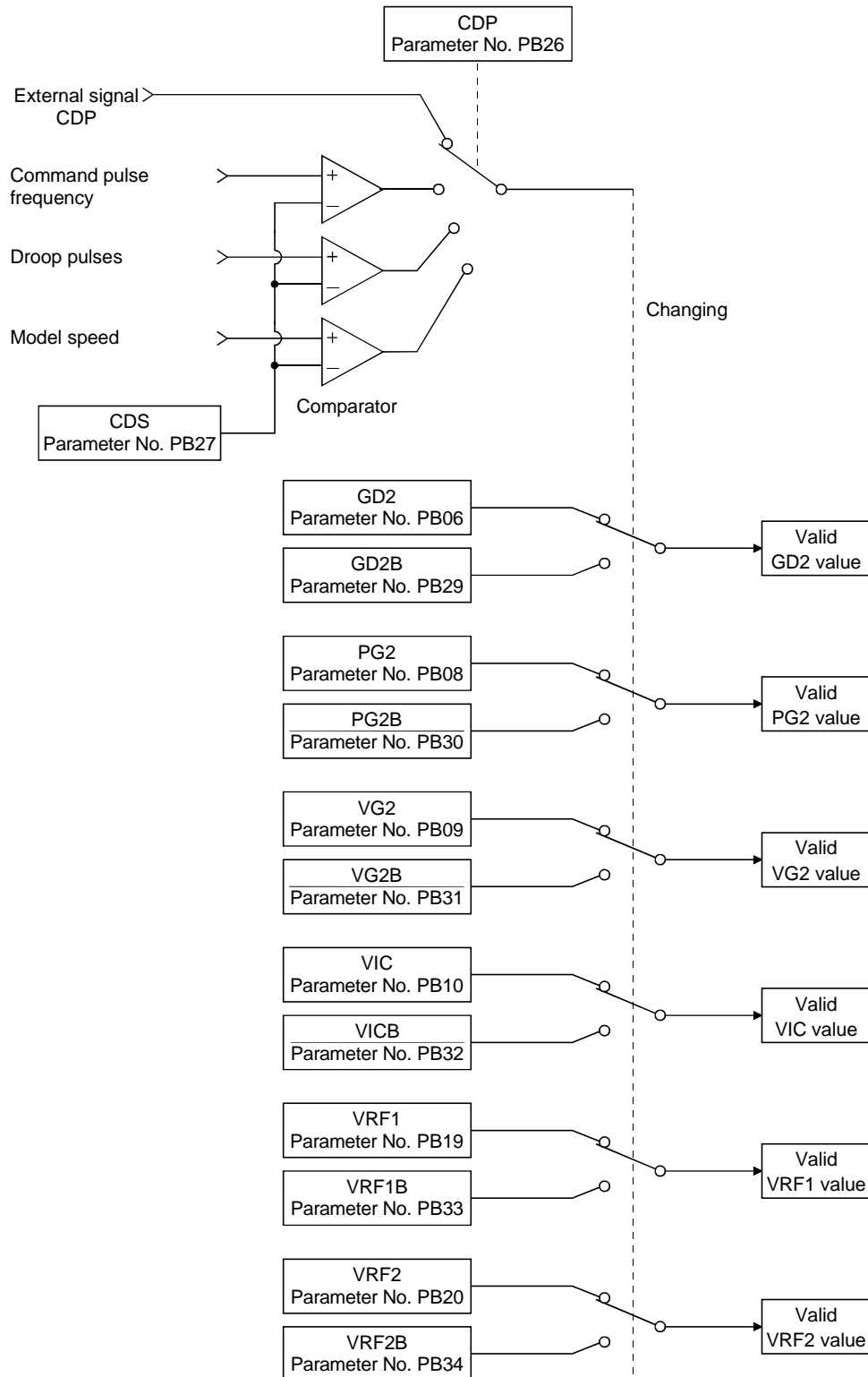
This function is used when:

- (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 external signal to ensure stability of the servo system since the load inertia moment ratio varies greatly during a stop (e.g. a large load is mounted on a carrier).

8. SPECIAL ADJUSTMENT FUNCTIONS

8.6.2 Function block diagram

The valid loop gains PG2, VG2, VIC and GD2 of the actual loop are changed according to the conditions selected by gain changing selection CDP (parameter No. PB26) and gain changing condition CDS (parameter No. PB27).



8. SPECIAL ADJUSTMENT FUNCTIONS

8.6.3 Parameters

When using the gain changing function, always set "□□□3" in parameter No. PA08 (auto tuning) to choose the manual mode of the gain adjustment modes. The gain changing function cannot be used in the auto tuning mode.

Parameter No.	Abbreviation	Name	Unit	Description
PB07	PG1	Model loop gain	rad/s	Position and speed gains of a model used to set the response level to a command. Always valid.
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	times	Control parameters before changing
PB08	PG2	Position loop gain	rad/s	
PB09	VG2	Speed loop gain	rad/s	
PB10	VIC	Speed integral compensation	ms	
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	times	Used to set the ratio of load inertia moment to servo motor inertia moment after changing.
PB30	PG2B	Gain changing position loop gain 2	rad/s	Used to set the value of the after-changing position loop gain 2.
PB31	VG2B	Gain changing speed loop gain 2	rad/s	Used to set the value of the after-changing speed loop gain.
PB32	VICB	Gain changing speed integral compensation	ms	Used to set the value of the after-changing speed integral compensation.
PB26	CDP	Gain changing selection		Used to select the changing condition.
PB27	CDS	Gain changing condition	kpps pulse r/min	Used to set the changing condition values.
PB28	CDT	Gain changing time constant	ms	You can set the filter time constant for a gain change at changing.
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	Hz	Used to set the value of the after-changing vibration suppression control vibration frequency setting.
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	Hz	Used to set the value of the after-changing vibration suppression control resonance frequency setting.

8. SPECIAL ADJUSTMENT FUNCTIONS

(1) Parameters No. PB06 to PB10

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

(2) Gain changing ratio of load inertia moment to servo motor inertia moment (GD2B: parameter No. PB29)

Set the ratio of load inertia moment to servo motor inertia moment after changing. If the load inertia moment ratio does not change, set it to the same value as ratio of load inertia moment to servo motor inertia moment (parameter No. PB06).

(3) Gain changing position loop gain (parameter No. PB30), Gain changing speed loop gain (parameter No. PB31), Gain changing speed integral compensation (parameter No. PB32)

Set the values of after-changing position loop gain, speed loop gain and speed integral compensation.

(4) Gain changing selection (parameter No. PB26)

Used to set the gain changing condition. Choose the changing condition in the first digit. If you set "1" here, you can use the gain changing (CDP) external input signal for gain changing. The gain changing (CDP) can be assigned to the pins using parameters No. PB13 to PB16, PB18.

Parameter No. PB26

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Gain changing selection

Gains are changed in accordance with the settings of parameters No. PB29 to PB32 under any of the following conditions:

- 0: Invalid
- 1: Gain changing (CDP) input is ON
- 2: Command frequency is equal to higher than parameter No. PB27 setting
- 3: Droop pulse value is equal to higher than parameter No. PB27 setting
- 4: Servo motor speed is equal to higher than parameter No. PB27 setting

(5) Gain changing condition (parameter No. PB27)

When you selected "command frequency", "droop pulses" or "servo motor speed" in gain changing selection (parameter No. PB26), set the gain changing level.

The setting unit is as follows:

Gain changing condition	Unit
Command frequency	kpps
Droop pulses	pulse
Servo motor speed	r/min

(6) Gain changing time constant (parameter No. PB28)

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

8. SPECIAL ADJUSTMENT FUNCTIONS

8.6.4 Gain changing operation

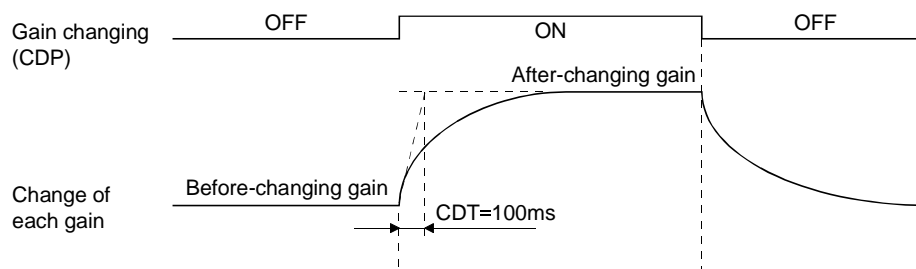
This operation will be described by way of setting examples.

(1) When you choose changing by external input

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB07	PG1	Model loop gain	100	rad/s
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	times
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	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	times
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0001 (Changed by ON/OFF of Input signal)	
PB28	CDT	Gain changing time constant	100	ms
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	Used to set the value of the after-changing vibration suppression control vibration frequency setting.	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	Used to set the value of the after-changing vibration suppression control resonance frequency setting.	Hz

(b) Changing operation



Model loop gain 1	100		
Ratio of load inertia moment to servo motor inertia moment	4.0	→	10.0 → 4.0
Position loop gain	120	→	84 → 120
Speed loop gain	3000	→	4000 → 3000
Speed integral compensation	20	→	50 → 20

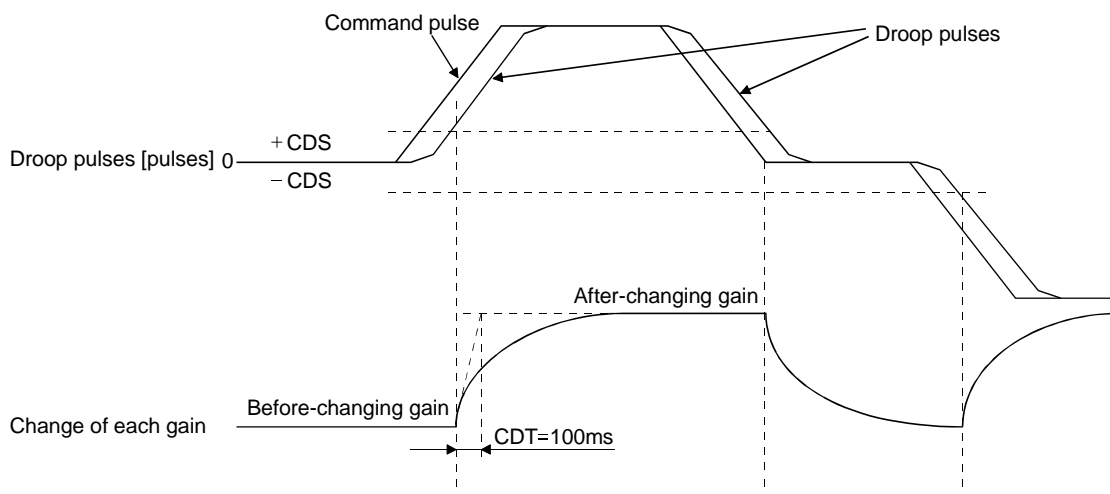
8. SPECIAL ADJUSTMENT FUNCTIONS

(2) When you choose changing by droop pulses

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB07	PG1	Model loop gain	100	rad/s
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	times
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain 2	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	times
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0003 (Changed by droop pulses)	
PB27	CDS	Gain changing condition	50	pulse
PB28	CDT	Gain changing time constant	100	ms

(b) Changing operation



Model loop gain	100					
Ratio of load inertia moment to servo motor inertia moment	4.0	→	10.0	→	4.0	→ 10.0
Position loop gain	120	→	84	→	120	→ 84
Speed loop gain	3000	→	4000	→	3000	→ 4000
Speed integral compensation	20	→	50	→	20	→ 50

[illegible]

9. TROUBLESHOOTING

9. TROUBLESHOOTING

POINT
<ul style="list-style-type: none"> Configure up a circuit which will detect the trouble (ALM) and turn off the servo-on (SON) at occurrence of an alarm.

If an alarm/warning has occurred, refer to this chapter and remove its cause.

9.1 Alarms and warning list

When a fault occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to Section 9.2 or 9.3 and take the appropriate action. When an alarm occurs, ALM turns off. Set "□□□1" in parameter No.PD24 to output the alarm code is outputted by ON/OFF of bit0 to bit2. Warnings (AL.92 to AL.EA) have no alarm codes. Any alarm code is output at occurrence of the corresponding alarm. In the normal status, the alarm code is not output.

After its cause has been removed, the alarm can be deactivated in any of the methods marked ○ in the alarm deactivation column.

	Display	(Note 2) Alarm code			Name	Alarm deactivation		
		CN1 22 (bit2)	CN1 23 (bit1)	CN1 24 (bit0)		Power OFF→ON	Press "SET" on current alarm screen.	Alarm reset (RES)
Alarms	AL.10	0	1	0	Undervoltage	○	○	○
	AL.12	0	0	0	Memory error1 (RAM)	○		
	AL.13	0	0	0	Clock error	○		
	AL.15	0	0	0	Memory error2 (EEP-ROM)	○		
	AL.16	1	1	0	Encoder error1 (At power on)	○		
	AL.17	0	0	0	Board error	○		
	AL.19	0	0	0	Memory error3 (Flash-ROM)	○		
	AL.1A	1	1	0	Motor combination error	○		
	AL.20	1	1	0	Encoder error2	○		
	AL.24	1	0	0	Main circuit error	○	○	○
	AL.25	1	1	0	Absolute position erase	○		
	AL.30	0	0	1	Regenerative error	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.31	1	0	1	Overspeed	○	○	○
	AL.32	1	0	0	Overcurrent	○	○	○
	AL.33	0	0	1	Overvoltage	○	○	○
	AL.35	1	0	1	Command pulse frequency alarm	○	○	○
	AL.37	0	0	0	Parameter error	○		
	AL.45	0	1	1	Main circuit device overheat	○	○	○
	AL.46	0	1	1	Servo motor overheat	○	○	○
	AL.47	0	1	1	Cooling fan alarm	○		
	AL.50	0	1	1	Overload1	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.51	0	1	1	Overload2	(Note 1) ○	(Note 1) ○	(Note 1) ○
	AL.52	1	0	1	Error excessive	○	○	○
	AL.8A	0	0	0	Serial communication time-out	○	○	○
	AL.8E	0	0	0	Serial communication error	○	○	○
	88888				Watchdog	○		
Warnings	AL.92				Open battery cable warning			
	AL.96				Home position setting error			
	AL.99				Stoke limit warning			
	AL.9F				Battery warning			
	AL.E0				Excessive regeneration warning			
	AL.E1				Overload warning 1			
	AL.E3				Absolute position counter warning			
	AL.E5				ABS time-out warning			
	AL.E6				Servo emergency stop warning			
	AL.E8				Cooling fan speed reduction warning			
	AL.E9				Main circuit off warning			
	AL.EA				ABS servo on warning			
	AL.EC				Overload warning 2			
	AL.ED				Output watt excess warning			

Note 1. Deactivate the alarm about 30 minutes of cooling time after removing the cause of occurrence.

2. 0: off

1: on

9. TROUBLESHOOTING

9.2 Remedies for alarms



CAUTION

- When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur.
- If an absolute position erase (AL.25) occurred, always make home position setting again. Otherwise, misoperation may occur.
- As soon as an alarm occurs, turn off Servo-on (SON) and power off the main circuit and control circuit.

POINT

- When any of the following alarms has occurred, do not deactivate the alarm and resume operation repeatedly. To do so will cause the servo amplifier/servo motor to fail. Remove the cause of occurrence, and leave a cooling time of more than 30 minutes before resuming operation.
 - Regenerative error (AL.30)
 - Overload 1 (AL.50)
 - Overload 2 (AL.51)
- The alarm can be deactivated by switching power off, then on press the "SET" button on the current alarm screen or by turning on the reset (RES). For details, refer to Section 10.2.1.

When an alarm occurs, the trouble (ALM) switches off and the dynamic brake is operated to stop the servomotor. At this time, the display indicates the alarm No.

The servo motor comes to a stop. Remove the cause of the alarm in accordance with this section. The optional servo configuration software may be used to refer to the cause.

Display	Name	Definition	Cause	Action
AL.10	Undervoltage	Power supply voltage dropped. MR-J3-□A: 160VAC or less MR-J3-□A1: 83VAC or less	1. Power supply voltage is low.	Review the power supply.
			2. There was an instantaneous control power failure of 60ms or longer.	
			3. Shortage of power supply capacity caused the power supply voltage to drop at start, etc.	
			4. The bus voltage dropped to the following value or less. MR-J3-□A: 200VDC MR-J3-□A1: 158VDC	
			5. Faulty parts in the servo amplifier <div style="border: 1px solid black; padding: 5px; margin-top: 5px;"> Checking method Alarm (AL.10) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables. </div>	Change the servo amplifier.
AL.12	Memory error 1 (RAM)	RAM, memory fault	Faulty parts in the servo amplifier <div style="border: 1px solid black; padding: 5px; margin-top: 5px;"> Checking method Alarm (any of AL.11 and AL.13) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables. </div>	Change the servo amplifier.
AL.13	Clock error	Printed board fault		

9. TROUBLESHOOTING

Display	Name	Definition	Cause	Action
AL.15	Memory error 2 (EEP-ROM)	EEP-ROM fault	<div> 1. Faulty parts in the servo amplifier <div> Checking method Alarm (AL.15) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables. </div> </div> 2. The number of write times to EEPROM exceeded 100,000.	Change the servo amplifier.
AL.16	Encoder error 1 (At power on)	Communication error occurred between encoder and servo amplifier.	1. Encoder connector (CN2) disconnected. 2. Encoder fault 3. Encoder cable faulty (Wire breakage or shorted) 4. Encoder cable type (2-wire, 4-wire) selection was wrong in parameter setting.	Connect correctly. Change the servo motor. Repair or change cable. Correct the setting in the fourth digit of parameter No. PC22.
AL.17	Board error 2	CPU/parts fault	Faulty parts in the servo amplifier	Change the servo amplifier.
AL.19	Memory error 3 (Flash ROM)	ROM memory fault	<div> Checking method Alarm (AL.17 or AL.19) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable. </div>	
AL.1A	Motor combination error	Wrong combination of servo amplifier and servo motor.	Wrong combination of servo amplifier and servo motor connected.	Use correct combination.
AL.20	Encoder error 2	Communication error occurred between encoder and servo amplifier.	1. Encoder connector (CN2) disconnected. 2. Encoder cable faulty (Wire breakage or shorted) 3. Encoder fault	Connect correctly. Repair or change the cable. Change the servo motor.
AL.24	Main circuit error	Ground fault occurred at the servo motor power (U,V and W phases) of the servo amplifier.	1. Power input wires and servo motor power wires are in contact. 2. Sheathes of servo motor power cables deteriorated, resulting in ground fault. 3. Main circuit of servo amplifier failed. <div> Checking method AL.24 occurs if the servo is switched on after disconnecting the U, V, W power cables from the servo amplifier. </div>	Connect correctly. Change the cable. Change the servo amplifier.
AL.25	Absolute position erase	Absolute position data in error Power was switched on for the first time in the absolute position detection system.	1. Voltage drop in encoder (Battery disconnected.) 2. Battery voltage low 3. Battery cable or battery is faulty. 4. Home position not set.	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again. Change battery. Always make home position setting again. After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.

9. TROUBLESHOOTING

Display	Name	Definition	Cause	Action
AL.30	Regenerative alarm	Permissible regenerative power of the built-in regenerative brake resistor or regenerative brake option is exceeded.	1. Wrong setting of parameter No. PA02	Set correctly.
			2. Built-in regenerative brake resistor or regenerative brake option is not connected.	Connect correctly
			3. High-duty operation or continuous regenerative operation caused the permissible regenerative power of the regenerative brake option to be exceeded. <div>Checking method Call the status display and check the regenerative load ratio.</div>	1. Reduce the frequency of positioning. 2. Use the regenerative brake option of larger capacity. 3. Reduce the load.
			4. Power supply voltage is abnormal. MR-J3-□A:260VAC or more MR-J3-□A1:More than 135VAC	Review power supply
			5. Built-in regenerative brake resistor or regenerative brake option faulty.	Change servo amplifier or regenerative brake option.
		Regenerative transistor fault	6. Regenerative transistor faulty. <div>Checking method 1) The regenerative brake option has overheated abnormally. 2) The alarm occurs even after removal of the built-in regenerative brake resistor or regenerative brake option.</div>	Change the servo amplifier.
AL.31	Overspeed	Speed has exceeded the instantaneous permissible speed.	1. Input command pulse frequency exceeded the permissible instantaneous speed frequency.	Set command pulses correctly.
			2. Small acceleration/deceleration time constant caused overshoot to be large.	Increase acceleration/deceleration time constant.
			3. Servo system is instable to cause overshoot.	1. Re-set servo gain to proper value. 2. If servo gain cannot be set to proper value: 1) Reduce load inertia moment ratio; or 2) Reexamine acceleration/ deceleration time constant.
			4. Electronic gear ratio is large (parameters No. PA06, PA07)	Set correctly.
			5. Encoder faulty.	Change the servo motor.
AL.32	Overcurrent	Current that flew is higher than the permissible current of the servo amplifier.	1. Short occurred in servo motor power (U, V, W).	Correct the wiring.
			2. Transistor (IPM) of the servo amplifier faulty. <div>Checking method Alarm (AL.32) occurs if power is switched on after U,V and W are disconnected.</div>	Change the servo amplifier.
			3. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
			4. External noise caused the overcurrent detection circuit to misoperate.	Take noise suppression measures.

9. TROUBLESHOOTING

Display	Name	Definition	Cause	Action
AL.33	Overvoltage	Converter bus voltage exceeded 400VDC.	1. Lead of built-in regenerative brake resistor or regenerative brake option is open or disconnected.	1. Change lead. 2. Connect correctly.
			2. Regenerative transistor faulty.	Change servo amplifier
			3. Wire breakage of built-in regenerative brake resistor or regenerative brake option	1. For wire breakage of built-in regenerative brake resistor, change servo amplifier. 2. For wire breakage of regenerative brake option, change regenerative brake option.
			4. Capacity of built-in regenerative brake resistor or regenerative brake option is insufficient.	Add regenerative brake option or increase capacity.
			5. Power supply voltage high.	Review the power supply.
			6. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
AL.35	Command pulse frequency error	Input pulse frequency of the command pulse is too high.	1. Pulse frequency of the command pulse is too high.	Change the command pulse frequency to a proper value.
			2. Noise entered command pulses.	Take action against noise.
			3. Command device failure	Change the command device.
AL.37	Parameter error	Parameter setting is wrong.	1. Servo amplifier fault caused the parameter setting to be rewritten.	Change the servo amplifier.
			2. Regenerative brake option not used with servo amplifier was selected in parameter No.PA02.	Set parameter No.PA02 correctly.
			3. The number of write times to EEPROM exceeded 100,000 due to parameter write, etc.	Change the servo amplifier.
AL.45	Main circuit device overheat	Main circuit device overheat	1. Servo amplifier faulty.	Change the servo amplifier.
			2. The power supply was turned on and off continuously by overloaded status.	The drive method is reviewed.
			3. Air cooling fan of servo amplifier stops.	1. Exchange the cooling fan or the servo amplifier. 2. Reduce ambient temperature.
			4. Used beyond the specifications of close mounting.	Use within the range of specifications.
AL.46	Servo motor overheat	Servo motor temperature rise actuated the thermal protector.	1. Ambient temperature of servo motor is over 40°C.	Review environment so that ambient temperature is 0 to 40°C.
			2. Servo motor is overloaded.	1. Reduce load. 2. Review operation pattern. 3. Use servo motor that provides larger output.
			3. Thermal protector in encoder is faulty.	Change servo motor.
AL.47	Cooling fan alarm	The cooling fan of the servo amplifier stopped, or its speed decreased to or below the alarm level.	Cooling fan life expiration (Refer to Section 2.5.)	Change the cooling fan of the servo amplifier.
			Foreign matter caught in the fan stopped rotation.	Remove the foreign matter.
			The power supply of the cooling fan failed.	Change servo amplifier.

9. TROUBLESHOOTING

Display	Name	Definition	Cause	Action
AL.50	Overload 1	Load exceeded overload protection characteristic of servo amplifier.	1. Servo amplifier is used in excess of its continuous output current.	1. Reduce load. 2. Review operation pattern. 3. Use servo motor that provides larger output.
			2. Servo system is instable and hunting.	1. Repeat acceleration/ deceleration to execute auto tuning. 2. Change auto tuning response setting. 3. Set auto tuning to OFF and make gain adjustment manually.
			3. Machine struck something.	1. Review operation pattern. 2. Install limit switches.
			4. Wrong connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.
			5. Encoder faulty. <div> <div>Checking method</div> <p>When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.</p> </div>	Change the servo motor.
AL.51	Overload 2	Machine collision or the like caused max. output current to flow successively for several seconds. Servo motor locked: 1s or more During rotation: 2.5s or more	1. Machine struck something.	1. Review operation pattern. 2. Install limit switches.
			2. Wrong connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.
			3. Servo system is instable and hunting.	1. Repeat acceleration/deceleration to execute auto tuning. 2. Change auto tuning response setting. 3. Set auto tuning to OFF and make gain adjustment manually.
			4. Encoder faulty. <div> <div>Checking method</div> <p>When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.</p> </div>	Change the servo motor.

9. TROUBLESHOOTING

Display	Name	Definition	Cause	Action
AL.52	Error excessive	The difference between the model position and the actual servomotor position exceeds three rotations. (Refer to the function block diagram in Section 1.2.)	1. Acceleration/deceleration time constant is too small.	Increase the acceleration/deceleration time constant.
			2. Forward torque limit (parameter No.PA11) or reverse torque limit (parameter No.PA12) are too small.	Increase the torque limit value.
			3. Motor cannot be started due to torque shortage caused by power supply voltage drop.	1. Review the power supply capacity. 2. Use servo motor which provides larger output.
			4. Model loop gain 1 (parameter No.PB07) value is small.	Increase set value and adjust to ensure proper operation.
			5. Servo motor shaft was rotated by external force.	1. When torque is limited, increase the limit value. 2. Reduce load. 3. Use servo motor that provides larger output.
			6. Machine struck something.	1. Review operation pattern. 2. Install limit switches.
			7. Encoder faulty	Change the servo motor.
			8. Wrong connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.
AL.8A	Serial communication time-out error	Communication stopped for longer than the specified time.	1. Communication cable breakage.	Repair or change communication cable
			2. Communication cycle longer than regulated time.	Shorten the communication cycle.
			3. Wrong protocol.	Correct protocol.
AL.8E	Serial communication error	Serial communication error occurred between servo amplifier and communication device (e.g. personal computer).	1. Communication cable fault (Open cable or short circuit)	Repair or change the cable.
			2. Communication device (e.g. personal computer) faulty	Change the communication device (e.g. personal computer).
(Note) 88888	Watchdog	CPU, parts faulty	Fault of parts in servo amplifier <div style="border: 1px solid black; padding: 5px; margin-top: 10px;"> Checking method Alarm (88888) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable. </div>	Change servo amplifier.

Note. At power-on, "88888" appears instantaneously, but it is not an error.

9.3 Remedies for warnings

If AL.E6 or AL.EA occurs, the servo off status is established. If any other warning occurs, operation can be continued but an alarm may take place or proper operation may not be performed. Use the optional servo configuration software to refer to the cause of warning.

Remove the cause of warning according to this section. Use the optional servo configuration software to refer to a factor of warning occurrence.

9. TROUBLESHOOTING

Display	Name	Definition	Cause	Action
AL.92	Open battery cable warning	Absolute position detection system battery voltage is low.	1. Battery cable is open. 2. Battery voltage dropped to 2.8V or less.	Repair cable or changed. Change battery.
AL.96	Home position setting warning	Home position setting could not be made.	1. Droop pulses remaining are greater than the in-position range setting. 2. Command pulse entered after clearing of droop pulses. 3. Creep speed high.	Remove the cause of droop pulse occurrence Do not enter command pulse after clearing of droop pulses. Reduce creep speed.
AL.99	Stroke limit warning	The stroke end (LSP or LSN) of the direction which gave instructions was turned off.	The limit switch became valid.	Reexamine the operation pattern to turn LSP/LSN ON.
AL.9F	Battery warning	Voltage of battery for absolute position detection system reduced.	Battery voltage fell to 3.2V or less.	Change the battery.
AL.E0	Excessive regenerative warning	There is a possibility that regenerative power may exceed permissible regenerative power of built-in regenerative brake resistor or regenerative brake option.	Regenerative power increased to 85% or more of permissible regenerative power of built-in regenerative brake resistor or regenerative brake option. Checking method Call the status display and check regenerative load ratio.	1. Reduce frequency of positioning. 2. Change regenerative brake option for the one with larger capacity. 3. Reduce load.
AL.E1	Overload warning 1	There is a possibility that overload alarm 1 or 2 may occur.	Load increased to 85% or more of overload alarm 1 or 2 occurrence level. Cause, checking method Refer to AL.50,51.	Refer to AL.50, AL.51.
AL.E3	Absolute position counter warning	Absolute position encoder pulses faulty.	1. Noise entered the encoder. 2. Encoder faulty.	Take noise suppression measures. Change servo motor.
AL.E5	ABS time-out warning		1. PC ladder program wrong. 2. Reverse rotation start (ST2) * Limiting torque (TLC) improper wiring	Contact the program. Connect properly.
AL.E6	Servo emergency stop warning	EMG is off.	External emergency stop was made valid. (EMG was turned off.)	Ensure safety and deactivate emergency stop.
AL.E8	Cooling fan speed reduction warning	The speed of the servo amplifier decreased to or below the warning level. This warning is not displayed with MR-J3-70A/100A among servo amplifiers equipped with a cooling fan.	Cooling fan life expiration (Refer to Section 2.5.) The power supply of the cooling fan is broken.	Change the cooling fan of the servo amplifier. Change servo amplifier.
AL.E9	Main circuit off warning	Servo-on (SON) was switched on with main circuit power off.		Switch on main circuit power.
AL.EA	ABS servo-on warning	Servo-on (SON) turned on more than 1s after servo amplifier had entered absolute position data transfer mode.	1. PC ladder program wrong. 2. Servo-on (SON) improper wiring.	1. Correct the program. 2. Connect properly.
AL.EC	Overload warning 2	Operation, in which a current exceeding the rating flew intensively in any of the U, V and W phases of the servo motor, was repeated.	During a stop, the status in which a current flew intensively in any of the U, V and W phases of the servo motor occurred repeatedly, exceeding the warning level.	1. Reduce the positioning frequency at the specific positioning address. 2. Reduce the load. 3. Replace the servo amplifier/ servo motor with the one of larger capacity.
AL.ED	Output watt excess warning	The status, in which the output wattage (speed × torque) of the servo motor exceeded the rated output, continued steadily.	Continuous operation was performed with the output wattage (speed × torque) of the servo motor exceeding 150% of the rated output.	1. Reduce the servo motor speed. 2. Reduce the load.

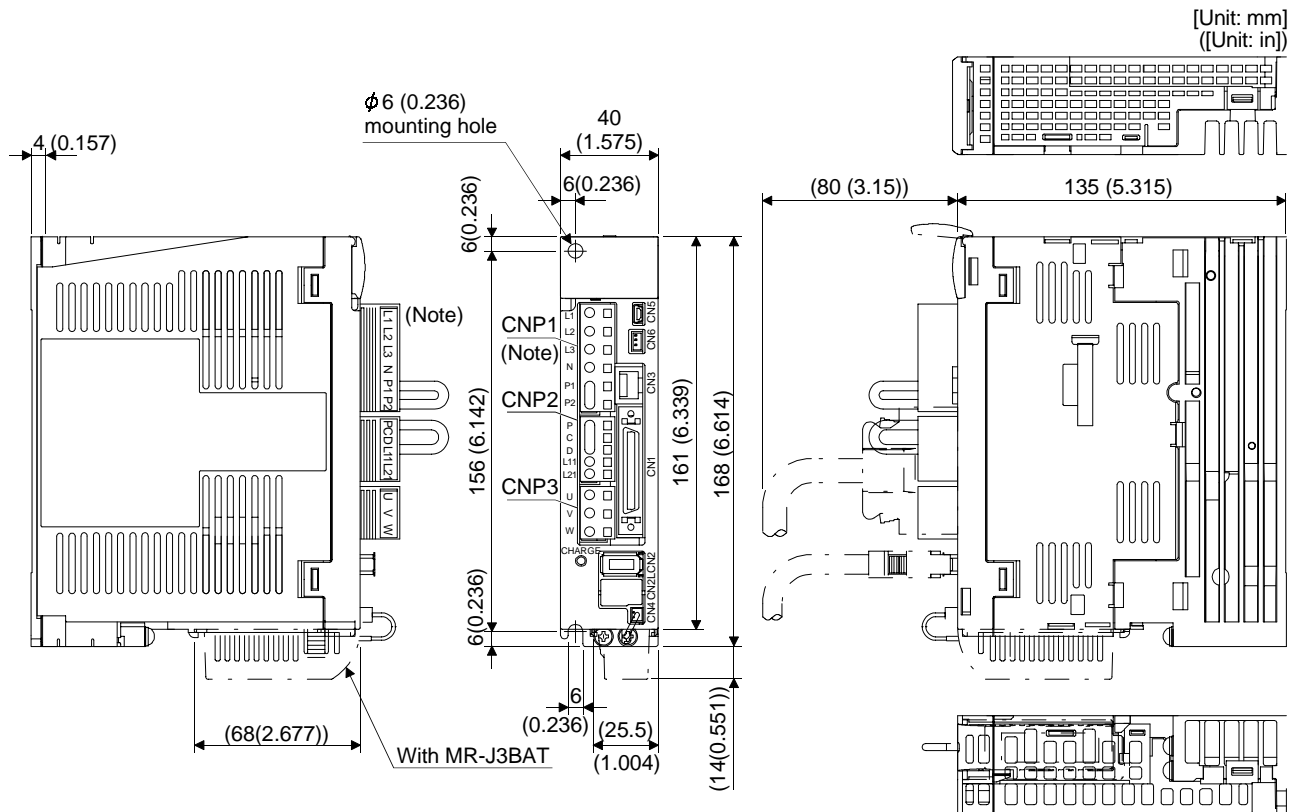
10. OUTLINE DRAWINGS

10. OUTLINE DRAWINGS

10.1 Servo Amplifier

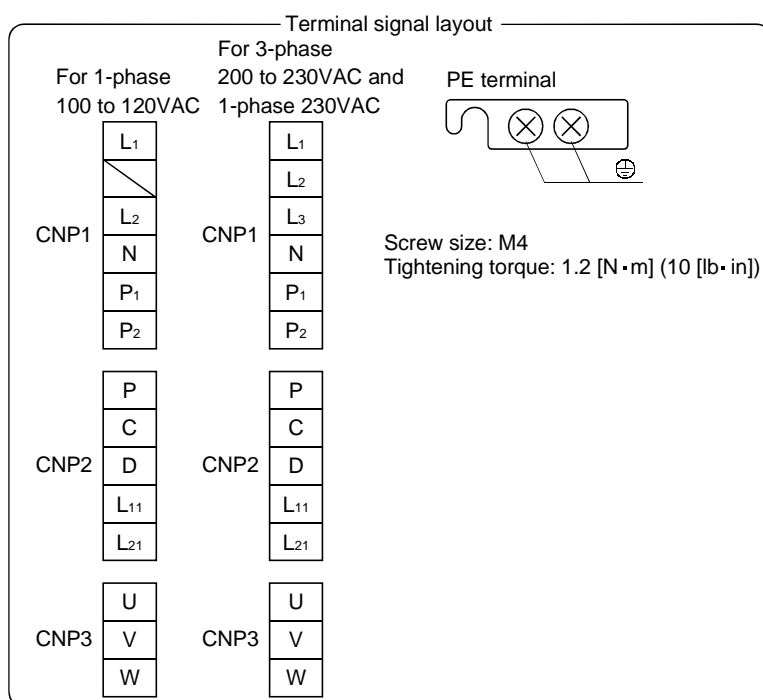
(1) MR-J3-10A • MR-J3-20A

MR-J3-10A1 • MR-J3-20A1



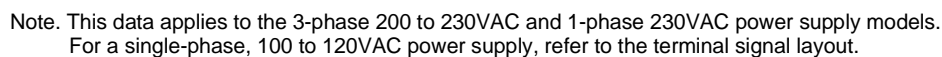
Note. This data applies to the 3-phase 200 to 230VAC and 1-phase 230VAC power supply models.
For a single-phase, 100 to 120VAC power supply, refer to the terminal signal layout.

Mass: 0.8 [kg] (1.764 [lb])

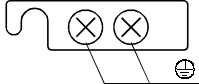


Mounting screw
Screw size: M5
Tightening torque: 3.24 [N·m] (28.676 [lb·in])

(2) MR-J3-40A ▪ MR-J3-60A
MR-J3-40A1



Terminal signal layout

For 1-phase 100 to 120VAC	For 3-phase 200 to 230VAC and 1-phase 230VAC	PE terminal
CNP1	CNP1	
CNP2	CNP2	
CNP3	CNP3	

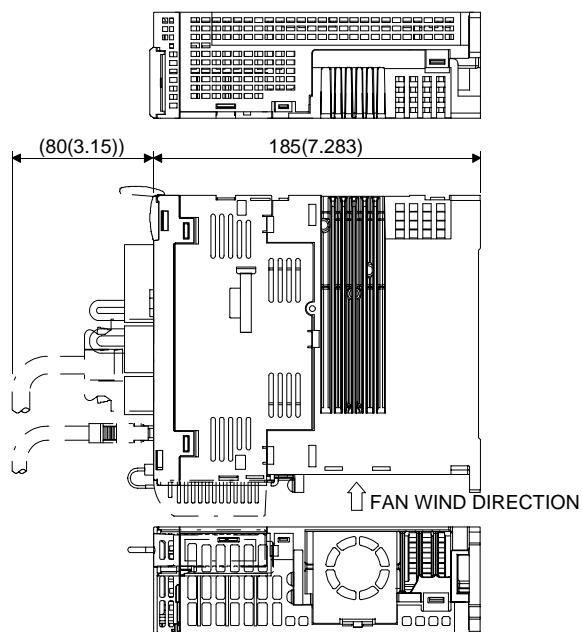
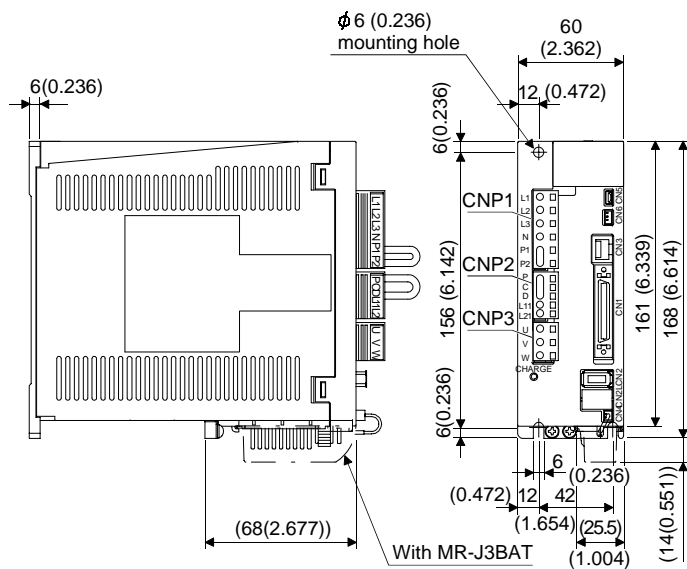
Screw size: M4
Tightening torque: 1.2 [N·m] (10 [lb·in])

10 - 2

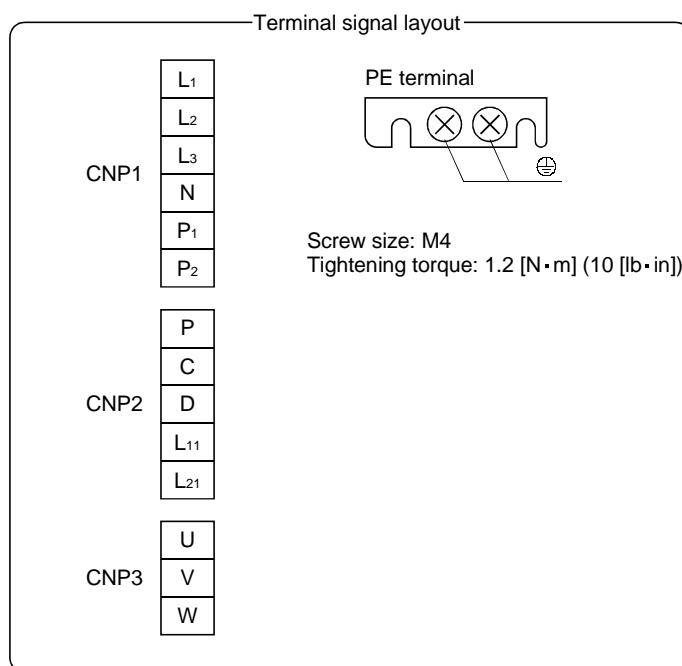
10. OUTLINE DRAWINGS

(3) MR-J3-70A • MR-J3-100A

[Unit: mm]
([Unit: in])



Mass: 1.4 [kg] (3.086 [lb])

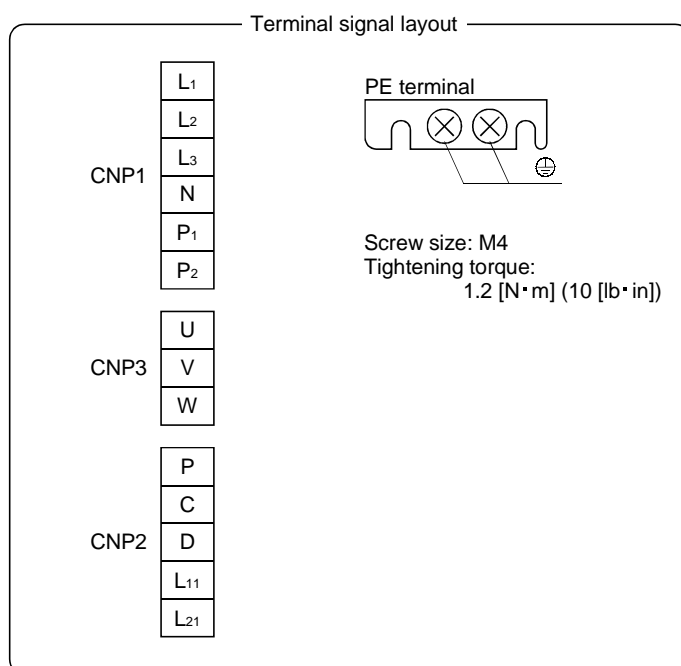
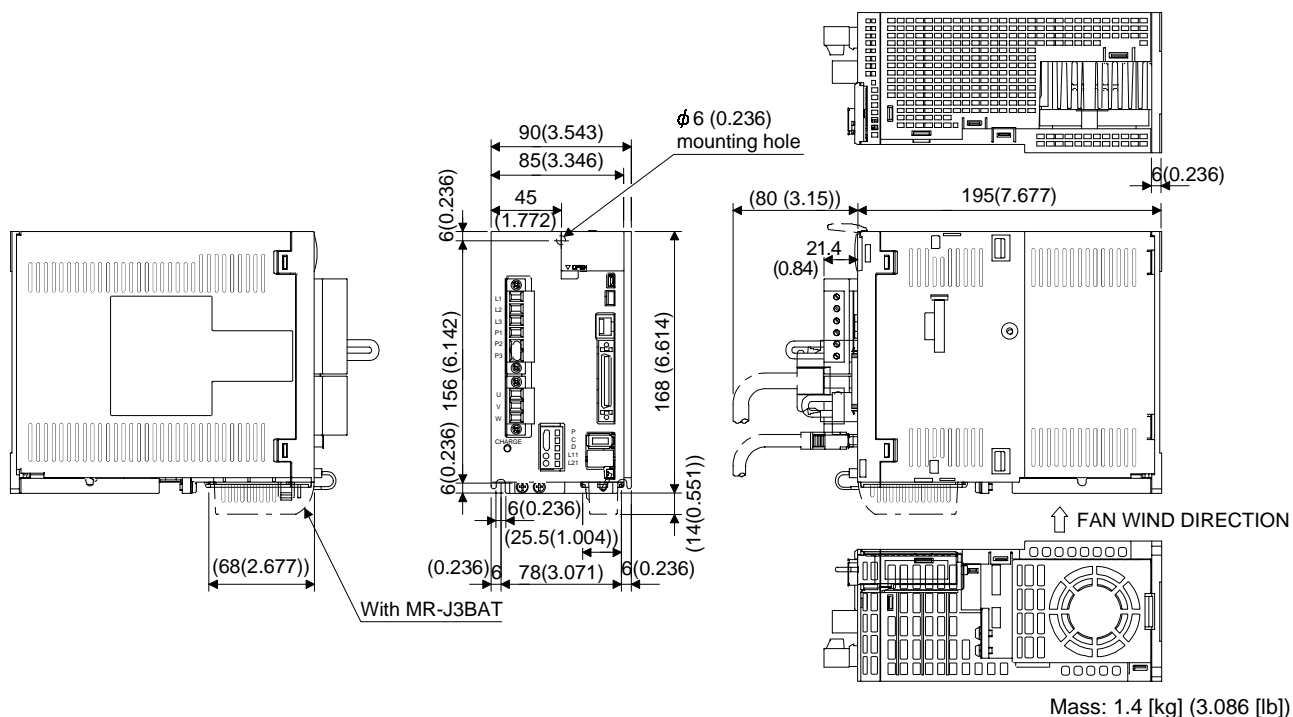


Mounting screw
Screw size: M5
Tightening torque: 3.24 [N·m] (28.676 [lb·in])

10. OUTLINE DRAWINGS

(4) MR-J3-200A • MR-J3-350A

[Unit: mm]
([Unit: in])



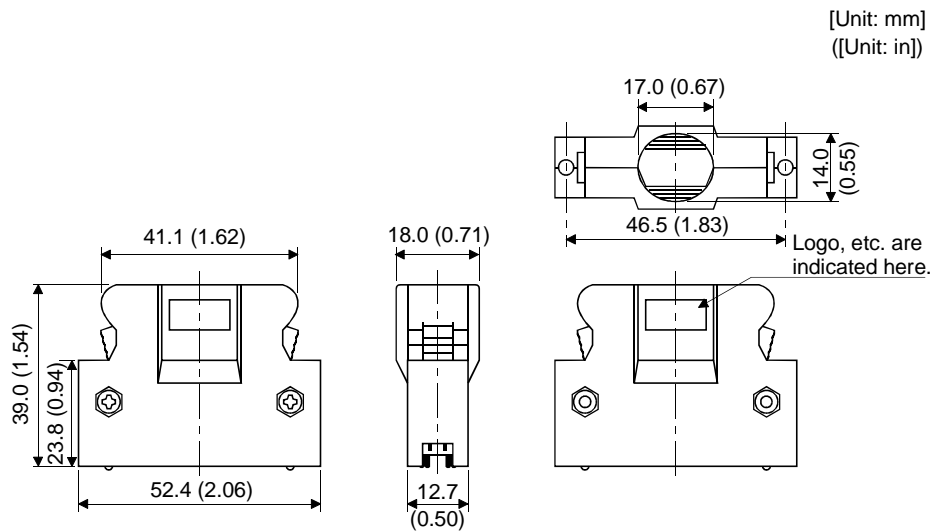
Mounting screw
Screw size: M5
Tightening torque:
3.24 [N·m] (28.676 [lb·in])

10. OUTLINE DRAWINGS

10.2 Connector (for CN1)

(1) Soldered type (3M)

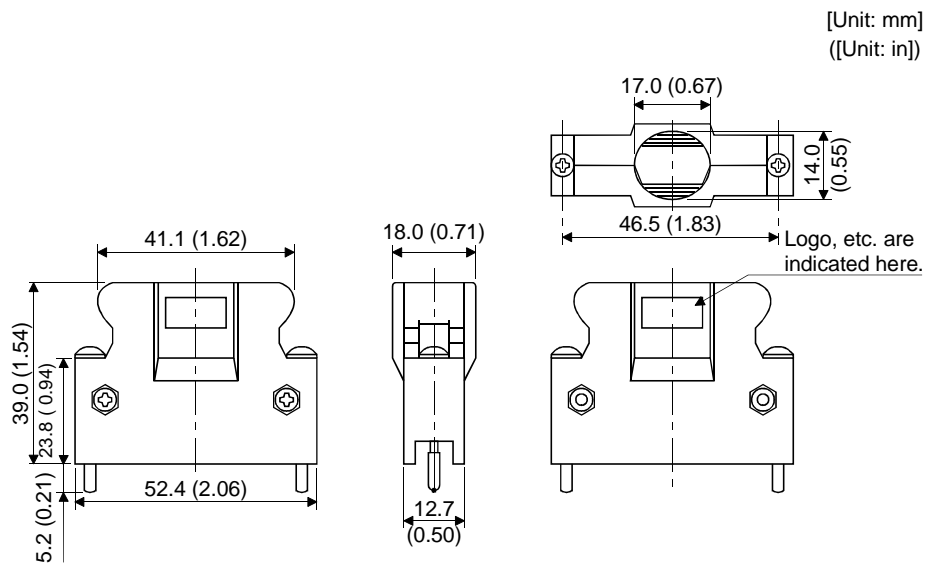
Model Connector : 10150-3000VE
Shell kit : 10350-52F0-008



(2) Threaded type (3M)

Model Connector : 10150-3000VE
Shell kit : 10350-52A0-008

Note. This is not available as option and should be user-prepared.

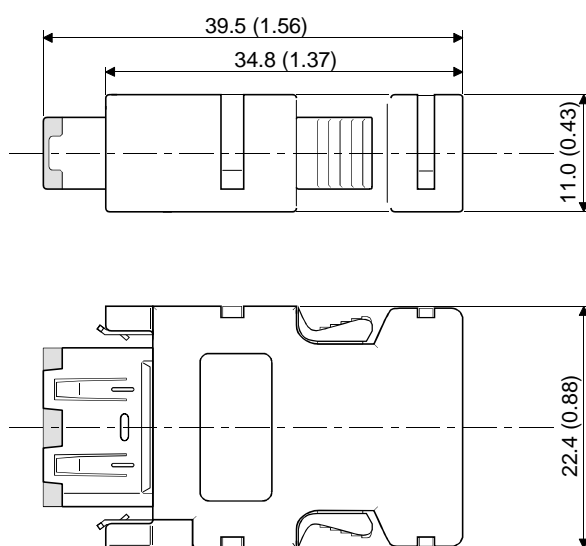


10. OUTLINE DRAWINGS

(3) For CN2 connector (3M)

Receptacle: 36210-0100JL

Shell kit : 36310-3200-008



11. CHARACTERISTICS

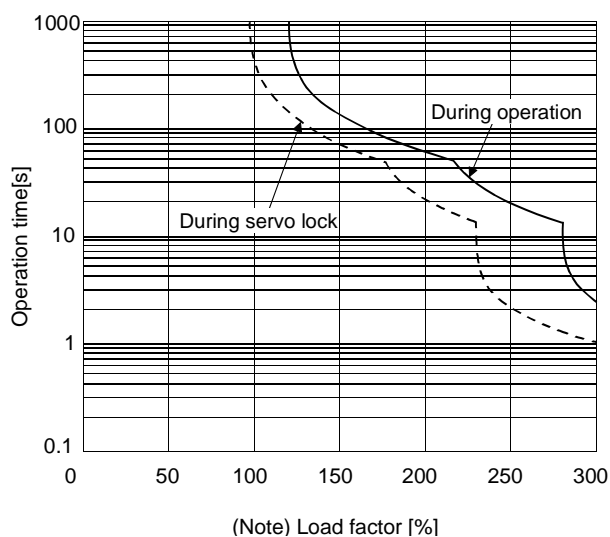
11. CHARACTERISTICS

11.1 Overload protection characteristics

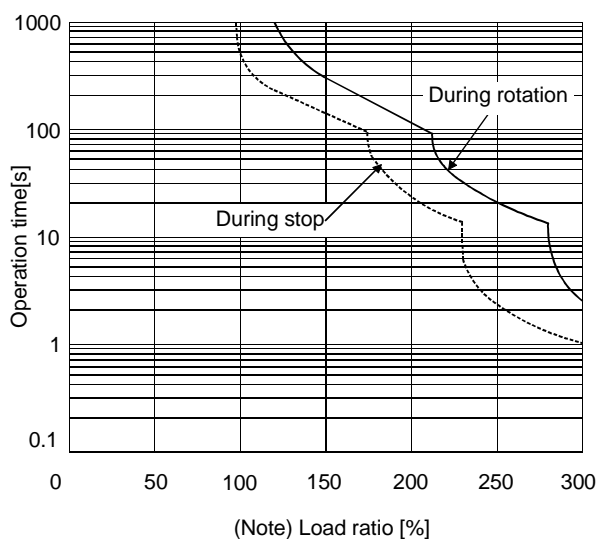
An electronic thermal relay is built in the servo amplifier to protect the servo motor and servo amplifier from overloads. Overload 1 alarm (AL.50) occurs if overload operation performed is above the electronic thermal relay protection curve shown in any of Figs 11.1. Overload 2 alarm (AL.51) occurs if the maximum current flow continuously for several seconds due to machine collision, etc. Use the equipment on the left-hand side area of the continuous or broken line in the graph.

In a machine like the one for vertical lift application where unbalanced torque will be produced, it is recommended to use the machine so that the unbalanced torque is 70% or less of the rated torque.

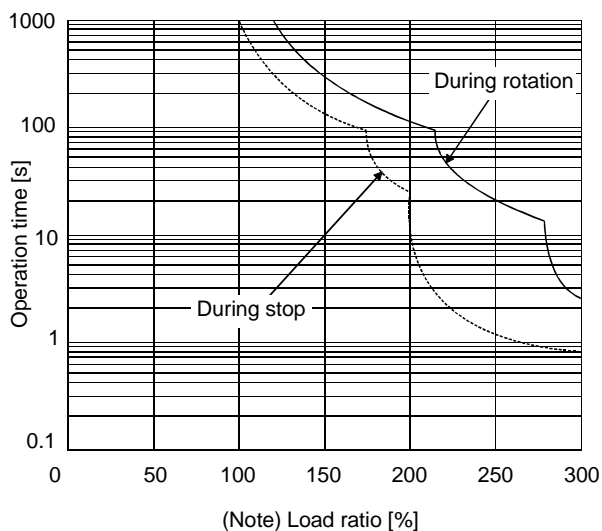
When you carry out adhesion mounting of the servo amplifier, make circumference temperature into 0 to 45°C, or use it at 75% or a smaller effective load ratio.



a. HF-KP053 · 13



b. HF-KP23 to 73
HF-SP52 · 102



c. HF-SP152 to 352

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 30r/min or less low-speed operation status, the servo amplifier may fail even when the electronic thermal relay protection is not activated.

Fig 11.1 Electronic thermal relay protection characteristics

11. CHARACTERISTICS

11.2 Power supply equipment capacity and generated loss

(1) Amount of heat generated by the servo amplifier

Table 11.1 indicates servo amplifiers' power supply capacities and losses generated under rated load. For thermal design of an enclosure, use the values in Table 11.1 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 maximum 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 11.1 Power supply capacity and generated heat per servo amplifier 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	
			At rated torque	With servo off	[m ²]	[ft ²]
MR-J3-10A (1)	HF-KP053 • 13	0.3	25	15	0.5	5.4
MR-J3-20A (1)	HF-KP23	0.5	25	15	0.5	5.4
MR-J3-40A (1)	HF-KP43	0.9	35	15	0.7	7.5
MR-J3-60A	HF-SP52	1.0	40	15	0.8	8.6
MR-J3-70A	HF-KP73	1.3	50	15	1.0	10.8
MR-J3-100A	HF-SP102	1.7	50	15	1.0	10.8
MR-J3-200A	HF-SP152	2.5	90	20	1.8	19.8
	HF-SP202	3.5	90	20	1.8	19.8
MR-J3-350A	HF-SP352	5.5	130	20	2.7	29.1

Note 1. Note that the power supply capacity will vary according to the power supply impedance. This value assumes that the power factor improving 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 brake option, in Section 12.2.

11. CHARACTERISTICS

(2) Heat dissipation area for enclosed servo amplifier

The enclosed control box (hereafter called the control box) 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. (With a 5°C (41°F) safety margin, the system should operate within a maximum 55°C (131°F) limit.) The necessary enclosure heat dissipation area can be calculated by Equation 11.1:

$$A = \frac{P}{K \cdot \Delta T} \dots\dots\dots (11.1)$$

where, A : Heat dissipation area [m²]
P : Loss generated in the control box [W]
 ΔT : Difference between internal and ambient temperatures [°C]
K : Heat dissipation coefficient [5 to 6]

When calculating the heat dissipation area with Equation 11.1, assume that P is the sum of all losses generated in the enclosure. Refer to Table 11.1 for heat generated by the servo amplifier. "A" indicates the effective area for heat dissipation, but if the enclosure is directly installed on an insulated wall, that extra amount must be added to the enclosure's surface area.

The required heat dissipation area will vary with the conditions in the enclosure. If convection in the enclosure is poor and heat builds up, effective heat dissipation will not be possible. Therefore, arrangement of the equipment in the enclosure and the use of a fan should be considered.

Table 11.1 lists the enclosure dissipation area for each servo amplifier when the servo amplifier is operated at the ambient temperature of 40°C (104°F) under rated load.

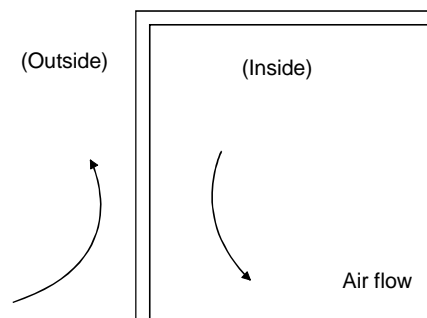


Fig. 11.2 Temperature distribution in enclosure

When air flows along the outer wall of the enclosure, effective heat exchange will be possible, because the temperature slope inside and outside the enclosure will be steeper.

11. CHARACTERISTICS

11.3 Dynamic brake characteristics

Fig. 11.3 shows the pattern in which the servo motor comes to a stop when the dynamic brake is operated. Use Equation 11.2 to calculate an approximate coasting distance to a stop. The dynamic brake time constant τ varies with the servo motor and machine operation speeds. (Refer to Fig. 11.4)

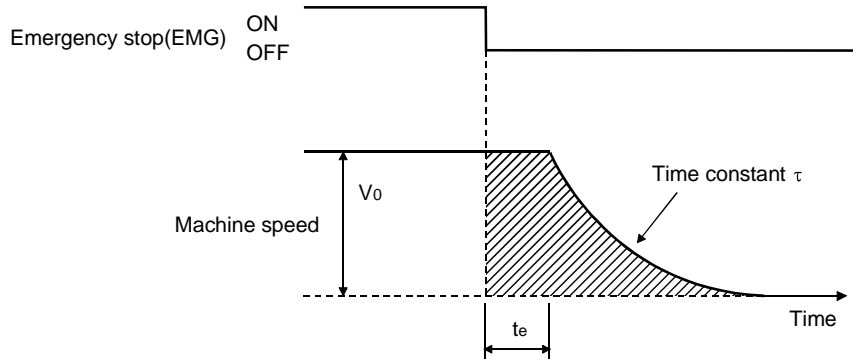
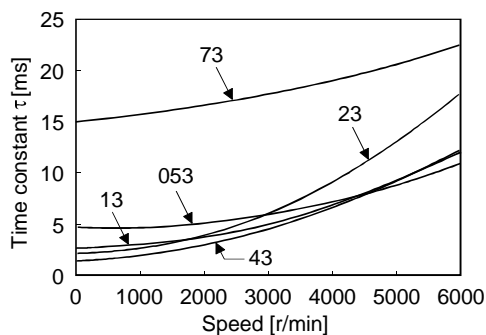


Fig. 11.3 Dynamic brake operation diagram

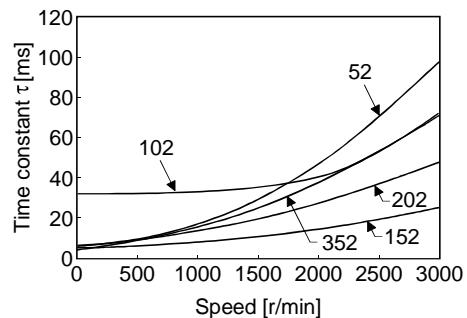
$$L_{\max} = \frac{V_0}{60} \cdot \left\{ t_e + \tau \left(1 + \frac{J_L}{J_M} \right) \right\} \quad (11.2)$$

L_{\max} : Maximum coasting distance [mm][in]
 V_0 : Machine rapid feedrate [mm/min][in/min]
 J_M : Servo motor inertial moment [kg · cm²][oz · in²]
 J_L : Load inertia moment converted into equivalent value on servo motor shaft [kg · cm²][oz · in²]
 τ : Brake time constant [s]
 t_e : Delay time of control section [s]

For 7kW or less servo, there is internal relay delay time of about 30ms. For 11kW to 22kW servo, there is delay time of about 100ms caused by a delay of the external relay and a delay of the magnetic contactor built in the external dynamic brake.



HF-KP series



HF-SP series

Fig. 11.4 Dynamic brake time constant

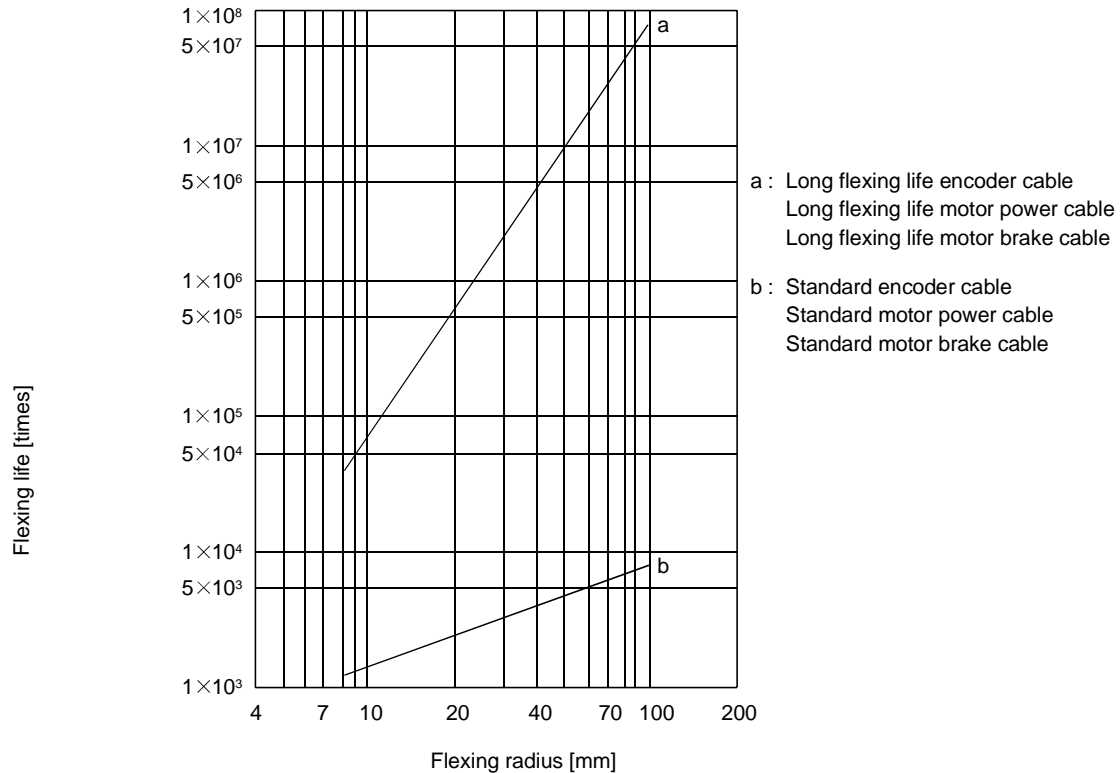
Use the dynamic brake at the load inertia moment indicated in the following table. If the load inertia moment is higher than this value, the built-in dynamic brake may burn. If there is a possibility that the load inertia moment may exceed the value, contact Mitsubishi.

Servo amplifier	Load inertia moment ratio [times]
MR-J3-10A (1)	30
MR-J3-20A (1)	
MR-J3-40A (1)	
MR-J3-60A	
MR-J3-70A	
MR-J3-100A	
MR-J3-200A	
MR-J3-350A	16

11. CHARACTERISTICS

11.4 Encoder cable flexing life

The flexing life of the cables is shown below. This graph calculated values. Since they are not guaranteed values, provide a little allowance for these values.



11.5 Inrush currents at power-on of main circuit and control circuit

The following table indicates the inrush currents (reference data) that will flow when the maximum permissible voltage (253VAC) is applied at the power supply capacity of 2500kVA and the wiring length of 1m (3.28ft).

Servo Amplifier	Inrush Currents (A_0 -p)	
	Main circuit power supply (L_1, L_2, L_3)	Control circuit power supply (L_{11}, L_{21})
MR-J3-10A to 60A	30A (Attenuated to approx. 5A in 10ms)	20 to 30A (Attenuated to approx. 0A in 1 to 2ms)
MR-J3-70A * 100A	54A (Attenuated to approx. 12A in 10ms)	
MR-J3-200A * 350A	120A (Attenuated to approx. 12A in 20ms)	
MR-J3-10A1 to 40A1	38A (Attenuated to approx. 14A in 10ms)	

Since large inrush currents flow in the power supplies, always use no-fuse breakers and magnetic contactors. (Refer to Section 12.7.)

When circuit protectors are used, it is recommended to use the inertia delay type that will not be tripped by an inrush current.

MEMO

[illegible]

12. OPTIONS AND AUXILIARY EQUIPMENT

12. OPTIONS AND AUXILIARY EQUIPMENT



WARNING

▪ Before connecting any option or auxiliary equipment, make sure that the charge lamp is off more than 10 minutes after power-off, then confirm the voltage with a tester or the like. Otherwise, you may get an electric shock.



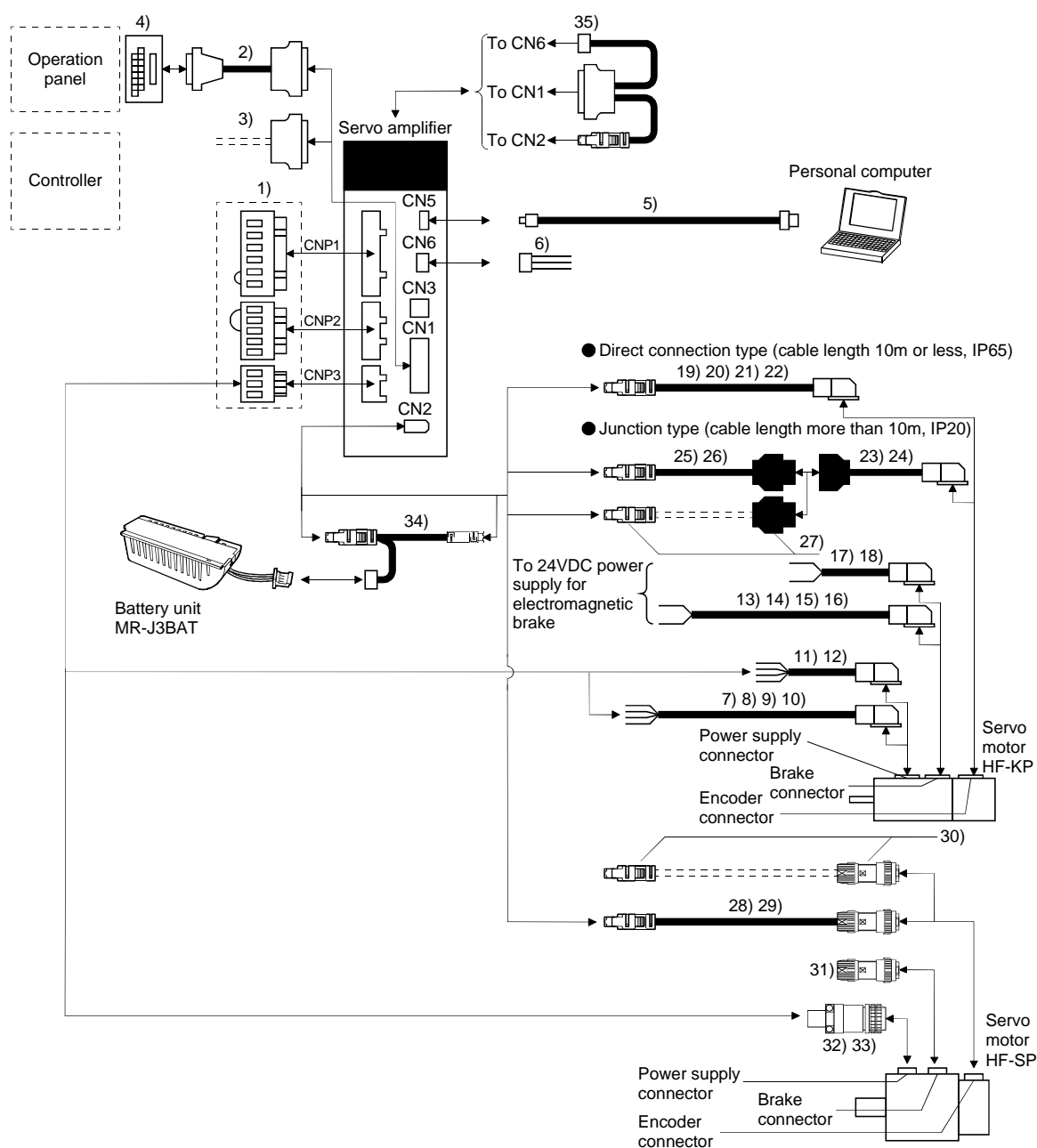
CAUTION

▪ Use the specified auxiliary equipment and options. Unspecified ones may lead to a fault or fire.

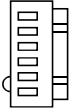


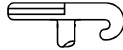



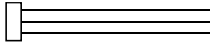
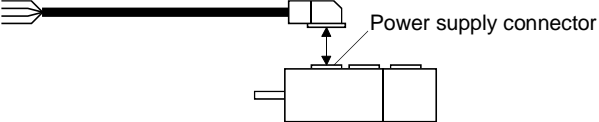
12.1 Cable/Connector Sets

As the cables and connectors used with this servo, purchase the options indicated in this section.

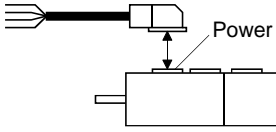
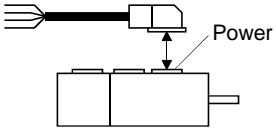
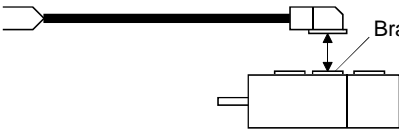
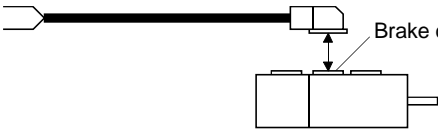
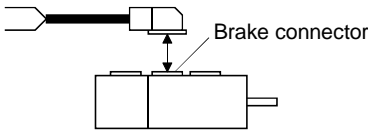
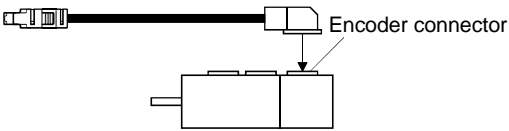
12.1.1 Combinations of cable/connector sets



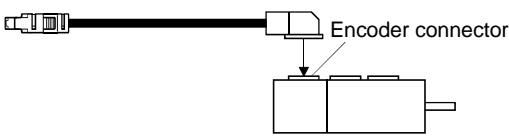
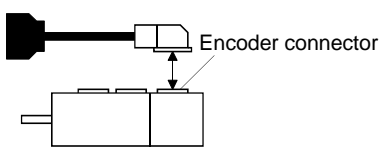





12. OPTIONS AND AUXILIARY EQUIPMENT

No.	Product	Model	Description	Application
1)	Servo amplifier power supply connector		   CNP1 connector: 54928-0610 (Molex) CNP2 connector: 54927-0510 (Molex) CNP3 connector: 54928-0310 (Molex) <Applicable cable example> Wire size: 0.14mm ² (AWG26) to 2.5mm ² (AWG14) Cable finish OD: to ϕ 3.8mm  REC. Lever: 54932-0000 (Molex)	Supplied with servo amplifier.
2)	Junction terminal block cable	MR-J2M-CN1TBL □ M Cable length: 0.5 · 1m (Refer to Section 12.3)	For junction terminal block connector Connector: D7950-B500FL (3M)  CN1 connector Connector: 10150-6000EL Shell kit: 10350-3210-000 (3M or equivalent)	For junction terminal block connection
3)	CN1 connector set	MR-J3CN1	Connector: 10150-3000VE Shell kit: 10350-52F0-008 (3M or equivalent) 	
4)	Junction terminal block cable	MR-TB50	Refer to Section 12.3.	
5)	USB cable	MR-J3USBCBL3M Cable length: 3m	For CN5 connector minB connector (5 pins)  For personal computer connector A connector	For connection with PC-AT compatible personal computer
6)	Monitoring cable	MR-J3CN6CBL1M Cable length: 1m	 CN6 connector Housing: 51004-0300 Terminal: 50011-8100 (Molex)	
7)	Motor power supply cable	MR-PWS1CBL □ M-A1-L Cable length: 2 · 5 · 10m	 Power supply connector Refer to Section 12.1.3 for details.	IP65 Load side lead
8)	Motor power supply cable	MR-PWS1CBL □ M-A1-H Cable length: 2 · 5 · 10m		IP65 Load side lead Long flex life
9)	Motor power supply cable	MR-PWS1CBL □ M-A2-L Cable length: 2 · 5 · 10m		IP65 Opposite-to-load side lead
10)	Motor power supply cable	MR-PWS1CBL □ M-A2-H Cable length: 2 · 5 · 10m		IP65 Opposite-to-load side lead Long flex life



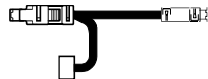
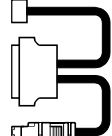
12. OPTIONS AND AUXILIARY EQUIPMENT

No.	Product	Model	Description	Application
11)	Motor power supply cable	MR-PWS2CBL03M-A1-L Cable length: 0.3m	 <p>Power supply connector</p> <p>Refer to Section 12.1.3 for details.</p>	IP55 Load side lead
12)	Motor power supply cable	MR-PWS2CBL03M-A2-L Cable length: 0.3m	 <p>Power supply connector</p> <p>Refer to Section 12.1.3 for details.</p>	IP55 Opposite-to-load side lead
13)	Motor brake cable	MR-BKS1CBL □ M-A1-L Cable length: 2 · 5 · 10m	 <p>Brake connector</p> <p>Refer to Section 12.1.4 for details.</p>	IP65 Load side lead
14)	Motor brake cable	MR-BKS1CBL □ M-A1-H Cable length: 2 · 5 · 10m		IP65 Load side lead Long flex life
15)	Motor brake cable	MR-BKS1CBL □ M-A2-L Cable length: 2 · 5 · 10m		IP65 Opposite-to-load side lead
16)	Motor brake cable	MR-BKS1CBL □ M-A2-H Cable length: 2 · 5 · 10m	 <p>Brake connector</p> <p>Refer to Section 12.1.4 for details.</p>	IP65 Opposite-to-load side lead Long flex life
17)	Motor brake cable	MR-BKS2CBL03M-A1-L Cable length: 0.3m		IP55 Load side lead
18)	Motor brake cable	MR-BKS2CBL03M-A2-L Cable length: 0.3m	 <p>Brake connector</p> <p>Refer to Section 12.1.4 for details.</p>	IP55 Opposite-to-load side lead
19)	Encoder cable	MR-J3ENCBL □ M-A1-L Cable length: 2 · 5 · 10m	 <p>Encoder connector</p> <p>Refer to Section 12.1.2 (1) for details.</p>	IP65 Load side lead
20)	Encoder cable	MR-J3ENCBL □ M-A1-H Cable length: 2 · 5 · 10m		IP65 Opposite-to-load side lead Long flex life

12. OPTIONS AND AUXILIARY EQUIPMENT

No.	Product	Model	Description	Application
21)	Encoder cable	MR-J3ENCBL □ M-A2-L Cable length: 2 • 5 • 10m	 Encoder connector	IP65 Opposite-to-load side lead
22)	Encoder cable	MR-J3ENCBL □ M-A2-H Cable length: 2 • 5 • 10m	Refer to Section 12.1.2 (1) for details.	IP65 Opposite-to-load side lead Long flex life
23)	Encoder cable	MR-J3JCBL03M-A1-L Cable length: 0.3m	 Encoder connector	IP20 Load side lead
24)	Encoder cable	MR-J3JCBL03M-A2-L Cable length: 0.3m	Refer to Section 12.1.2 (3) for details.	IP20 Opposite-to-load side lead
25)	Encoder cable	MR-EKCBL □ M-L Cable length: 20 • 30m	 Refer to Section 12.1.2 (2) for details.	IP20
26)	Encoder cable	MR-EKCBL □ M-H Cable length: 20 • 30 • 40 • 50m		IP20 Long flex life
27)	Encoder connector set	MR-ECNM	 Refer to Section 12.1.2 (2) for details.	IP20
28)	Encoder cable	MR-J3ENSCBL □ M-L Cable length: 2 • 5 • 10 • 20 • 30m	 Refer to Section 12.1.2 (4) for details.	IP67 Standard flex life
29)	Encoder cable	MR-J3ENSCBL □ M-H Cable length: 2 • 5 • 10 • 20 • 30 • 40 • 50m		IP67 Long flex linfe
30)	Encoder connector set	MR-J3CNS	 Refer to Section 12.1.2 (4) for details.	IP67
31)	Brake connector set	MR-BKCNS1	Straight plug: CM10-SP2S-L Socket contact: CM10-#22SC(S2)-100 (DDK) 	IP67

12. OPTIONS AND AUXILIARY EQUIPMENT

No.	Product	Model	Description	Application
32)	Power supply connector set	MR-PWCNS4 (For HF-SP52 • 102 • 152 motor)	Plug: CE05-6A18-10SD-B-BSS Cable clamp: CE3057-10A-1 (D265) (DDK) Example of applicable cable Wire size: 2mm ² (AWG14) to 3.5mm ² (AWG12) Cable finish ϕ D: ϕ 10.5 to 14.1mm 	IP67
33)	Power supply connector set	MR-PWCNS5 (For HF-SP202 • 352 motor)	Plug: CE05-6A22-22D-B-BSS Cable clamp: CE3057-12A-1 (D265) (DDK) Example of applicable cable Wire size: 5.5mm ² (AWG10) to 8mm ² (AWG8) Cable finish ϕ D: ϕ 12.5 to 16mm 	IP67
34)	Cable for connecting battery	MR-J3BTCBL03M	 <p>Refer to Section 12.1.2 (5) for details.</p>	For connection of battery
35)	Diagnosis cable	MR-J3ACHECK	 <p>Necessary for amplifier diagnosis function of MR-Configurator (Servo configuration software). Refer to Section 12.4 (4) (c) for details.</p>	For diagnosis of servo amplifier

12. OPTIONS AND AUXILIARY EQUIPMENT

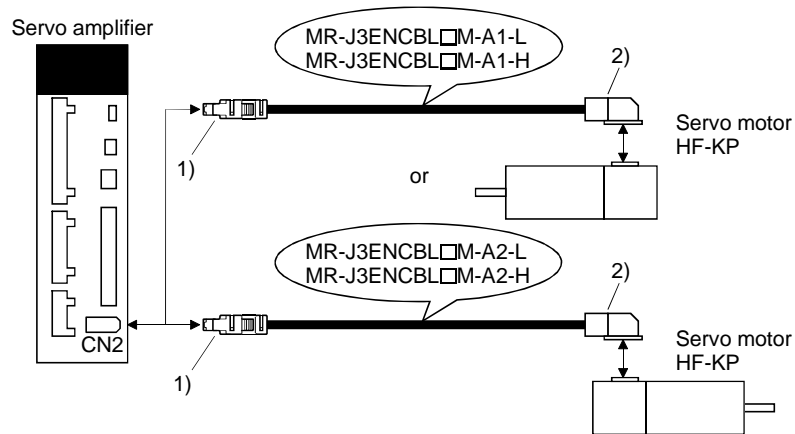
12.1.2 Encoder cable/connector sets

(1) MR-J3ENCBL □ M-A1-L/H • MR-J3ENCBL □ M-A2-L/H

These cables are encoder cables for the HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-J3ENCBL □ M-A1-L		2	5	10					IP65	Standard	For HF-KP servo motor
MR-J3ENCBL □ M-A1-H		2	5	10					IP65	Long flex	Load side lead
MR-J3ENCBL □ M-A2-L		2	5	10					IP65	Standard	For HF-KP servo motor
MR-J3ENCBL □ M-A2-H		2	5	10					IP65	Long flex	Opposite-to-load side lead

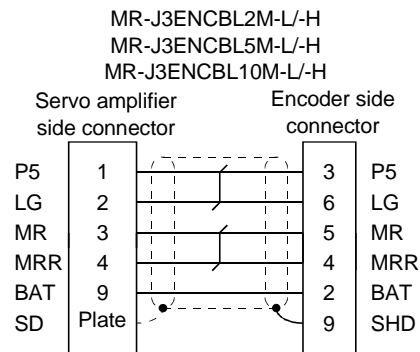
(a) Connection of servo amplifier and servo motor



Cable Model	1) For CN2 Connector	2) For Encoder Connector
MR-J3ENCBL □ M-A1-L	Receptacle: 36210-0100JL Shell kit: 536310-3200-008 (3M or equivalent)	Connector: 1674320-1
MR-J3ENCBL □ M-A1-H	(Note) Signal layout <p>View seen from wiring side.</p>	(Note) Signal layout <p>View seen from wiring side.</p>
MR-J3ENCBL □ M-A2-L	Note. Keep open the pins shown with . Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	Note. Keep open the pin shown with an .
MR-J3ENCBL □ M-A2-H		

12. OPTIONS AND AUXILIARY EQUIPMENT

(b) Cable internal wiring diagram



(2) MR-EKCBL □ M-L/H

POINT	
	<ul style="list-style-type: none"> The following encoder cables are of four-wire type. When using any of these encoder cables, set parameter No. PC22 to "1 □ □ □" to select the four-wire type. <p>MR-EKCBL30M-L MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H</p>

The servo amplifier and servo motor cannot be connected with these cables only. The servo motor side encoder cable (MR-J3JCBL03M-A1-L or MR-J3JCBL03M-A2-L) is required.

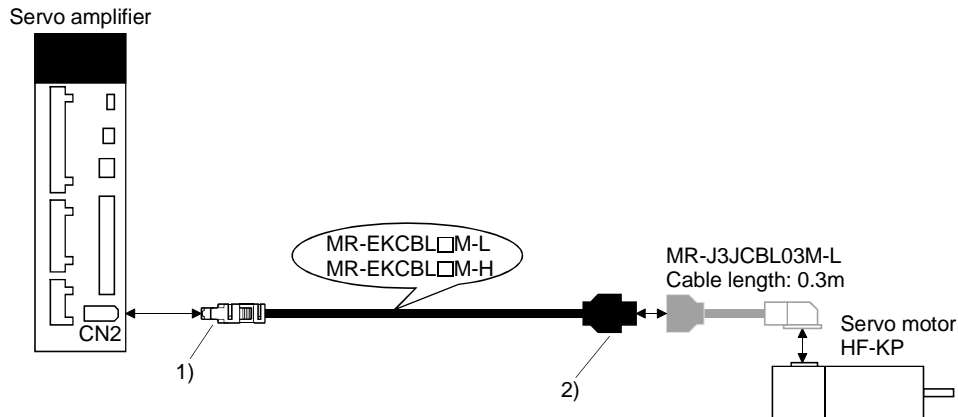
The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-EKCBL □ M-L					20	(Note) 30			IP20	Standard	For HF-KP servo motor Use in combination with MR-J3JCBL03M-A1-L or MR-J3JCBL03M-A2-L.
MR-EKCBL □ M-H					20	(Note) 30	(Note) 40	(Note) 50	IP20	Long flex	

Note. Four-wire type cable.

12. OPTIONS AND AUXILIARY EQUIPMENT

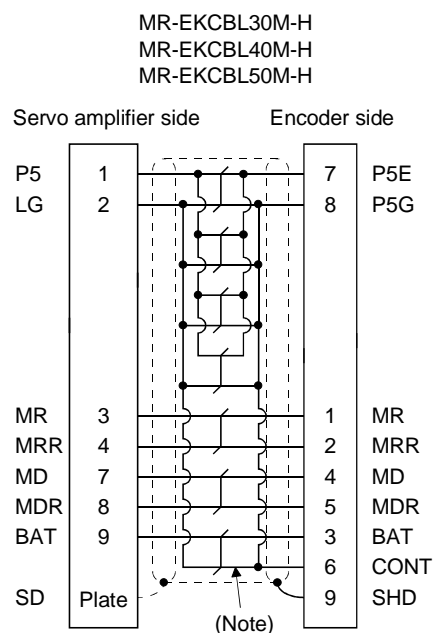
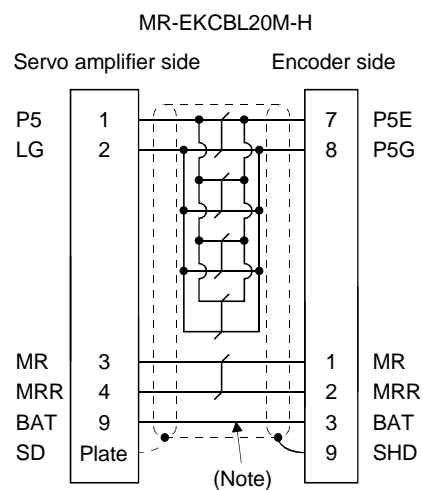
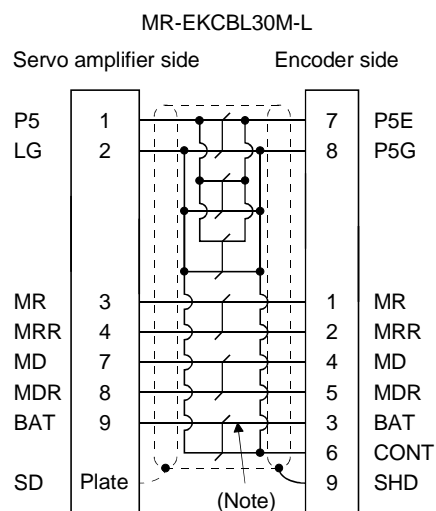
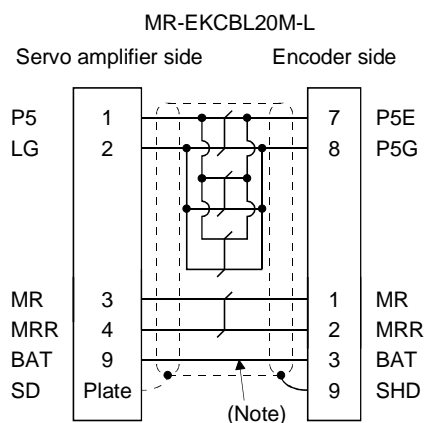
(a) Connection of servo amplifier and servo motor



Cable Model	1) CN2 Connector	2) Junction Connector																				
MR-EKCBL □ M-L	<div><div>(1) For soldering</div><div>Connector housing: 54593-1011</div><div>Cover A: 54594-1015</div><div>Cover B: 54595-1005</div><div>Shell cover: 58935-1000</div><div>Shell body: 58934-1000</div><div>Cable clamp: 58937-0000</div><div>Screw: 58203-0010</div><div>(Molex or equivalent)</div></div> <div><div>(2) For crimping</div><div>Connector housing: 51209-1001</div><div>Cover A: 54594-1015</div><div>Cover B: 54595-1005</div><div>Shell cover: 58935-1000</div><div>Shell body: 58934-1000</div><div>Terminal: 59351-8187</div><div>Cable clamp: 58937-0000</div><div>Screw: 58203-0010</div><div>(Molex or equivalent)</div></div>	<div>Housing: 1-172161-9</div> <div>Connector pin: 170359-1</div> <div>(AMP or equivalent)</div> <div>Cable clamp: MTI-0002</div> <div>(Toa Electric Industries)</div> <div><div>Signal layout</div><div><table><tr><td>1</td><td>2</td><td>3</td></tr><tr><td>MR</td><td>MRR</td><td>BAT</td></tr><tr><td>4</td><td>5</td><td>6</td></tr><tr><td>MD</td><td>MDR</td><td>CONT</td></tr><tr><td>7</td><td>8</td><td>9</td></tr><tr><td>P5</td><td>LG</td><td>SHD</td></tr></table></div></div> <div>View seen from wiring side.</div>	1	2	3	MR	MRR	BAT	4	5	6	MD	MDR	CONT	7	8	9	P5	LG	SHD		
1	2	3																				
MR	MRR	BAT																				
4	5	6																				
MD	MDR	CONT																				
7	8	9																				
P5	LG	SHD																				
MR-EKCBL □ M-H	<div><div>Signal layout</div><div><table><tr><td>2</td><td>4</td><td>6</td><td>8</td><td>10</td></tr><tr><td>LG</td><td>MRR</td><td></td><td>MDR</td><td></td></tr><tr><td>1</td><td>3</td><td>5</td><td>7</td><td>9</td></tr><tr><td>P5</td><td>MR</td><td></td><td>MD</td><td>BAT</td></tr></table></div></div> <div>View seen from wiring side.</div>	2	4	6	8	10	LG	MRR		MDR		1	3	5	7	9	P5	MR		MD	BAT	
2	4	6	8	10																		
LG	MRR		MDR																			
1	3	5	7	9																		
P5	MR		MD	BAT																		

12. OPTIONS AND AUXILIARY EQUIPMENT

(b) Internal wiring diagram



Note. Always make connection for use in an absolute position detection system. Wiring is not necessary for use in an incremental system.



When fabricating the cable, use the wiring diagram corresponding to the length indicated below.

Cable Flex Life	Applicable Wiring Diagram	
	Less than 10m	30m to 50m
Standard	MR-EKCBL20M-L	MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H
Long flex	MR-EKCBL20M-H	

12. OPTIONS AND AUXILIARY EQUIPMENT

(c) When fabricating the encoder cable

When fabricating the cable, prepare the following parts and tool, and fabricate it according to the wiring diagram in (b). Refer to Section 12.6 for the specifications of the used cable.

Parts/Tool	Description
Connector set	<div> <div>MR-ECNM</div> <div>For CN2 connector</div> <div>Connector housing: 54593-1011</div> <div>Cover A: 54594-1015</div> <div>Cover B: 54595-1005</div> <div>Shell cover: 58935-1000</div> <div>Shell body: 58934-1000</div> <div>Cable clamp: 58937-0000</div> <div>Screw: 58203-0010</div> <div>(Molex)</div> </div> <div> <div>Housing: 1-172161-9</div> <div>Connector pin: 170359-1</div> <div>(AMP or equivalent)</div> <div>Cable clamp: MTI-0002</div> <div>(Toa Electric Industries)</div> </div> <div>   </div>

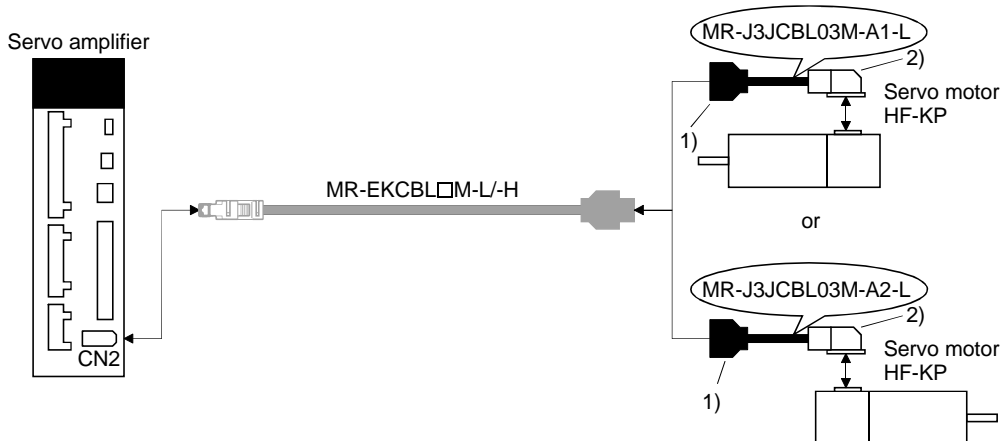
(3) MR-J3JCBL03M-A1-L · MR-J3JCLB03M-A2-L

The servo amplifier and servo motor cannot be connected with these cables only. The servo motor side encoder cable (MR-EKCBL □ M-L/H) is required.

Cable Model	Cable Length	Protective Structure	Flex Life	Application
MR-J3JCBL03M-A1-L	0.3m	IP20	Standard	For HF-KP servo motor Load side lead Use in combination with MR-EKCBL □ M-L/H.
MR-J3JCBL03M-A2-L				For HF-KP servo motor Opposite-to-load side lead Use in combination with MR-EKCBL □ M-L/H.

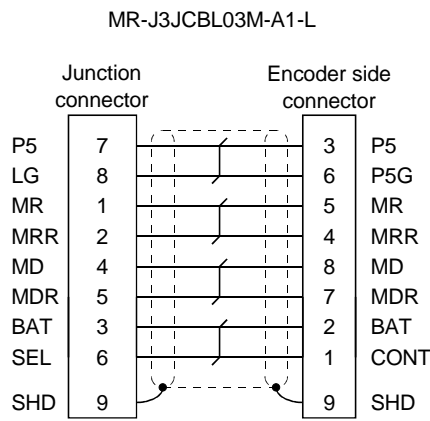
12. OPTIONS AND AUXILIARY EQUIPMENT

(a) Connection of servo amplifier and servo motor



Cable Model	1) Junction Connector	2) For Encoder Connector																																					
MR-J3JCBL03M-A1-L	<div>Housing: 1-172169-9</div> <div>Contact: 1473226-1</div> <div>Cable clamp: 316454-1</div> <div>(AMP)</div> <div><div>Signal layout</div><div><table><tr><td>3</td><td>2</td><td>1</td></tr><tr><td>BAT</td><td>MRR</td><td>MR</td></tr><tr><td>6</td><td>5</td><td>4</td></tr><tr><td>CONT</td><td>MDR</td><td>MD</td></tr><tr><td>9</td><td>8</td><td>7</td></tr><tr><td>SHD</td><td>LG</td><td>P5</td></tr></table></div><div>View seen from wiring side.</div></div>	3	2	1	BAT	MRR	MR	6	5	4	CONT	MDR	MD	9	8	7	SHD	LG	P5	<div>Connector: 1674320-1</div> <div>Crimping tool for ground clip: 1596970-1</div> <div>Crimping tool for receptacle contact: 1596847</div> <div>(AMP)</div> <div><div>Signal layout</div><div><table><tr><td>9</td><td>SHD</td><td></td></tr><tr><td>7</td><td>MDR</td><td>8</td><td>MD</td></tr><tr><td>5</td><td>MR</td><td>6</td><td>P5G</td></tr><tr><td>3</td><td>P5</td><td>4</td><td>MRR</td></tr><tr><td>1</td><td>CONT</td><td>2</td><td>BAT</td></tr></table></div><div>View seen from wiring</div></div>	9	SHD		7	MDR	8	MD	5	MR	6	P5G	3	P5	4	MRR	1	CONT	2	BAT
3	2	1																																					
BAT	MRR	MR																																					
6	5	4																																					
CONT	MDR	MD																																					
9	8	7																																					
SHD	LG	P5																																					
9	SHD																																						
7	MDR	8	MD																																				
5	MR	6	P5G																																				
3	P5	4	MRR																																				
1	CONT	2	BAT																																				
MR-J3JCBL03M-A2-L																																							

(b) Internal wiring diagram



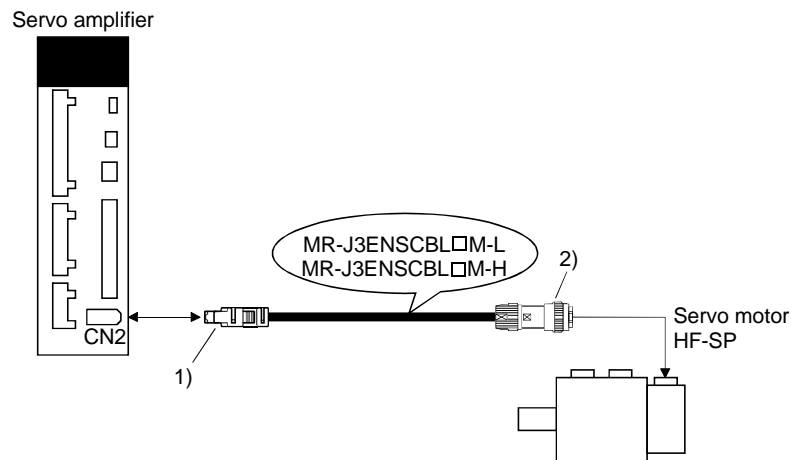
12. OPTIONS AND AUXILIARY EQUIPMENT

(4) MR-J3ENSCBL □ M-L • MR-J3ENSCBL □ M-H

These cables are detector cables for HF-SP Series servomotors. The number in the cable length column of the table indicates the symbol filling the square □ in the cable model. Cable lengths corresponding to the specified symbols are prepared.

Cable Model	Cable Length							Protective Structure	Flex Life	Application
	2m	5m	10m	20m	30m	40m	50m			
MR-J3ENSCBL □ M-L	2	5	10	20	30	40	50	IP67	Standard	For HF-SP servo motor
MR-J3ENSCBL □ M-H	2	5	10	20	30	40	50	IP67	Long flex	

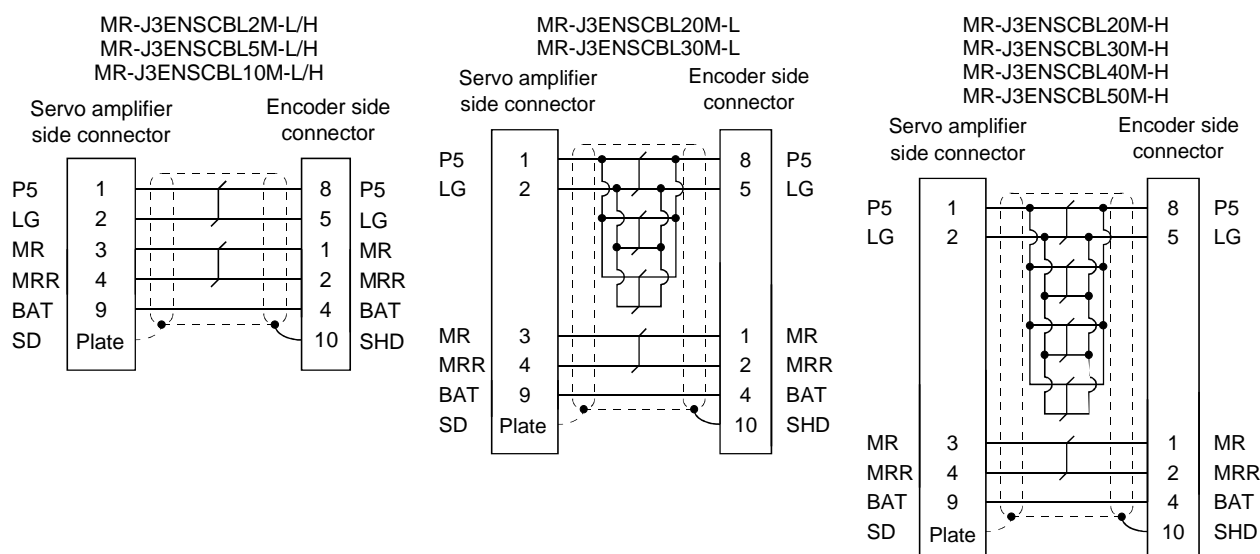
(a) Connection of servo amplifier and servo motor



Cable Model	1) For CN2 Connector	2) For Encoder Connector
MR-J3ENSCBL □ M-L	<p>Receptacle: 36210-0100JL Shell kit: 536310-3200-008 (3M or equivalent)</p> <p>(Note) Signal layout</p> <p>View seen from wiring side.</p>	<p>In case of 10m or shorter cables Straight plug: CM10-SP10S-M Socket contact: CM10-#22SC(C1)-100 Crimping tool: 357J-50446 (DDK) Applicable cable AWG20 to 22</p> <p>In case of 20m or longer cables Straight plug: CM10-SP10S-M Socket contact: CM10-#22SC(C2)-100 Crimping tool: 357J-50447 (DDK) Applicable cable AWG23 to 28</p>
MR-J3ENSCBL □ M-H	<p>Note. Keep open the pins shown with . Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.</p>	<p>(Note) Signal layout</p> <p>View seen from wiring side</p> <p>Note. Keep open the pin shown with an .</p>



12. OPTIONS AND AUXILIARY EQUIPMENT

(b) Internal wiring diagram



(c) When fabricating the encoder cable

When fabricating the cable, prepare the following parts and tool, and fabricate it according to the wiring diagram in (b). Refer to Section 12.6 for the specifications of the used cable.

Parts/Tool	Description
Connector set	<p>MR- J3SCNS (Option)</p> <p>Receptacle: 36210-0100JL</p> <p>Shell kit: 36310-3200-008 (3M)</p> <p>Straight plug: CM10-SP10S-M</p> <p>Socket contact: CM10-#22SC(S1)-100</p> <p>Applicable wire size: AWG20 or less (DDK)</p>
	 

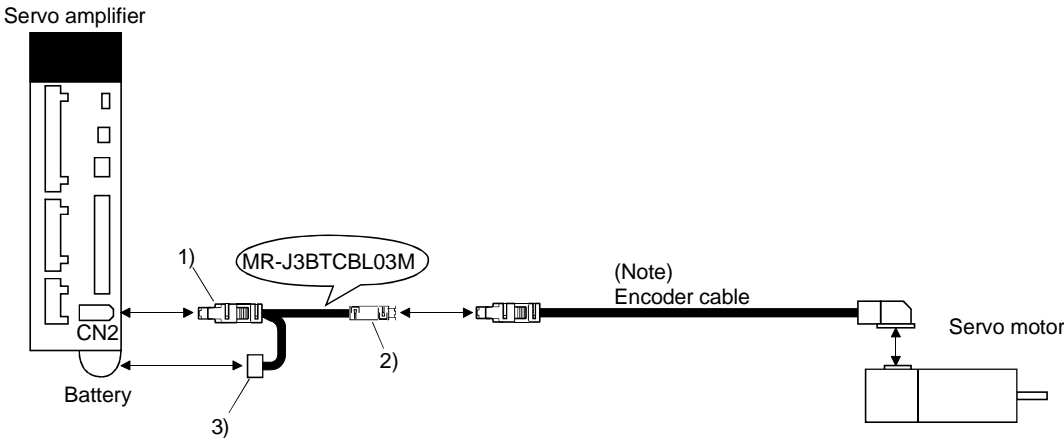
12. OPTIONS AND AUXILIARY EQUIPMENT

(5) MR-J3BTCBL03M

This cable is a battery connection cable. Use this cable to retain the current position even if the detector cable is disconnected from the servo amplifier.

Cable Model	Cable Length	Application
MR-J3BTCBL03M	0.3m	For HF-KP ▫ HF-SP servo motor

(a) Connection of servo amplifier and servo motor



Note. For the detector cable, refer to (1), (2), (3) and (4) in this section.

Cable Model	1) For CN2 Connector	1) Junction Connector	2) For Battery Connector
MR-J3BTCBL03M	Receptacle: 36210-0100JL Shell kit: 36310-3200-008 (3M or equivalent)	Plug: 36110-3000FD Shell kit: 36310-F200-008 (3M)	Connector: DF3-2EP-2C Contact: DF3-EP2428PCFA (Hirose Denki)

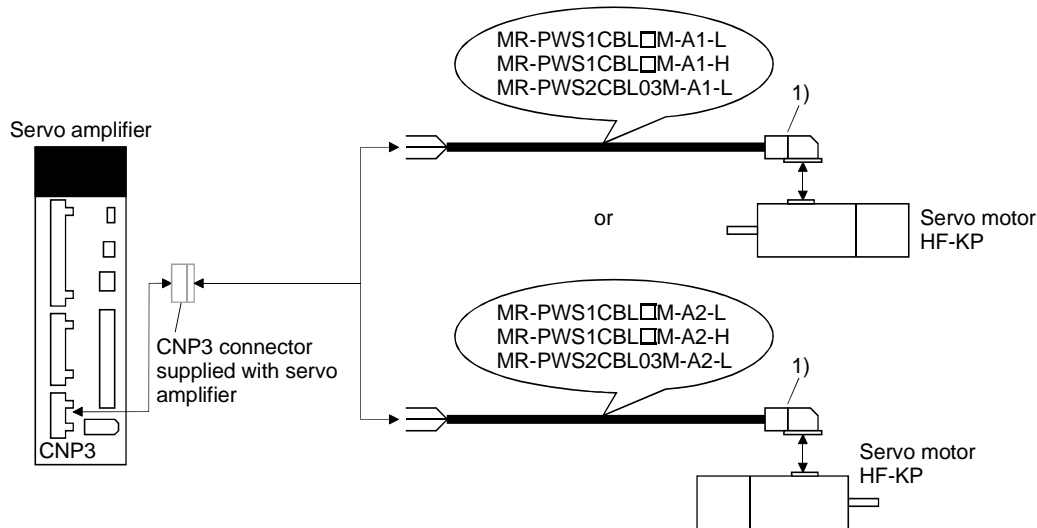
12. OPTIONS AND AUXILIARY EQUIPMENT

12.1.3 Motor power supply cables

These cables are motor power supply cables for the HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

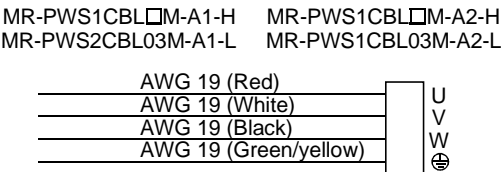
Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-PWS1CBL □ M-A1-L		2	5	10					IP65	Standard	For HF-KP servo motor Load side lead
MR-PWS1CBL □ M-A2-L		2	5	10					IP65	Standard	For HF-KP servo motor Opposite-to-load side lead
MR-PWS1CBL □ M-A1-H		2	5	10					IP65	Long flex	For HF-KP servo motor Load side lead
MR-PWS1CBL □ M-A2-H		2	5	10					IP65	Long flex	For HF-KP servo motor Opposite-to-load side lead
MR-PWS2CBL □ M-A1-L	03								IP55	Standard	For HF-KP servo motor Load side lead
MR-PWS2CBL □ M-A2-L	03								IP55	Standard	For HF-KP servo motor Opposite-to-load side lead

(1) Connection of servo amplifier and servo motor



Cable Model	1) For Motor Power Supply Connector	
MR-PWS1CBL □ M-A1-L	Connector: JN4FT04SJ1 Hod, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100(A534G) Crimping tool: CT160-3TM5B (Japan Aviation Electronics Industry)	Signal layout View seen from wiring side.
MR-PWS1CBL □ M-A2-L		
MR-PWS1CBL □ M-A1-H		
MR-PWS1CBL □ M-A2-H		
MR-PWS2CBL03M-A1-L		
MR-PWS2CBL03M-A2-L		

(2) Internal wiring diagram



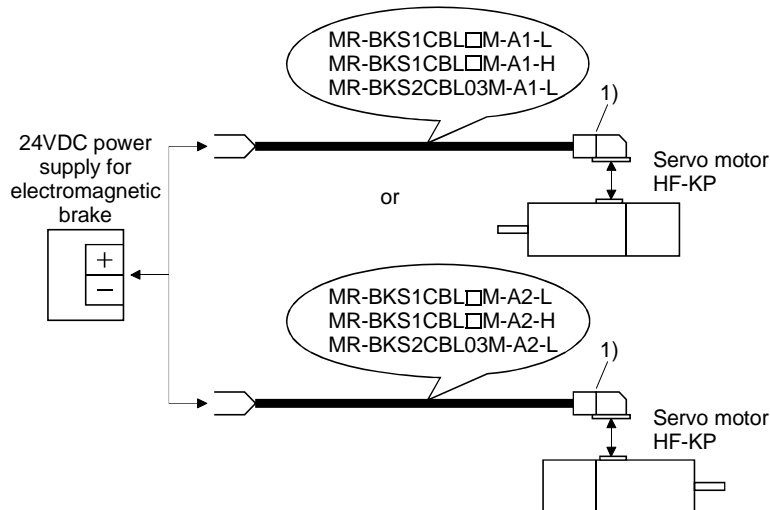
12. OPTIONS AND AUXILIARY EQUIPMENT

12.1.4 Motor brake cables

These cables are motor brake cables for the HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

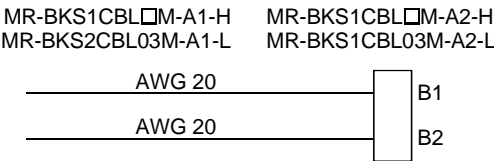
Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-BKS1CBL □ M-A1-L		2	5	10					IP65	Standard	For HF-KP servo motor Load side lead
MR-BKS1CBL □ M-A2-L		2	5	10					IP65	Standard	For HF-KP servo motor Opposite-to-load side lead
MR-BKS1CBL □ M-A1-H		2	5	10					IP65	Long flex	For HF-KP servo motor Load side lead
MR-BKS1CBL □ M-A2-H		2	5	10					IP65	Long flex	For HF-KP servo motor Opposite-to-load side lead
MR-BKS2CBL □ M-A1-L	03								IP55	Standard	For HF-KP servo motor Load side lead
MR-BKS2CBL □ M-A2-L	03								IP55	Standard	For HF-KP servo motor Opposite-to-load side lead

(1) Connection of servo amplifier and servo motor



Cable Model	1) For Motor Brake Connector	
MR-BKS1CBL □ M-A1-L	Connector: JN4FT02SJ1 Hod, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100(A534G) Crimping tool: CT160-3TMH5B (Japan Aviation Electronics Industry)	Signal layout View seen from wiring side.
MR-BKS1CBL □ M-A2-L		
MR-BKS1CBL □ M-A1-H		
MR-BKS1CBL □ M-A2-H		
MR-BKS2CBL03M-A1-L		
MR-BKS2CBL03M-A2-L		

(2) Internal wiring diagram



12. OPTIONS AND AUXILIARY EQUIPMENT

12.2 Regenerative brake options



CAUTION

The specified combinations of regenerative brake options and servo amplifiers may only be used. Otherwise, a fire may occur.

(1) Combination and regenerative power

The power values in the table are resistor-generated powers and not rated powers.

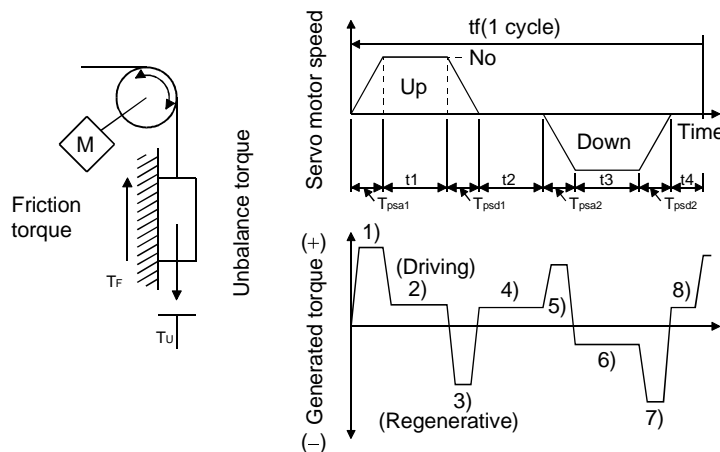
Servo amplifier	Regenerative power[W]					
	Built-in regenerative brake resistor	MR-RB032 [40Ω]	MR-RB12 [40Ω]	MR-RB30 [13Ω]	MR-RB32 [40Ω]	MR-RB50 [13Ω]
MR-J3-10A (1)		30				
MR-J3-20A (1)	10	30	100			
MR-J3-40A (1)	10	30	100			
MR-J3-60A	10	30	100			
MR-J3-70A	20	30	100		300	
MR-J3-100A	20	30	100		300	
MR-J3-200A	100			300		500
MR-J3-350A	100			300		500

(2) Selection of the regenerative brake option

Use the following method when regeneration occurs continuously in vertical motion applications or when it is desired to make an in-depth selection of the regenerative brake option:

(a) Regenerative energy calculation

Use the following table to calculate the regenerative energy.



Formulas for calculating torque and energy in operation

Regenerative power	Torque applied to servo motor [N · m]	Energy [J]
1)	$T_1 = \frac{(J_L + J_M) \cdot N_0}{9.55 \times 10^4} \cdot \frac{1}{T_{psa1}} + T_U + T_F$	$E_1 = \frac{0.1047}{2} \cdot N_0 \cdot T_1 \cdot T_{psa1}$
2)	$T_2 = T_U + T_F$	$E_2 = 0.1047 \cdot N_0 \cdot T_2 \cdot t_1$
3)	$T_3 = \frac{(J_L + J_M) \cdot N_0}{9.55 \times 10^4} \cdot \frac{1}{T_{psd1}} + T_U + T_F$	$E_3 = \frac{0.1047}{2} \cdot N_0 \cdot T_3 \cdot T_{psd1}$
4), 8)	$T_4 = T_U$	$E_4 \geq 0$ (No regeneration)
5)	$T_5 = \frac{(J_L + J_M) \cdot N_0}{9.55 \times 10^4} \cdot \frac{1}{T_{psa2}} - T_U + T_F$	$E_5 = \frac{0.1047}{2} \cdot N_0 \cdot T_5 \cdot T_{psa2}$
6)	$T_6 = T_U + T_F$	$E_6 = 0.1047 \cdot N_0 \cdot T_6 \cdot t_3$
7)	$T_7 = \frac{(J_L + J_M) \cdot N_0}{9.55 \times 10^4} \cdot \frac{1}{T_{psd2}} - T_U + T_F$	$E_7 = \frac{0.1047}{2} \cdot N_0 \cdot T_7 \cdot T_{psd2}$

From the calculation results in 1) to 8), find the absolute value (Es) of the sum total of negative energies.

12. OPTIONS AND AUXILIARY EQUIPMENT

(b) 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-J3-10A	55	9
MR-J3-10A1	55	4
MR-J3-20A	70	9
MR-J3-20A1	70	4
MR-J3-40A	85	11
MR-J3-40A1	85	10
MR-J3-60A	85	11
MR-J3-70A	80	18
MR-J3-100A	80	18
MR-J3-200A	85	40
MR-J3-350A	85	40

Inverse efficiency (η) :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 brake option.

$$ER [J] = \eta \cdot E_s - E_c$$

Calculate the power consumption of the regenerative brake option on the basis of single-cycle operation period t_f [s] to select the necessary regenerative brake option.

$$PR [W] = ER/t_f \dots\dots\dots(12.1)$$

(3) Connection of the regenerative brake option

Set parameter No. PA02 according to the open to be used.

Parameter No. PA02

--	--	--	--

Selection of regenerative

00: Regenerative brake option is not used

• For MR-J3-10A, regenerative brake resistor is not used.

• For MR-J3-20A, built-in regenerative brake resistor is used.

02: MR-RB032

03: MR-RB12

04: MR-RB32

05: MR-RB30

06: MR-RB50

12. OPTIONS AND AUXILIARY EQUIPMENT

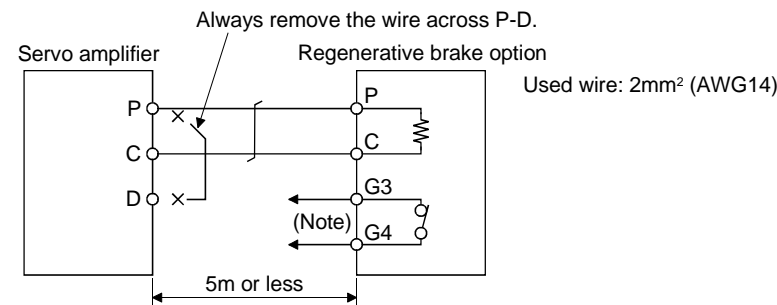
(4) Connection of the regenerative brake option

POINT
<ul style="list-style-type: none"> When the MR-RB50 is used, a fan is required to cool it. The cooling fan should be prepared by the customer.

The regenerative brake option will generate heat of about 100°C. Fully examine heat dissipation, installation position, used cables, etc. before installing the option. For wiring, use flame-resistant cables and keep them clear of the regenerative brake option body. Always use twisted cables of max. 5m(16.4ft) length for connection with the servo amplifier.

Always remove the wiring from across P-D and fit the regenerative brake option across P-C.

The G3 and G4 terminals act as a thermal protector. G3-G4 are disconnected when the regenerative brake option overheats abnormally.



Note. Make up a sequence which will switch off the magnetic contactor (MC) when abnormal heating occurs.

G3-G4 contact specifications

Maximum voltage: 120V AC/DC

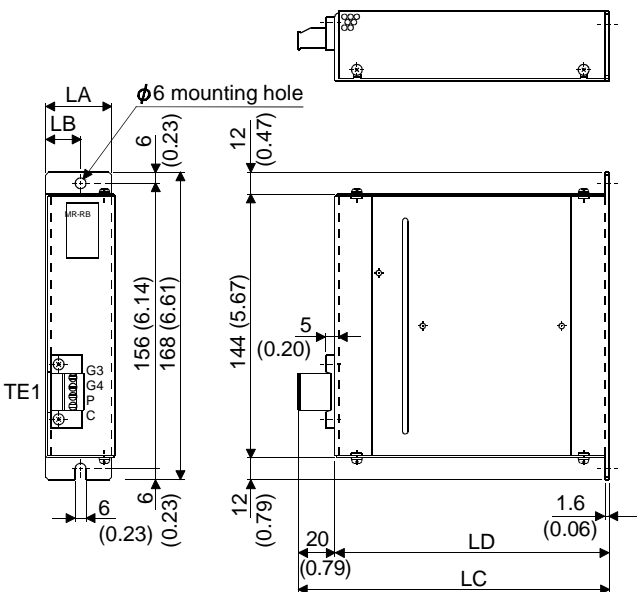
Maximum current: 0.5A/4.8VDC

Maximum capacity: 2.4VA

(5) Outline dimension drawings

(a) MR-RB032 • MR-RB12

[Unit: mm]



• TE1 terminal block

G3
G4
P
C

Terminal screw: M3

Tightening torque: 0.5 to 0.6 [N · m] (4 to 5 [lb · in])

• Mounting screw

Screw: M5

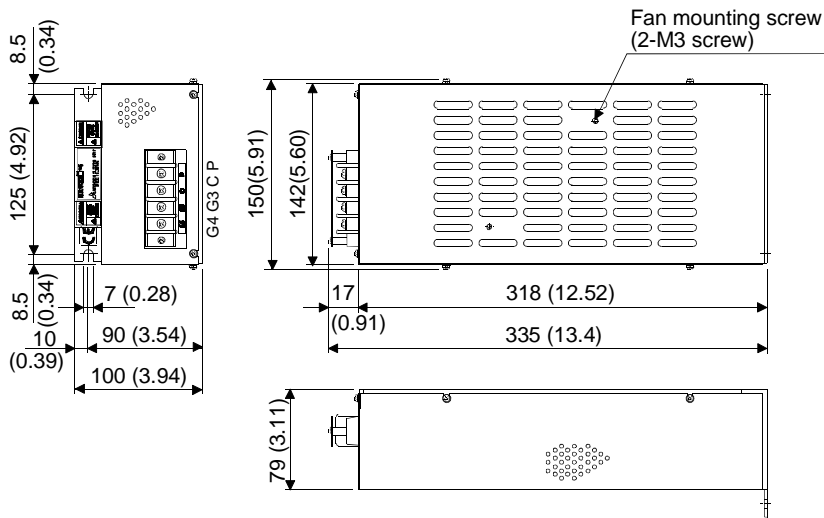
Tightening torque: 3.2 [N · m] (28.3 [lb · in])

Regenerative brake option	Variable dimensions				Mass	
	LA	LB	LC	LD	[kg]	[lb]
MR-RB032	30 (1.18)	15 (0.59)	119 (4.69)	99 (3.9)	0.5	1.1
MR-RB12	40 (1.57)	15 (0.59)	169 (6.69)	149 (5.58)	1.1	2.4

12. OPTIONS AND AUXILIARY EQUIPMENT

(b) MR-RB30 • MR-RB32

[Unit: mm]



• Terminal block

P
C
G3
G4

Terminal screw: M4
Tightening torque: 1.2 [N·m] (10 [lb·in])

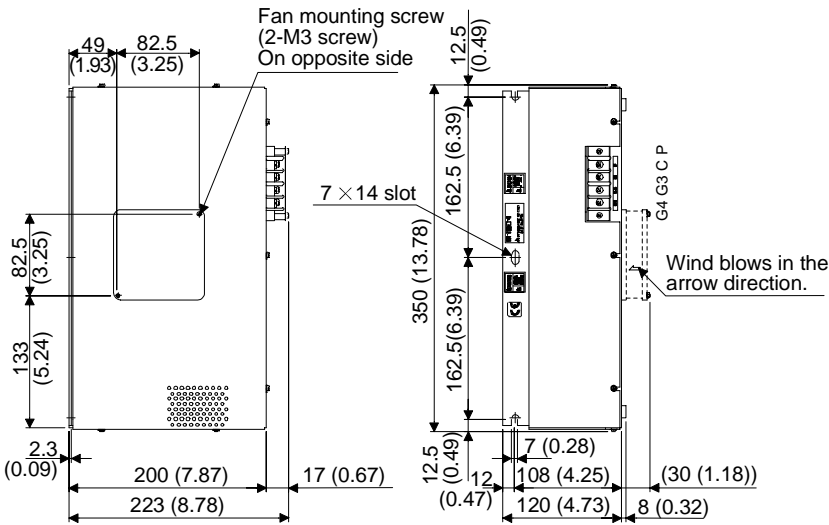
• Mounting screw

Screw: M6
Tightening torque: 5.4 [N·m] (47.8 [lb·in])

Regenerative brake option	Mass	
	[kg]	[lb]
MR-RB30	2.9	6.4
MR-RB32		

(c) MR-RB50

[Unit: mm]



• Terminal block

[Unit: mm (in)]

P
C
G3
G4

Terminal screw: M4
Tightening torque: 1.2 [N·m] (10 [lb·in])

• Mounting screw

Screw : M6
Tightening torque: 5.4 [N·m] (47.79 [lb·in])

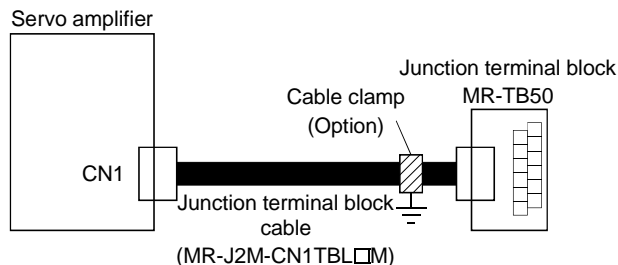
Regenerative brake option	Mass	
	[kg]	[lb]
MR-RB50	5.6	12.3

12. OPTIONS AND AUXILIARY EQUIPMENT

12.3 Junction terminal block MR-TB50

(1) How to use the junction terminal block

Always use the junction terminal block (MR-TB50) with the junction terminal block cable (MR-J2M-CN1TBL □ M) as a set. A connection example is shown below:



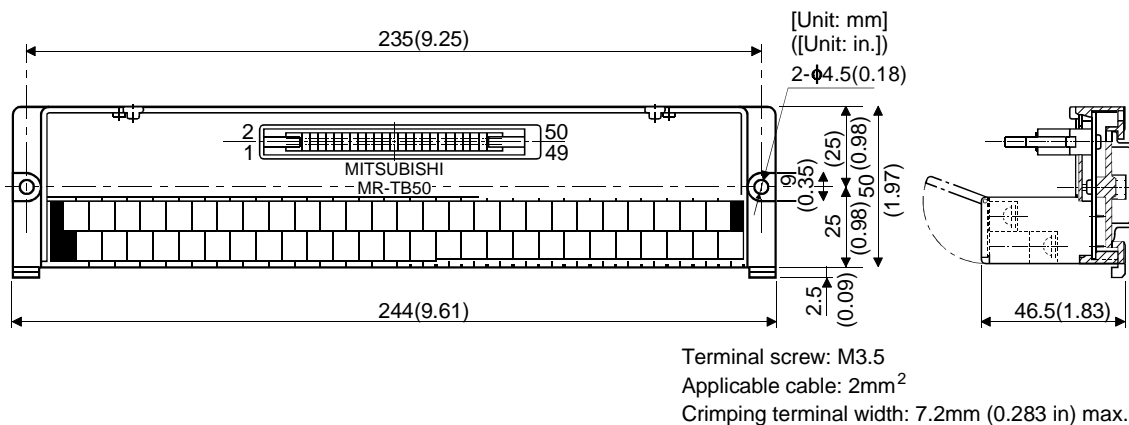
Ground the junction terminal block cable on the junction terminal block side with the standard accessory cable clamp fitting (AERSBAN-ESET). For the use of the cable clamp fitting, refer to Section 12.12, (2)(c).

(2) Terminal labels

Use the following junction terminal block labels. This label is supplied with the junction terminal block cable MR-J2M-CN1TBL.

P15R	LG	LAR	LBR	LZR	PG		SON	PC	RES	DL COM	ZSP	TLC	TLA			OP	NP			CR	LSP	LOP	DO COM	RD	
VC	LA	LB	LZ	PP	OPC		LOP	TL	DL COM	INP	INP		LG	LG		LG	NG			EMG	LSN	DO COM	ALM	SD	

(3) Outline drawing



12. OPTIONS AND AUXILIARY EQUIPMENT

(4) Junction terminal block cable MR-J2M-CN1TBL□M

(a) Model explanation

Model: MR-J2M-CN1TBL□M

Symbol	Cable length[m(ft)]
05	0.5 (1.64)
1	1 (3.28)

(b) Connection diagram

Signal Symbols					
Position	Speed	Torque	Pin No.		Pin No.
P15R	P15R	P15R	1		1
	VC	VLA	2		2
LG	LG	LG	3		3
LA	LA	LA	4		4
LAR	LAR	LAR	5		5
LB	LB	LB	6		6
LBR	LBR	LBR	7		7
LZ	LZ	LZ	8		8
LZR	LZR	LZR	9		9
PP			10		10
PG			11		11
OPC			12		12
			13		13
			14		14
SON	SON	SON	15		15
LOP	SP2	SP2	16		16
PC	ST1	RS2	17		17
TL	ST2	RS1	18		18
RES	RES	RES	19		19
DICOM	DICOM	DICOM	20		20
DICOM	DICOM	DICOM	21		21
INP	SA		22		22
ZSP	ZSP	ZSP	23		23
INP	SA		24		24
TLC	TLC	TLC	25		25
			26		26
TLA	TLA	TC	27		27
LG	LG	LG	28		28
			29		29
LG	LG	LG	30		30
			31		31
			32		32
OP	OP	OP	33		33
LG	LG	LG	34		34
NP			35		35
NG			36		36
			37		37
			38		38
			39		39
			40		40
CR	SP1	SP1	41		41
EMG	EMG	EMG	42		42
LSP	LSP		43		43
LSN	LSN		44		44
LOP	LOP	LOP	45		45
DOCOM	DOCOM	DOCOM	46		46
DOCOM	DOCOM	DOCOM	47		47
ALM	ALM	ALM	48		48
RD	RD	RD	49		49
			50		50
SD	SD	SD	Plate		

12. OPTIONS AND AUXILIARY EQUIPMENT

12.4 MR Configurator (Soon to be released)

The MR configurator (MRZJW3-SETUP211E) uses the communication function of the servo amplifier to perform parameter setting changes, graph display, test operation, etc. on a personal computer.

(1) Specifications

Item	Description
Baudrate [bps]	115200, 57600, 38400, 19200, 9600
Monitor	Display, high speed monitor, trend graph Minimum resolution changes with the processing speed of the personal computer.
Alarm	Display, history, amplifier data
Diagnostic	Digital I/O, no motor rotation, total power-on time, amplifier version info, motor information, tuning data, absolute encoder data, automatic voltage control, Axis name setting.
Parameters	Parameter list, turning, change list, detailed information
Test operation	Jog operation, positioning operation, motor-less operation, Do forced output, program operation.
Advanced function	Machine analyzer, gain search, machine simulation.
File operation	Data read, save, print
Others	Automatic demo, help display

(2) System configuration

(a) Components

To use this software, the following components are required in addition to the servo amplifier and servo motor:

Model	Description
(Note 2) Personal computer	IBM PC-AT compatible where the English version of Windows® 98 Second Edition, Windows® Me, Windows® 2000 Professional, Windows® XP Professional and Windows® XP Home Edition operates Processor: Pentium 133MHz or more (Windows® 98 Second Edition, Windows® 2000 Professional) Pentium 150MHz or more (Windows® Me) Pentium 300MHz or more (Windows® XP Professional, Windows® XP Home Edition) Memory: 24MB or more (Windows® 98 Second Edition) 32MB or more (Windows® Me, Windows® 2000 Professional) 128MB or more (Windows® XP Professional, Windows® XP Home Edition) Free hard disk space: 60MB or more
OS	Windows® 98 Second Edition, Windows® Me, Windows® 2000 Professional, Windows® XP Professional, Windows® XP Home Edition (English version)
Display	One whose resolution is 800×600 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
RS-422/232C conversion cable	DSV-CABV (Diatrend) is recommended.
RS-422/232C converter	FA-T-RS40VS (Mitsubishi Electric Engineering) is recommended. Required for use of the multidrop communication function.

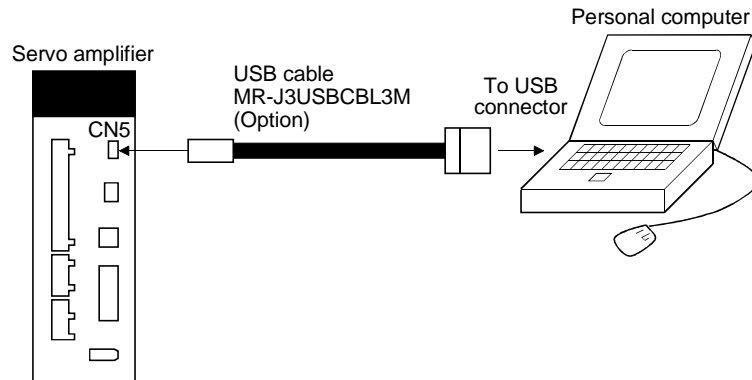
Note 1. Windows is the registered trademarks of Microsoft Corporation in the United State and other countries.

2. On some personal computers, this software may not run properly.

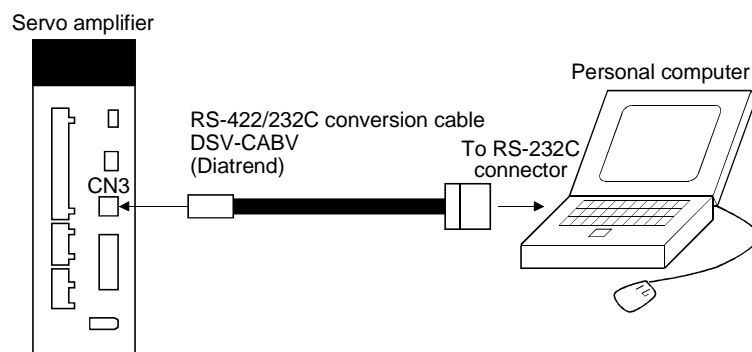
12. OPTIONS AND AUXILIARY EQUIPMENT

(b) Connection with servo amplifier

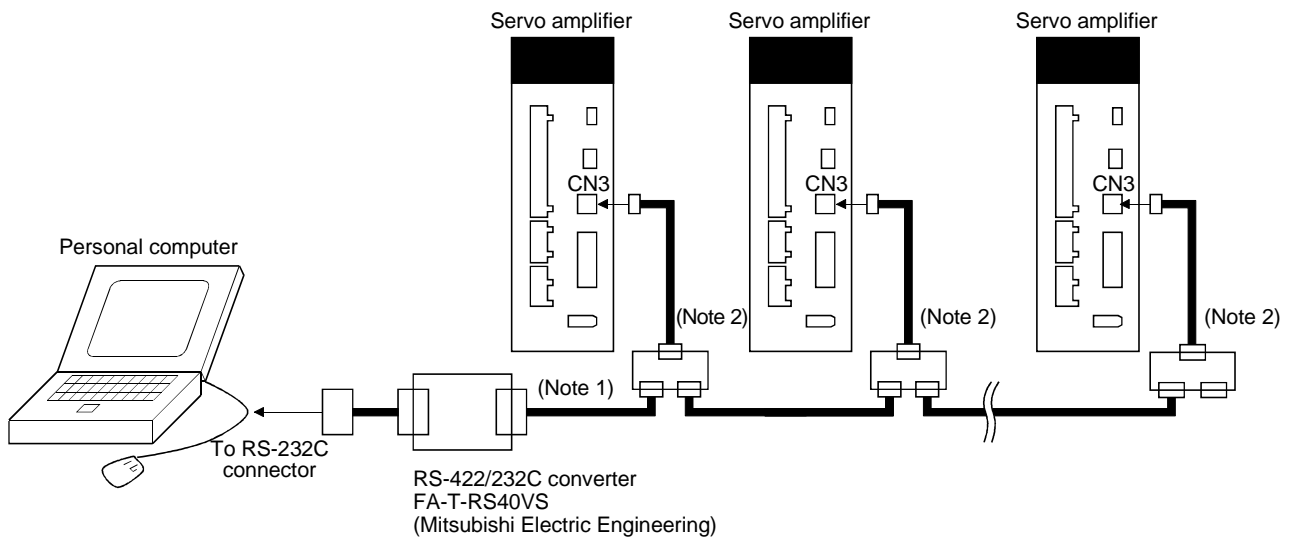
1) For use of USB



2) For use of RS-422



3) For use of RS-422 to make multidrop connection



Note 1. Refer to Section 13.1 for cable wiring.

2. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

12. OPTIONS AND AUXILIARY EQUIPMENT

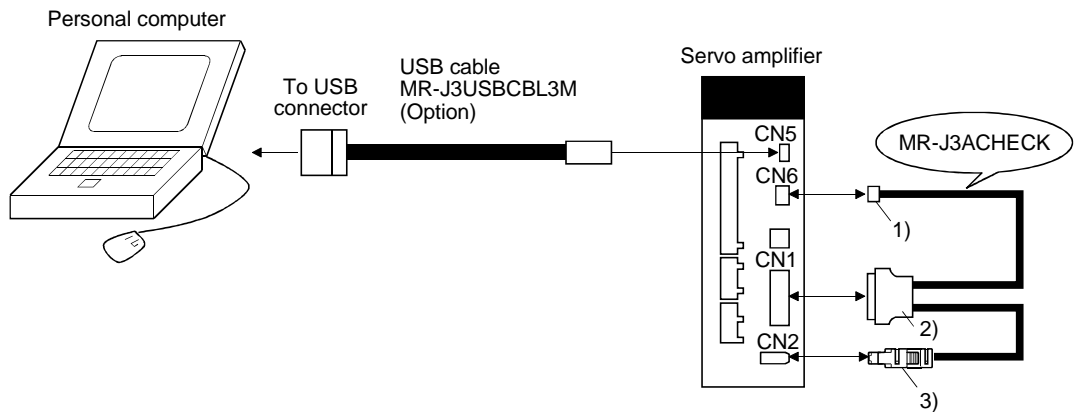
(c) To diagnose the trouble using diagnosis cable (MR-J3ACHECK)

POINT
<ul style="list-style-type: none">▪ The amplifier diagnosis function can be used with the following software versions of the servo amplifier. Servo amplifier: A1 or later▪ Do not turn the power on with all connectors connected. Do not connect or disconnect connectors after the power is turned on. Otherwise failure will be caused.

This cable is a diagnosis cable of the servo amplifier. The amplifier diagnosis function of MR Configurator (setup software) can be used when this cable is used.

Cable Model	Application
MR-J3ACHECK	Amplifier diagnosis cable for MR Configurator (servo configuration software)

Connection between the servo amplifier and servo motor is shown in the figure below.



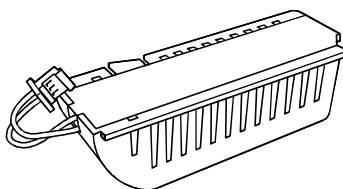
Cable Model	1) For CN6 Connector	2) For CN1 Connector	3) For CN2 Connector
MR-J3ACHECK	Housing: 51004-0300 Contact: 50011-8000 (molex)	Plug: 10150-3000VE Shell kit: 10350-52F0-008 (3M)	Receptacle: 36210-0100JE Shell kit: 36310-3200-008 (3M or equivalent)

12. OPTIONS AND AUXILIARY EQUIPMENT

12.5 Battery Unit MR-J3BAT

POINT	
	<ul style="list-style-type: none">▪ The revision (Edition 44) of the Dangerous Goods Rule of the International Air Transport Association (IATA) went into effect on January 1, 2003 and was enforced immediately. In this rule, "provisions of the lithium and lithium ion batteries" were revised to tighten the restrictions on the air transportation of batteries. However, since this battery is non-dangerous goods (non-Class 9), air transportation of 24 or less batteries is outside the range of the restrictions. Air transportation of more than 24 batteries requires packing compliant with the Packing Standard 903. When a self-certificate is necessary for battery safety tests, contact our branch or representative. For more information, consult our branch or representative. (As of April, 2004).

This battery is used to construct an absolute position detection system. Refer to Section 14.3 for the fitting method, etc.

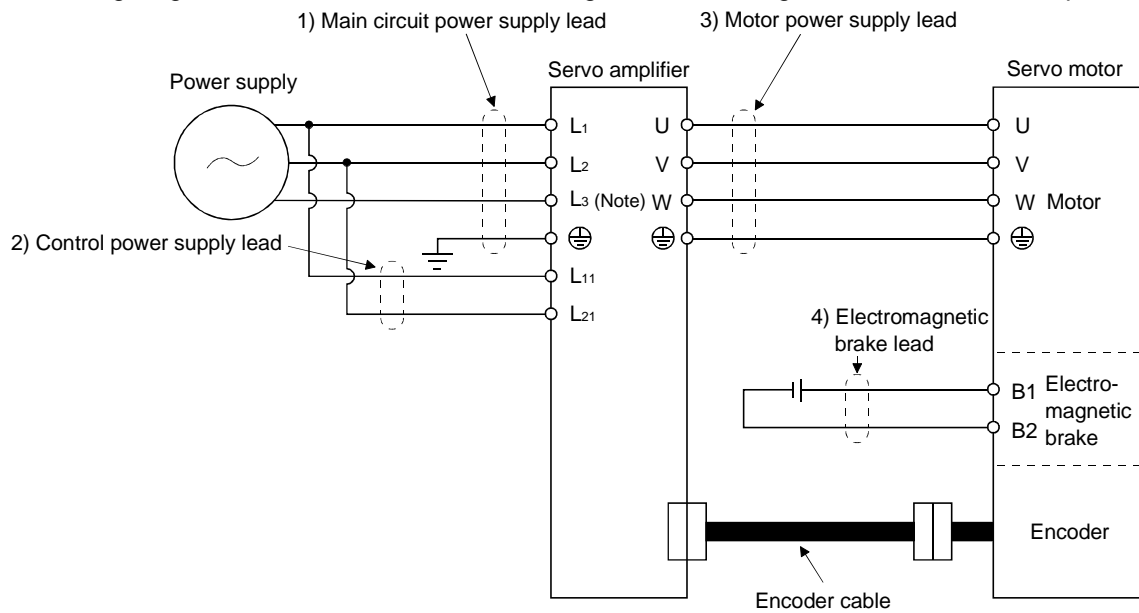


12. OPTIONS AND AUXILIARY EQUIPMENT

12.6 Recommended wires

(1) Wires for power supply wiring

The following diagram shows the wires used for wiring. Use the wires given in this section or equivalent.



Note. There is no L₃ for 1-phase 100 to 120VAC power supply.

The following table lists wire sizes. The wires used assume that they are 600V vinyl wires and the wiring distance is 30m(98.4ft) max. If the wiring distance is over 30m(98.4ft), choose the wire size in consideration of voltage drop.

To comply with the UL/C-UL (CSA) Standard, use UL-recognized copper wires rated at 60°C (140°F) or more for wiring.

Table 12.1 Recommended wires

Servo amplifier	Wires [mm ²]			
	1) L ₁ · L ₂ · L ₃ ·	2) L ₁₁ · L ₂₁	3) U · V · W ·	4) B1 · B2
MR-J3-10A (1)	2 (AWG14)	1.25 (AWG16)	1.25 (AWG16)	1.25 (AWG16)
MR-J3-20A (1)				
MR-J3-40A (1)				
MR-J3-60A			2 (AWG14)	
MR-J3-70A			3.5 (AWG12)	
MR-J3-100A			5.5 (AWG10)	
MR-J3-200A	3.5 (AWG12)	1.25 (AWG16)	3.5 (AWG12)	1.25 (AWG16)
MR-J3-350A	5.5 (AWG10)		5.5 (AWG10)	

12. OPTIONS AND AUXILIARY EQUIPMENT

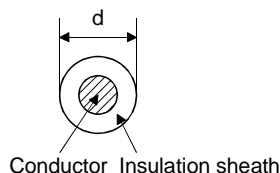
(2) Wires for cables

When fabricating a cable, use the wire models given in the following table or equivalent:

Table 12.2 Wires for option cables

Type	Model	Length [m(ft)]	Core size [mm ²]	Number of Cores	Characteristics of one core			(Note 3) Finishing OD [mm]	Wire model
					Structure [Wires/mm]	Conductor resistance [Ω/mm]	Insulation coating ODd [mm] (Note 1)		
Encoder cable	MR-J3ENCBL □ M-A1-L	2 to 10	AWG22	6 (3 pairs)	7/0.26	53 or less	1.2	7.1±0.3	(Note 4) VSVP 7/0.26 (AWG#22 or equivalent)-3P Specification-16823
	MR-J3ENCBL □ M-A2-L								
	MR-J3ENCBL □ M-A1-H	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 4) ETEF SVP 70/0.08 (AWG#22 or equivalent)-3P Specification- 16824
	MR-J3ENCBL □ M-A2-H								
	MR-J3JCBLO3M-A1-L	0.3	AWG26	8 (4 pairs)	30/0.08	233 or less	1.2	7.1±0.3	(Note 6) T/2464-1061/II A-SB 4P × 26AWG
	MR-J3JCBLO3M-A2-L								
	MR-EKCBL □ M-L	2 to 10	0.3mm ²	4 (2 pairs)	12/0.18	65.7 or less	1.3	7.3	(Note 4) 20276 composite 4-pair shielded cable (A-TYPE)
			0.08mm ²	4 (2 pairs)	7/0.127	234 or less	0.67		
		20 · 30	0.3mm ²	12 (6 pairs)	12/0.18	63.6 or less	1.2	8.2	UL20276 AWG#23 6pair(BLACK)
	MR-EKCBL □ M-H	2 to 10	0.2mm ²	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) A14B2339 6P
		20	0.2mm ²	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) A14B2343 6P
		30 to 50	0.2mm ²	14 (7 pairs)	40/0.08	105 or less	0.88	8.0	(Note 3) J14B0238(0.2"7P)
	MR-J3ENSCBL □ M-L	2 to 10	AWG22	6 (3 pairs)	7/0.26	53 or less	1.2	7.1±0.3	(Note 4) VSVP 7/0.26 (Equivalent to AWG#22)-3P Ban-gi-shi-16823
		20 · 30	AWG23	12 (6 pairs)	12/0.18	63.3 or less	1.2	8.2±0.3	(Note 4) 20276 VSVCAWG#23 × 6P KB-0122
	MR-J3ENSCBL □ M-H	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 4) ETEF SVP 70/0.08 (Equivalent to AWG#22)-3P Ban-gi-shi-16824
		20 to 50	AWG24	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 4) ETFE · SVP 40/0.08mm × 6P KB-0308
Motor power supply cable	MR-PWS1CBL □ M-A1-L	2 to 10	(Note 7) AWG19	4	50/0.08	25.40 or less	1.8	5.7±0.3	(Note 5) UL Style 2103 AWG19 4 cores
	MR-PWS1CBL □ M-A2-L	2 to 10							
	MR-PWS1CBL □ M-A1-H	2 to 10							
	MR-PWS1CBL □ M-A2-H	2 to 10							
	MR-PWS2CBL03M-A1-L	0.3							
Motor brake cable	MR-PWS2CBL03M-A2-L	0.3	(Note 7) AWG20	2	100/0.08	38.14 or less	1.3	4.0±0.3	(Note 5) UL Style 2103 AWG20 2 cores
	MR-BKS1CBL □ M-A1-L	2 to 10							
	MR-BKS1CBL □ M-A2-L	2 to 10							
	MR-BKS1CBL □ M-A1-H	2 to 10							
	MR-BKS1CBL □ M-A2-H	2 to 10							
	MR-BKS2CBL03M-A1-L	0.3							
	MR-BKS2CBL03M-A2-L	0.3							

Note 1. d is as shown below:



- Purchased from Toa Electric Industry
- Standard OD. Max. OD is about 10% greater.
- Bando Electric Wire
- Kurabe
- Taiyo Electric Wire and Cable
- These wire sizes assume that the UL-compliant wires are used at the wiring length of 10m.

12. OPTIONS AND AUXILIARY EQUIPMENT

12.7 No-fuse breakers, fuses, magnetic contactors

Always use one no-fuse breaker and one magnetic contactor with one servo amplifier. When using a fuse instead of the no-fuse breaker, use the one having the specifications given in this section.

Servo amplifier	No-fuse breaker	Fuse			Magnetic contactor
		(Note) Class	Current [A]	Voltage [V]	
MR-J3-10A (1)	30A frame 5A	K5	10	AC250	S-N10
MR-J3-20A	30A frame 5A	K5	10		
MR-J3-40A · 20A1	30A frame 10A	K5	15		
MR-J3-60A · 70A · 100A · 40A1	30A frame 15A	K5	20		
MR-J3-200A	30A frame 20A	K5	40		S-N18
MR-J3-350A	30A frame 30A	K5	70		S-N20

Note. This servo amplifier is UL/C-UL-listed when using a Class T fuse. Therefore, when using the servo amplifier as a UL/C-UL Standard compliant product, be sure to use the Class T fuse.

12. OPTIONS AND AUXILIARY EQUIPMENT

12.8 Power Factor Improving DC Reactor

POINT

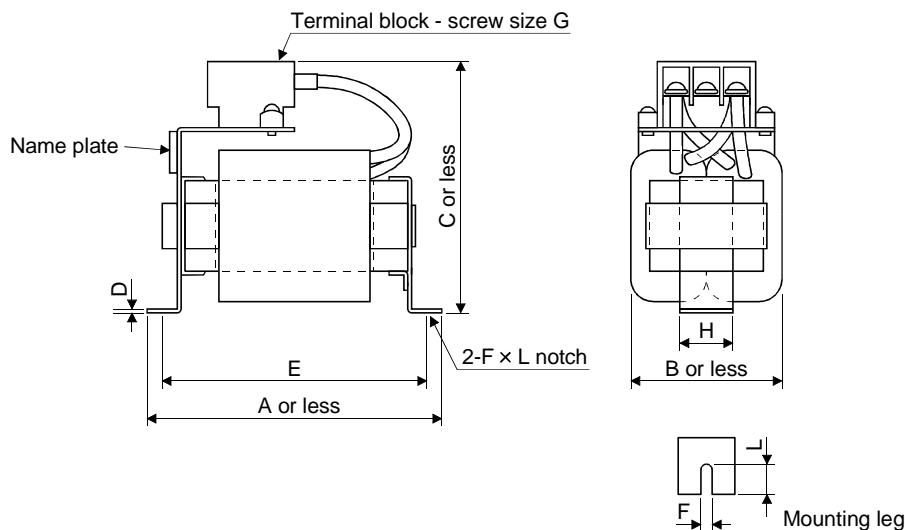
- For the 100VAC power supply type (MR-J3-□A1), the power factor improving DC reactor cannot be used.

The power factor improving DC reactor increases the form factor of the servo amplifier's input current to improve the power factor. It can decrease the power supply capacity. As compared to the power factor improving AC reactor (FR-BAL), it can decrease the loss. The input power factor is improved to about 95%. It is also effective to reduce the input side harmonics.

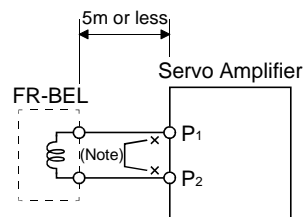
When connecting the power factor improving DC reactor to the servo amplifier, always disconnect the wiring across P1-P2. If it remains connected, the effect of the power factor improving DC reactor is not produced.

When used, the power factor improving DC reactor generates heat. To release heat, therefore, leave a 10cm or more clearance at each of the top and bottom, and a 5cm or more clearance on each side.

[Unit: mm]
([Unit: in])



Servo Amplifier	Power Factor Improving DC Reactor	Dimensions [mm(in)]									Mounting Screw Size	Mass [kg(lb)]	Used Power Supply [mm ²]
		A	B	C	D	E	F	L	G	H			
MR-J3-10A • 20A	FR-BEL-0.4K	110 (3.94)	50 (1.97)	94 (3.70)	1.6 (0.063)	95 (3.74)	6 (0.236)	12 (0.472)	M3.5	25 (0.984)	M5	0.5 (1.10)	2 (AWG14)
MR-J3-40A	FR-BEL-0.75K	120 (4.72)	53 (2.09)	102 (4.02)	1.6 (0.063)	105 (4.13)	6 (0.236)	12 (0.472)	M4	25 (0.984)	M5	0.7 (1.54)	
MR-J3-60A • 70A	FR-BEL-1.5K	130 (5.12)	65 (2.56)	110 (3.94)	1.6 (0.063)	115 (4.53)	6 (0.236)	12 (0.472)	M4	30 (1.18)	M5	1.1 (2.43)	
MR-J3-100A	FR-BEL-2.2K	130 (5.12)	65 (2.56)	110 (3.94)	1.6 (0.063)	115 (4.53)	6 (0.236)	12 (0.472)	M4	30 (1.18)	M5	1.2 (2.43)	
MR-J3-200A	FR-BEL-3.7K	150 (5.906)	75 (2.953)	102 (4.016)	2.0 (0.079)	135 (5.315)	6 (0.236)	12 (0.472)	M4	40 (1.575)	M5	1.7 (3.75)	3.5 (AWG12)
MR-J3-350A	FR-BEL-7.5K	150 (5.906)	75 (2.953)	126 (4.961)	2.0 (0.079)	135 (5.315)	6 (0.236)	12 (0.472)	M5	40 (1.575)	M5	2.3 (5.07)	5.5 (AWG10)

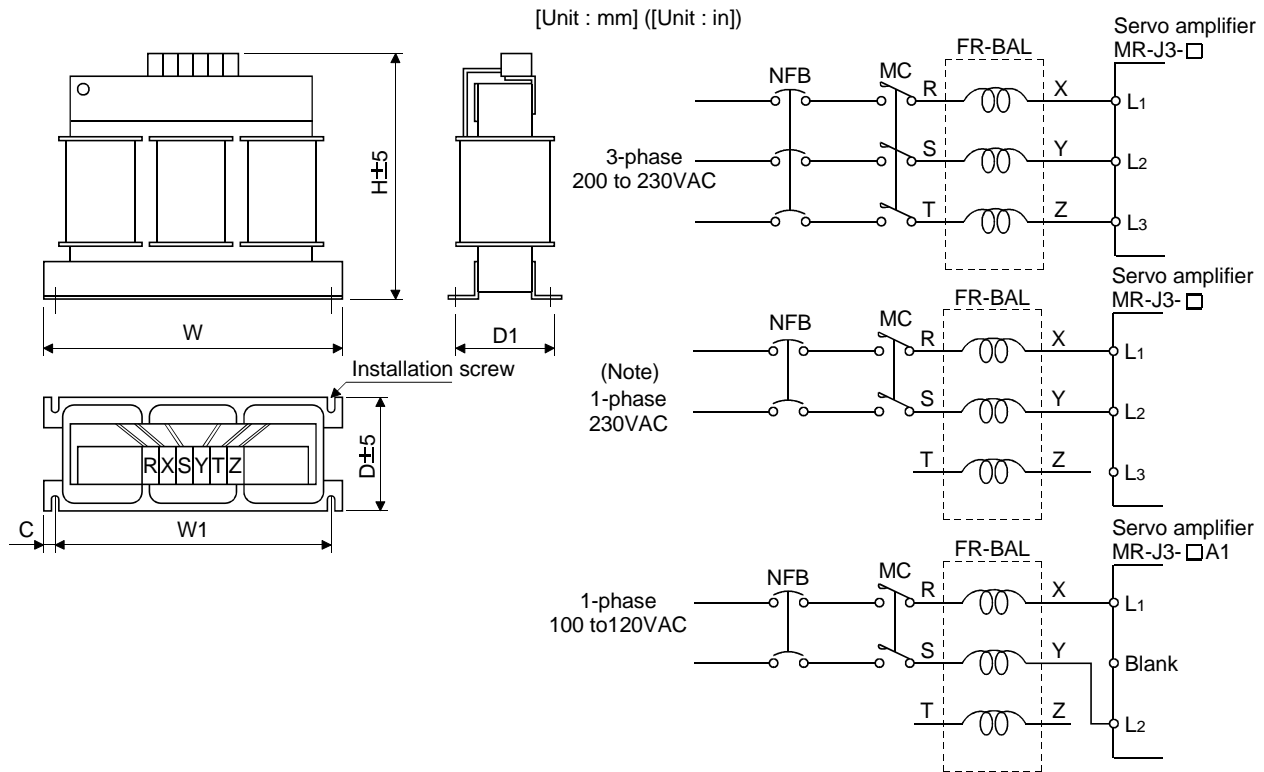


Note. When using the power factor improving DC reactor, disconnect the wiring across P1-P2.

12. OPTIONS AND AUXILIARY EQUIPMENT

12.9 Power factor improving reactors

The input power factor is improved to be about 90%. For use with a 1-phase power supply, it may be slightly lower than 90%.



Note. For the 1-phase 230V power supply, Connect the power supply to L1, L2 and leave L3 open.

Servo amplifier	Model	Dimensions [mm (in)]						Mounting screw size	Terminal screw size	Mass [kg (lb)]
		W	W1	H	D	D1	C			
MR-J3-10A/20A/10A1	FR-BAL-0.4K	135 (5.31)	120 (4.72)	115 (4.53)	59 (2.32)	45 $\frac{3}{2}$.5 (1.77 $\frac{3}{8}$.098)	7.5 (0.29)	M4	M3.5	2.0 (4.4)
MR-J3-40A/20A1	FR-BAL-0.75K	135 (5.31)	120 (4.72)	115 (4.53)	69 (2.72)	57 $\frac{3}{2}$.5 (2.24 $\frac{3}{8}$.098)	7.5 (0.29)	M4	M3.5	2.8 (6.17)
MR-J3-60A/70A/40A1	FR-BAL-1.5K	160 (6.30)	145 (5.71)	140 (5.51)	71 (2.79)	55 $\frac{3}{2}$.5 (2.17 $\frac{3}{8}$.098)	7.5 (0.29)	M4	M3.5	3.7 (8.16)
MR-J3-100A	FR-BAL-2.2K	160 (6.30)	145 (5.71)	140 (5.51)	91 (3.58)	75 $\frac{3}{2}$.5 (2.95 $\frac{3}{8}$.098)	7.5 (0.29)	M4	M3.5	5.6 (12.35)
MR-J3-200A	FR-BAL-3.7K	220 (8.66)	200 (7.87)	192 (7.56)	90 (3.54)	70 \pm 5 (2.76 \pm 0.2)	10 (0.39)	M5	M4	8.5 (18.74)
MR-J3-350A	FR-BAL-7.5K	220 (8.66)	200 (7.87)	194 (7.64)	120 (4.72)	100 \pm 5 (3.94 \pm 0.2)	10 (0.39)	M5	M5	14.5 (32.0)

12.10 Relays (Recommended)

The following relays should be used with the interfaces:

Interface	Selection example
Relay used for digital input command signals (interface DI-1)	To prevent defective contacts , use a relay for small signal (twin contacts). (Ex.) Omron : type G2A , MY
Relay used for digital output signals (interface DO-1)	Small relay with 12VDC or 24VDC of 40mA or less (Ex.) Omron : type MY

12. OPTIONS AND AUXILIARY EQUIPMENT

12.11 Surge absorbers (Recommended)

A surge absorber is required for the electromagnetic brake. Use the following surge absorber or equivalent. Insulate the wiring as shown in the diagram.

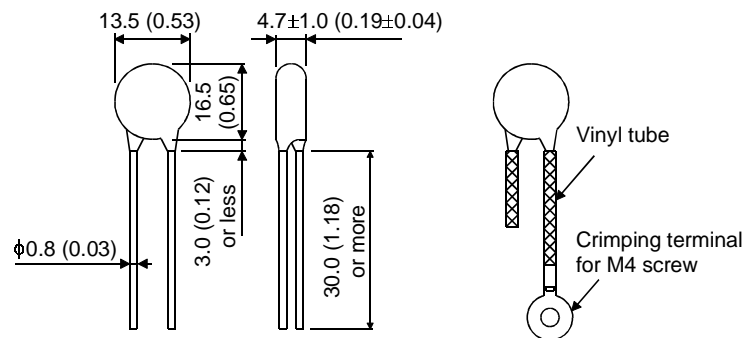
Maximum rating					Maximum limit voltage		Static capacity (reference value)	Varistor voltage rating (range) V1mA
Permissible circuit voltage		Surge immunity	Energy immunity	Rated power				
AC[Vma]	DC[V]	[A]	[J]	[W]	[A]	[V]	[pF]	[V]
140	180	(Note) 500/time	5	0.4	25	360	300	220 (198 to 242)

Note. 1 time = $8 \times 20\mu\text{s}$

(Example) ERZV10D221 (Matsushita Electric Industry)

TNR-10V221K (Nippon chemi-con)

Outline drawing [mm] ([in]) (ERZ-C10DK221)



12.12 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 devices 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 devices malfunction due to noises produced by the servo amplifier, noise suppression measures must be taken. The measures will vary slightly with the routes of noise transmission.

(1) Noise reduction techniques

(a) General reduction techniques

- Avoid laying power lines (input and output cables) and signal cables side by side or do not bundle them together. Separate power lines from signal cables.
- Use shielded, twisted pair cables for connection with the encoder and for control signal transmission, and connect the shield to the SD terminal.
- Ground the servo amplifier, servo motor, etc. together at one point (refer to Section 3.10).

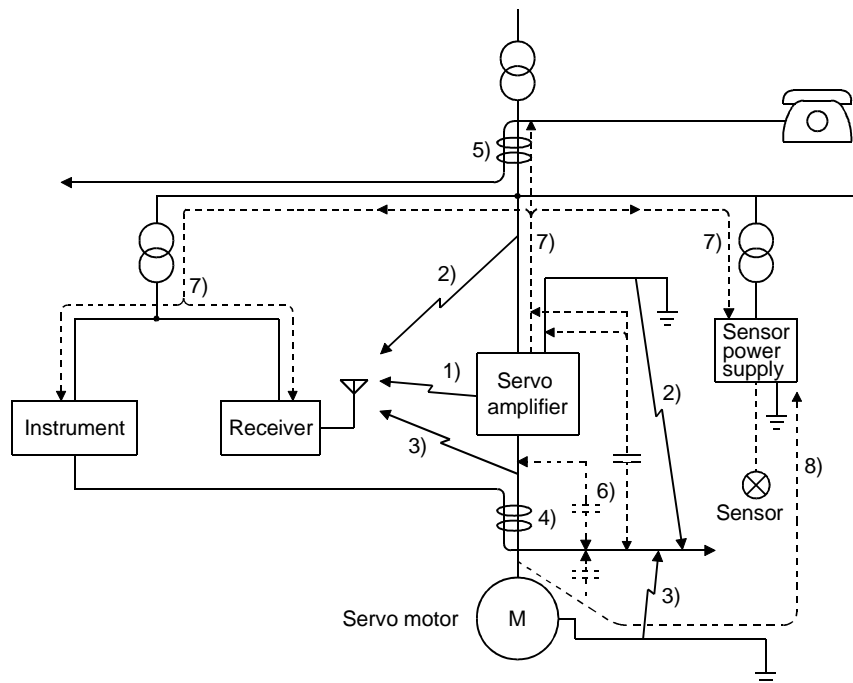
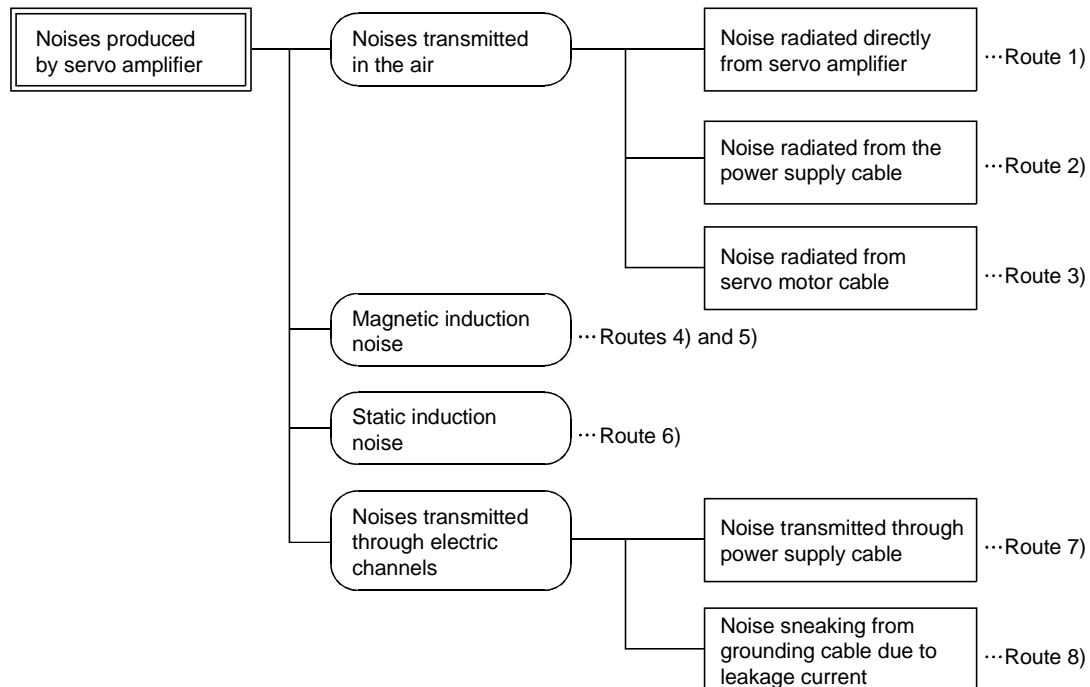
(b) Reduction techniques for external noises that cause the servo amplifier to malfunction

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.

12. OPTIONS AND AUXILIARY EQUIPMENT

- (c) Techniques for noises radiated by the servo amplifier that cause peripheral devices 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 devices located near the main circuit cables, and those transmitted through the power supply cables.



12. OPTIONS AND AUXILIARY 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 control box 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"> 1. Provide maximum clearance between easily affected devices and the servo amplifier. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier. 3. Avoid laying the power lines (Input cables of the servo amplifier) and signal cables side by side or bundling them together. 4. Insert a line noise filter to the I/O cables or a radio noise filter on the input line. 5. Use shielded wires for signal and power cables or put cables in separate metal conduits.
4) 5) 6)	<p>When the power lines and the signal cables 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"> 1. Provide maximum clearance between easily affected devices and the servo amplifier. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier. 3. Avoid laying the power lines (I/O cables of the servo amplifier) and signal cables side by side or bundling them together. 4. Use shielded wires for signal and power cables or put the cables in separate metal conduits.
7)	<p>When the power supply of peripheral devices 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"> 1. Insert the radio noise filter (FR-BIF) on the power cables (Input cables) of the servo amplifier. 2. Insert the line noise filter (FR-BSF01 • FR-BLF) on the power cables of the servo amplifier.
8)	<p>When the cables of peripheral devices are connected to the servo amplifier to make a closed loop circuit, leakage current may flow to malfunction the peripheral devices. If so, malfunction may be prevented by disconnecting the grounding cable of the peripheral device.</p>

(2) Noise reduction products

(a) Data line filter (Recommended)

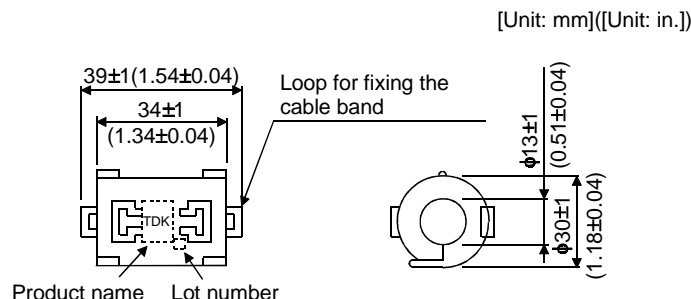
Noise can be prevented by installing a data line filter onto the encoder cable, etc.

For example, the ZCAT3035-1330 of TDK and the ESD-SR-25 of NEC TOKIN make are available as data line filters.

As a reference example, the impedance specifications of the ZCAT3035-1330 (TDK) are indicated below.

This impedances are reference values and not guaranteed values.

Impedance[Ω]	
10 to 100MHz	100 to 500MHz
80	150

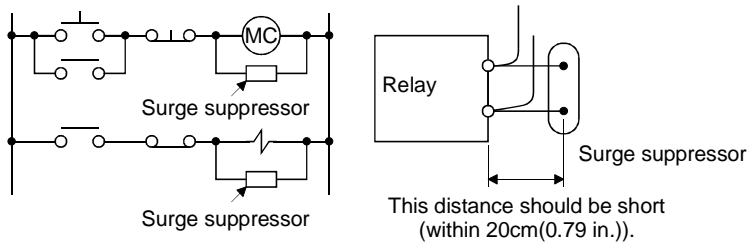


Outline drawing (ZCAT3035-1330)

12. OPTIONS AND AUXILIARY EQUIPMENT

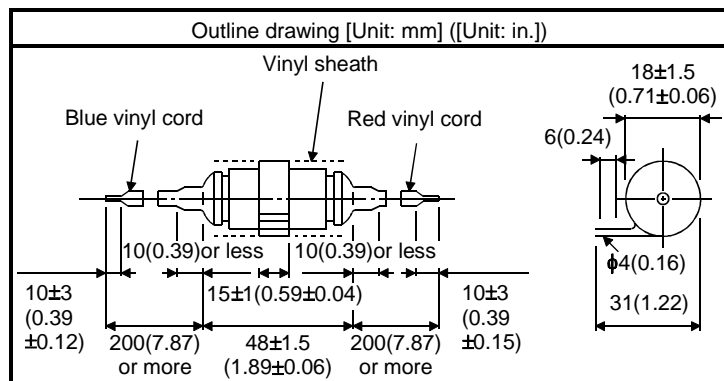
(b) Surge suppressor

The recommended surge suppressor for installation to an AC relay, AC valve, AC electromagnetic brake or the like near the servo amplifier is shown below. Use this product or equivalent.



(Ex.) 972A.2003 50411
(Matsuo Electric Co.,Ltd.—200VAC rating)

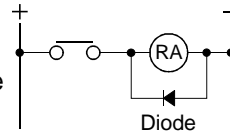
Rated voltage AC[V]	C [μ F]	R [Ω]	Test voltage AC[V]
200	0.5	50 (1W)	Across T-C 1000(1 to 5s)



Note that a diode should be installed to a DC relay, DC valve or the like.

Maximum voltage: Not less than 4 times the drive voltage of the relay or the like

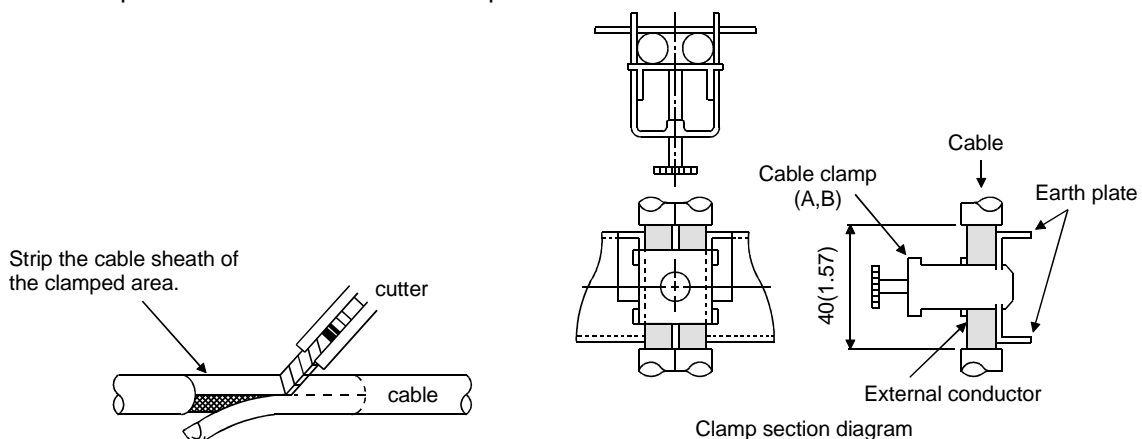
Maximum current: Not less than twice the drive current of the relay or the like



(c) Cable clamp fitting AERSBAN □-SET

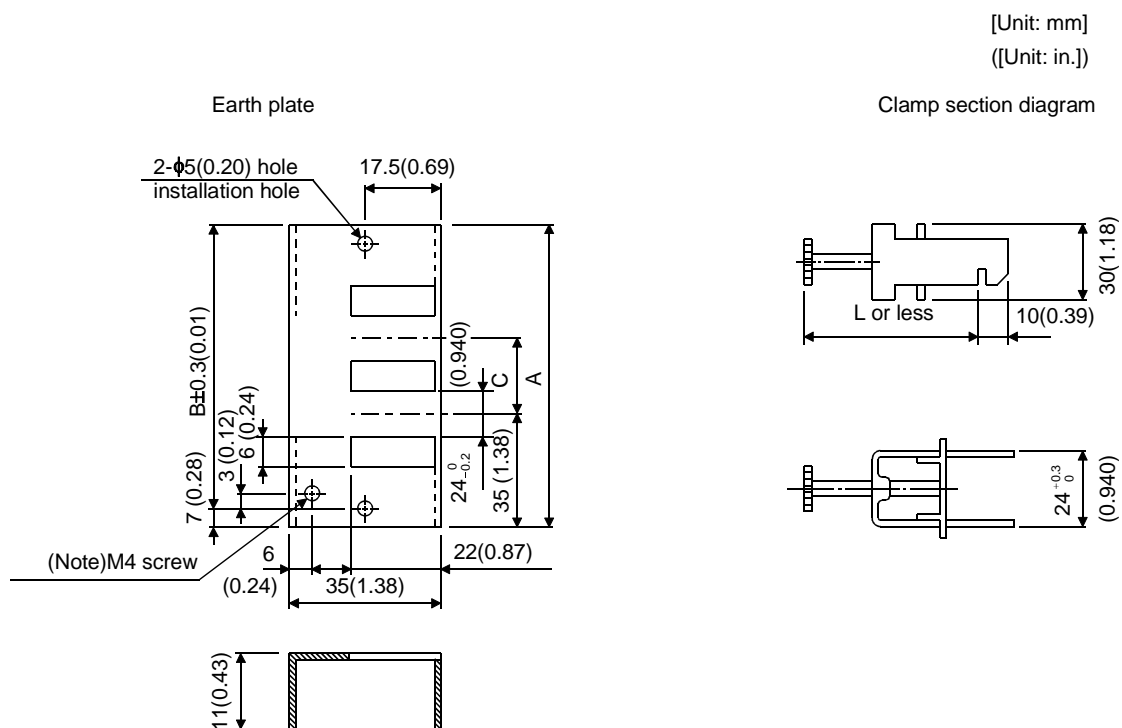
Generally, the earth of the shielded cable may only be connected to the connector's SD terminal. However, the effect can be increased by directly connecting the cable to an earth plate as shown below. Install the earth plate near the servo amplifier for the encoder cable. Peel part of the cable sheath to expose the external conductor, and press that part against the earth plate with the cable clamp. If the cable is thin, clamp several cables in a bunch.

The clamp comes as a set with the earth plate.



12. OPTIONS AND AUXILIARY EQUIPMENT

• Outline drawing



Note. Screw hole for grounding. Connect it to the earth plate of the control box.

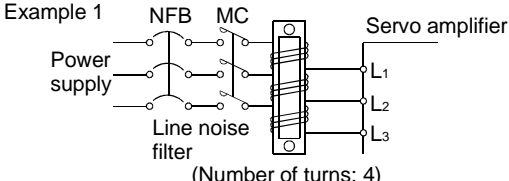
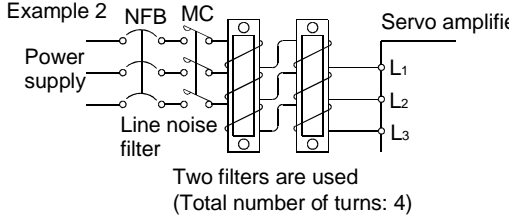
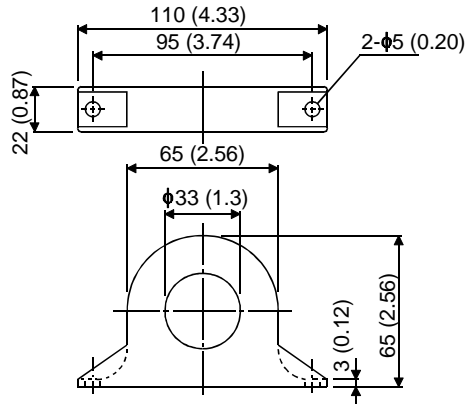
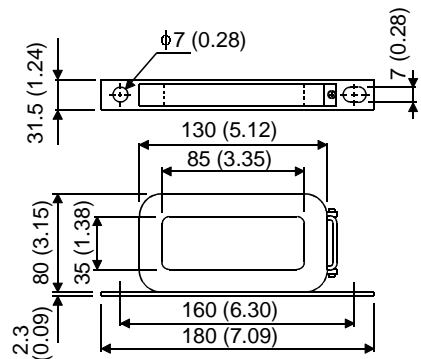
Type	A	B	C	Accessory fittings
AERSBAN-DSET	100 (3.94)	86 (3.39)	30 (1.18)	clamp A: 2pcs.
AERSBAN-ESET	70 (2.76)	56 (2.20)		clamp B: 1pc.

Clamp fitting	L
A	70 (2.76)
B	45 (1.77)

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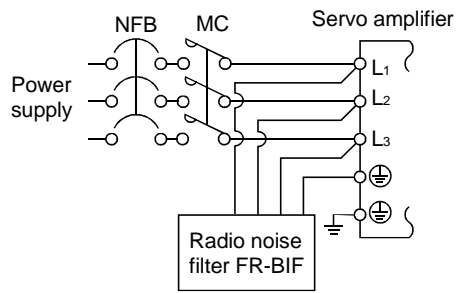
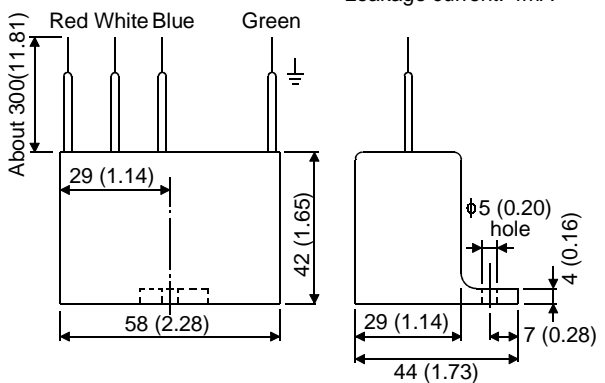
(d) Line noise filter (FR-BSF01, FR-BLF)

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 (zero-phase current) especially within 0.5MHz to 5MHz band.

Connection diagram	Outline drawing [Unit: mm] ([Unit: in.])
<p>Wind the 3-phase wires by the equal number of times in the same direction, and connect the filter to the power supply side and output side of the servo amplifier.</p> <p>The effect of the filter on the power supply side is higher as the number of winds is larger. The number of turns is generally four.</p> <p>If the wires are too thick to be wound, use two or more filters and make the total number of turns as mentioned above.</p> <p>On the output side, the number of turns must be four or less.</p> <p>Do not wind the grounding wire together with the 3-phase wires.</p> <p>The filter effect will decrease. Use a separate wire for grounding.</p> <p>Example 1</p>  <p>(Number of turns: 4)</p> <p>Example 2</p>  <p>Two filters are used (Total number of turns: 4)</p>	<p>FR-BSF01 (for MR-J3-200A or less)</p>  <p>FR-BLF(MR-J3-350A) or more</p> 

(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 10MHz and lower radio frequency bands. The FR-BIF is designed for the input only.

Connection diagram	Outline drawing (Unit: mm) ([Unit: in.])
<p>Make the connection cables as short as possible.</p> <p>Grounding is always required.</p> <p>When using the FR-BIF with a single-phase wire, always insulate the pins that are not used for wiring.</p> 	<p>Leakage current: 4mA</p> 

12. OPTIONS AND AUXILIARY EQUIPMENT

12.13 Leakage current breaker

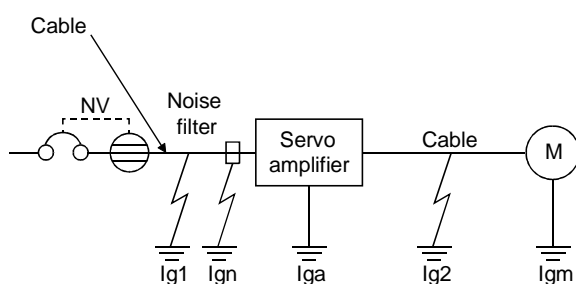
(1) Selection method

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 a leakage current breaker according to the following formula, and ground the servo amplifier, servo motor, etc. securely.

Make the input and output cables as short as possible, and also make the grounding cable as long as possible (about 30cm (11.8 in)) to minimize leakage currents.

$$\text{Rated sensitivity current} \geq 10 \cdot \{I_{g1} + I_{gn} + I_{ga} + K \cdot (I_{g2} + I_{gm})\} \text{ [mA]} \dots\dots\dots (12.2)$$



K: Constant considering the harmonic contents

Leakage current breaker		K
Type	Mitsubishi products	
Models provided with harmonic and surge reduction techniques	NV-SP NV-SW NV-CP NV-CW NV-L	1
General models	BV-C1 NFB NV-L	3

I_{g1} : Leakage current on the electric channel from the leakage current breaker to the input terminals of the servo amplifier (Found from Fig. 12.1.)

I_{g2} : Leakage current on the electric channel from the output terminals of the servo amplifier to the servo motor (Found from Fig. 12.1.)

I_{gn} : Leakage current when a filter is connected to the input side (4.4mA per one FR-BIF)

I_{ga} : Leakage current of the servo amplifier (Found from Table 12.4.)

I_{gm} : Leakage current of the servo motor (Found from Table 12.3.)

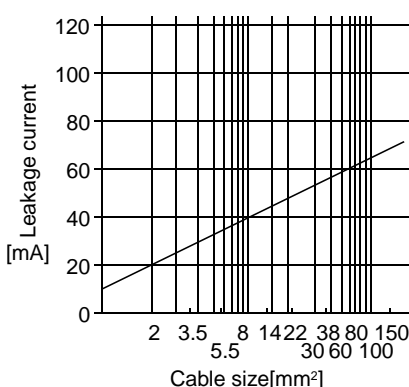


Fig. 12.1 Leakage current example (I_{g1} , I_{g2}) for CV cable run in metal conduit

Table 12.3 Servo motor's leakage current example (I_{gm})

Servo motor output [kW]	Leakage current [mA]
0.05 to 1	0.1
2	0.2
3.5	0.3

Table 12.4 Servo amplifier's leakage current example (I_{ga})

Servo amplifier capacity [kW]	Leakage current [mA]
0.1 to 0.6	0.1
0.75 to 3.5	0.15

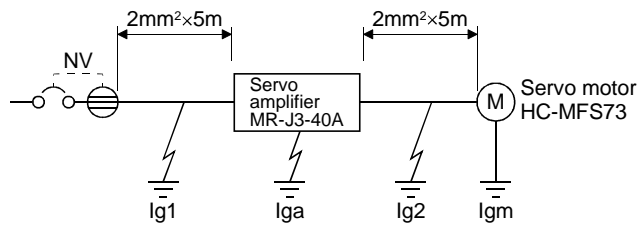
Table 12.5 Leakage circuit breaker selection example

Servo amplifier	Rated sensitivity current of leakage circuit breaker [mA]
MR-J3-10A to MR-J3-350A MR-J3-10A1 to MR-J3-40A1	15

12. OPTIONS AND AUXILIARY EQUIPMENT

(2) Selection example

Indicated below is an example of selecting a leakage current breaker under the following conditions:



Use a leakage current breaker generally available.

Find the terms of Equation (12.2) 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 (12.2):

$$I_g \geq 10 \cdot \{0.1+0+0.1+1 \cdot (0.1+0.1)\}$$

$$\geq 4.0 \text{ [mA]}$$

According to the result of calculation, use a leakage current breaker having the rated sensitivity current (I_g) of 4.0[mA] or more. A leakage current breaker having I_g of 15[mA] is used with the NV-SP/SW/CP/CW/HW series.

12. OPTIONS AND AUXILIARY EQUIPMENT

12.14 EMC filter (Recommended)

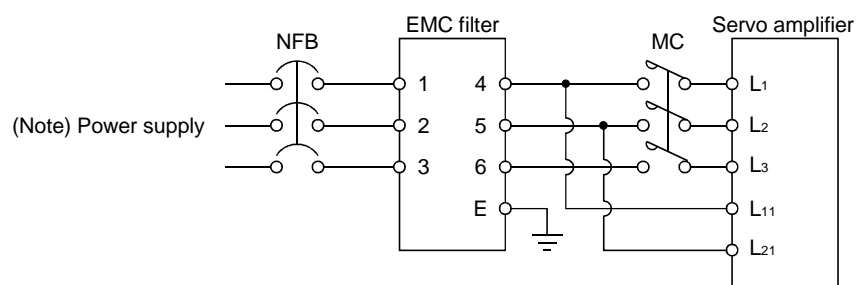
For compliance with the EMC directive of the EN Standard, it is recommended to use the following filter: Some EMC filters are large in leakage current.

(1) Combination with the servo amplifier

Servo amplifier	Recommended filter		Mass [kg]([lb])
	Model	Leakage current [mA]	
MR-J3-10A to MR-J3-100A MR-J3-10A1 to MR-J3-40A1	(Note) HF3010A-UN	5	3 (6.61)
MR-J3-250A ▪ MR-J3-350A	(Note) HF3030A-UN	5	5.5 (12.13)

Note. Soshin Electric A surge protector is separately required to use any of these EMC filters. (Refer to the EMC Installation Guidelines.)

(2) Connection example

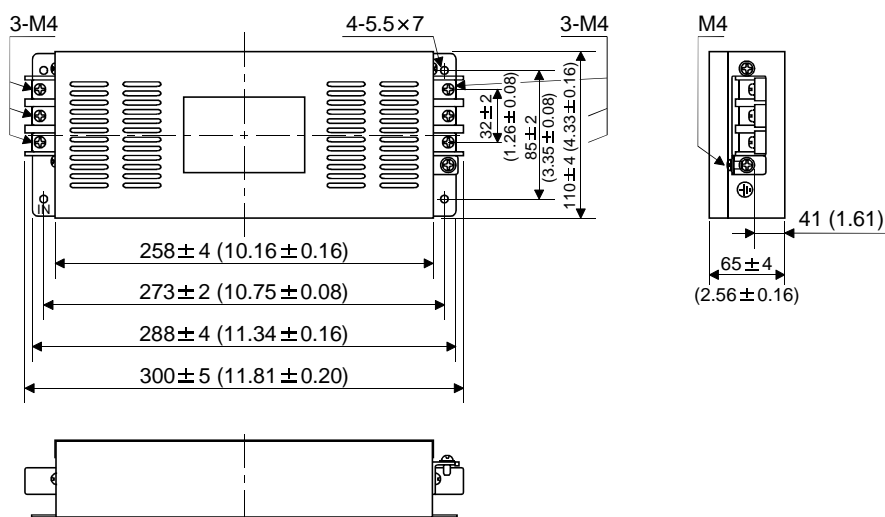


Note. For 1-phase 230VAC power supply, connect the power supply to L1, L2 and leave L3 open.
There is no L3 for 1-phase 100 to 120VAC power supply.

(3) Outline drawing

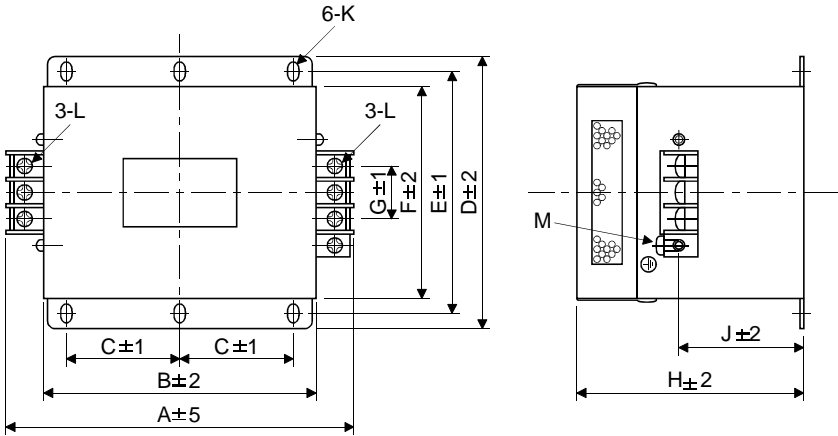
HF3010A-UN

[Unit: mm(in)]



12. OPTIONS AND AUXILIARY EQUIPMENT

HF3030-UN



Model	Dimensions [mm(in)]											
	A	B	C	D	E	F	G	H	J	K	L	M
HF3030-UN	260 (10.24)	210 (8.27)	85 (8.35)	155 (6.10)	140 (5.51)	125 (4.92)	44 (1.73)	140 (5.51)	70 (2.76)	R3.24, length 8 (0.32)	M5	M4

MEMO

This image shows a single sheet of white paper with horizontal ruling lines. The lines are evenly spaced and run across the width of the page. There are no margins, text, or other markings on the paper.

13. COMMUNICATION FUNCTION

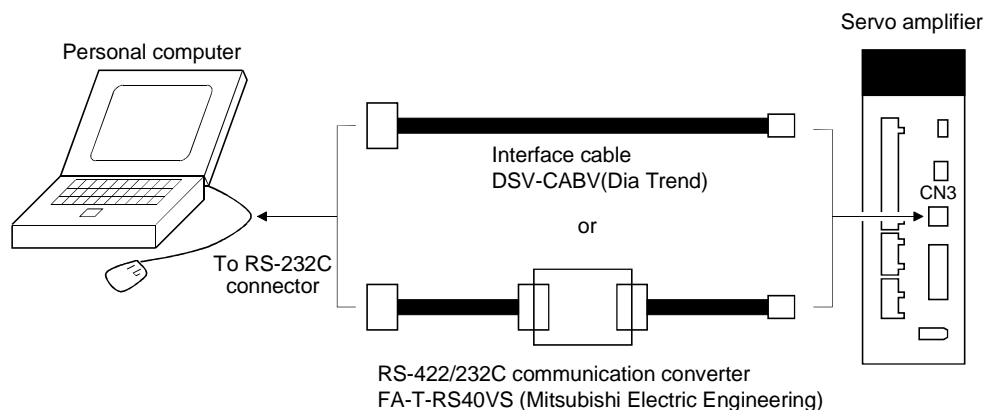
13. COMMUNICATION FUNCTION

Using the serial communication function of RS-422, this servo amplifier enables servo operation, parameter change, monitor function, etc.

13.1 Configuration

(1) Single axis

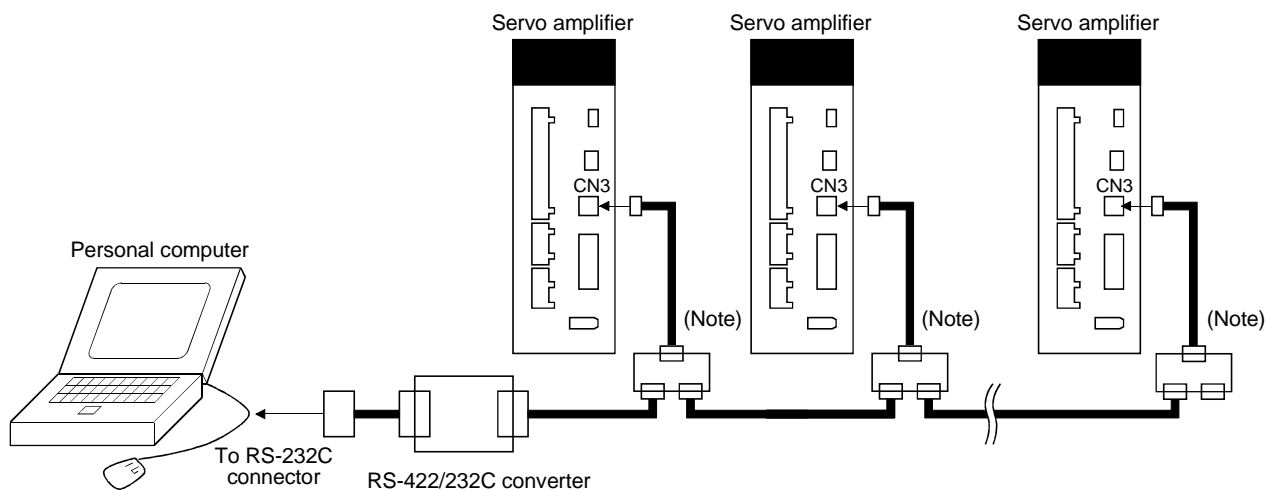
Operate the single-axis servo amplifier. It is recommended to use the following cable or RS-422/232C communication converter.



(2) Multidrop connection

(a) Diagrammatic sketch

Up to 32 axes of servo amplifiers from stations 0 to 31 can be operated on the same bus.

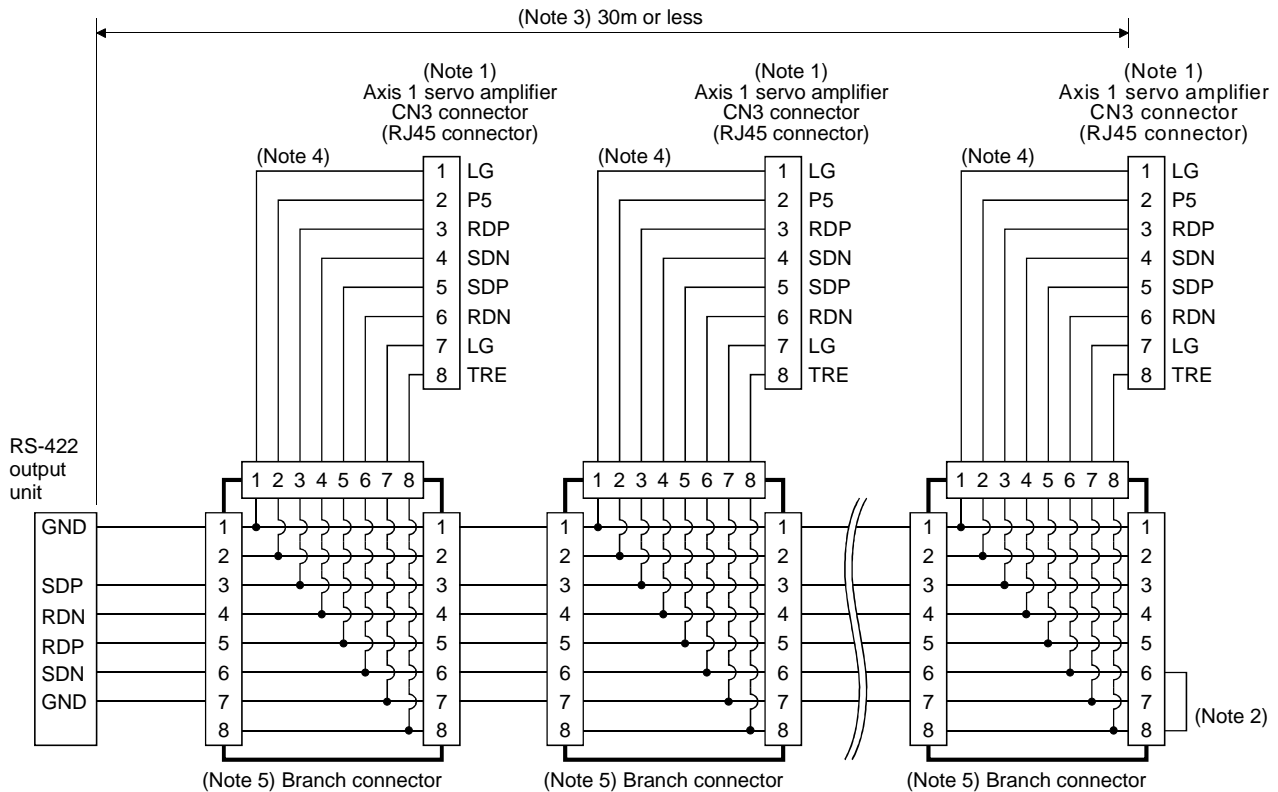


Note. The BMJ-8 (Hakko Electric Machine Works) is recommended as the branch connector.

13. COMMUNICATION FUNCTION

(b) Cable connection diagram

Wire the cables as shown below.



Note 1. Recommended connector (Hirose Electric)

Plug: TM10P-88P

Connection tool: CL250-0228-1

2. For the last axis, connect TRE and RDN.

3. The overall length is 30m or less in low-noise environment.

4. The wiring between the branch connector and servo amplifier should be as short as possible.

Use the EIA568-compliant cable (10BASE-T cable, etc.).

Recommended cable: SGLPE-V 0.5mm x 4P (Mitsubishi Cable Industries)

5. Recommended branch connector: BMJ-8 (Hakko Electric Machine Works)

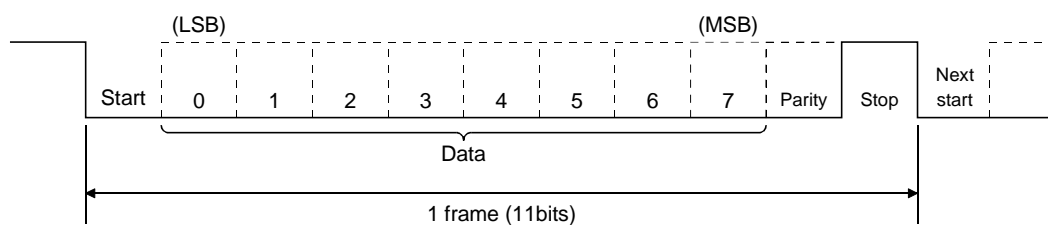
13. COMMUNICATION FUNCTION

13.2 Communication specifications

13.2.1 Communication overview

This servo amplifier is designed to send a reply on receipt of an instruction. The device which gives this instruction (e.g. personal computer) is called a master station and the device which sends a reply in response to the instruction (servo amplifier) is called a slave station. When fetching data successively, the master station repeatedly commands the slave station to send data.

Item	Description
Baudrate	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 protocol	Character system, half-duplex communication system



13. COMMUNICATION FUNCTION

13.2.2 Parameter setting

When the USB/RS-422 communication function is used to operate the servo, set the communication specifications of the servo amplifier in the corresponding parameters.

After setting the values of these parameters, they are made valid by switching power off once, then on again.

(1) Serial communication baudrate

Choose the communication speed. Match this value to the communication speed of the sending end (master station).

Parameter No. PC21

--	--	--	--

Communication baudrate
0: 9600[bps]
1: 19200[bps]
2: 38400[bps]
3: 57600[bps]
4: 115200[bps]

(2) RS-422 communication response delay time

Set the time from when the servo amplifier (slave station) receives communication data to when it sends back data. Set "0" to send back data in less than 800 μ s or "1" to send back data in 800 μ s or more.

Parameter No. PC21

--	--	--	--

RS422 communication response delay time
0: Invalid
1: Valid, reply sent in 800 μ s or more

(3) Station number setting

Set the station number of the servo amplifier in parameter No. PC20. The setting range is stations 0 to 31.

13. COMMUNICATION FUNCTION

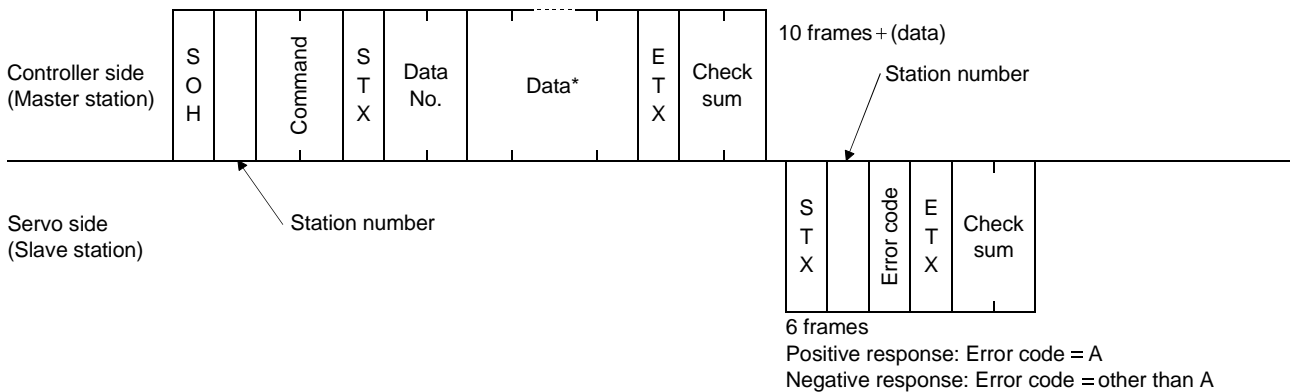
13.3 Protocol

13.3.1 Transmission data configuration

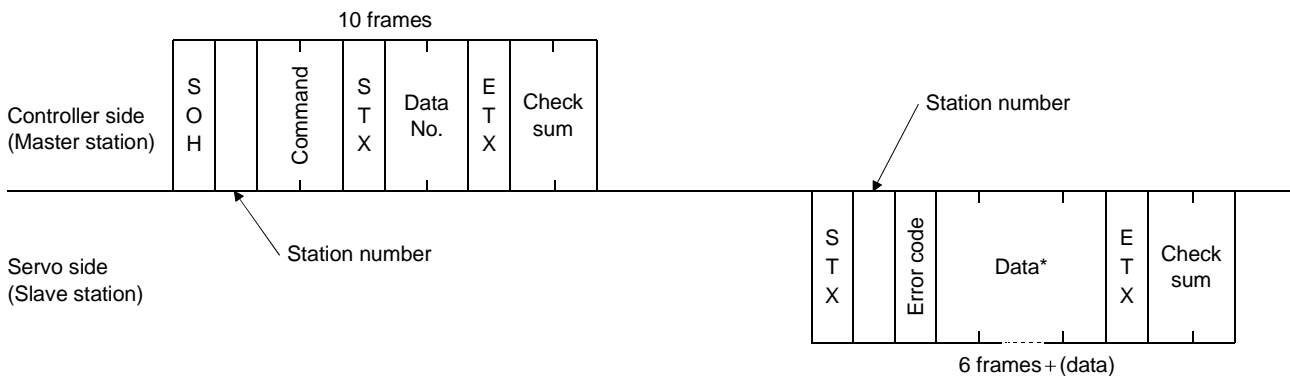
Since up to 32 axes may be connected to the bus, add a station number to the command, data No., etc. to determine the destination servo amplifier of data communication. Set the station number to each servo amplifier using the parameter. Transmission data is valid for the servo amplifier of the specified station number or group.

When "*" is set as the station number added to the transmission data, the transmission data is made valid 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 number of the servo amplifier which must provide the return data.

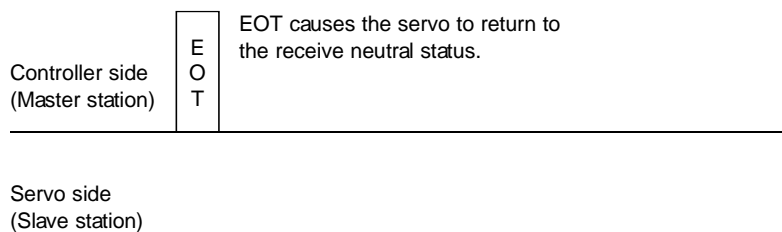
(1) Transmission of data from the controller to the servo



(2) Transmission of data request from the controller to the servo

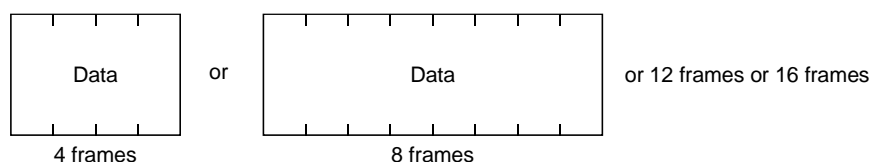


(3) Recovery of communication status by time-out



(4) Data frames

The data length depends on the command.



13. COMMUNICATION FUNCTION

13.3.2 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

ASCII unit codes are used.

→	b ₈	0	0	0	0	0	0	0	0
→	b ₇	0	0	0	0	1	1	1	1
→	b ₆	0	0	1	1	0	0	1	1
→	b ₅	0	1	0	1	0	1	0	1

b ₈ to b ₅	b ₄	b ₃	b ₂	b ₁	C \ R	0	1	2	3	4	5	6	7
	0	0	0	0	0	NUL	DLE	Space	0	@	P	`	p
	0	0	0	1	1	SOH	DC ₁	!	1	A	Q	a	q
	0	0	1	0	2	STX	DC ₂	"	2	B	R	b	r
	0	0	1	1	3	ETX	DC ₃	#	3	C	S	c	s
	0	1	0	0	4			\$	4	D	T	d	t
	0	1	0	1	5			%	5	E	U	e	u
	0	1	1	0	6			&	6	F	V	f	v
	0	1	1	1	7			'	7	G	W	g	w
	1	0	0	0	8			(8	H	X	h	x
	1	0	0	1	9)	9	I	Y	i	y
	1	0	1	0	10			*	:	J	Z	j	z
	1	0	1	1	11			+	:	K	[k	{
	1	1	0	0	12			,	<	L	¥	l	
	1	1	0	1	13			-	=	M]	m	}
	1	1	1	0	14			.	>	N	^	n	_
	1	1	1	1	15			/	?	O	_	o	DEL

(3) Station numbers

You may set 32 station numbers from station 0 to station 31 and the ASCII unit codes are used to specify the stations.

Station number	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 number	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 number of "0" (axis 1).

13. COMMUNICATION FUNCTION

13.3.3 Error codes

Error codes are used in the following cases and an error code of single-code length is transmitted.

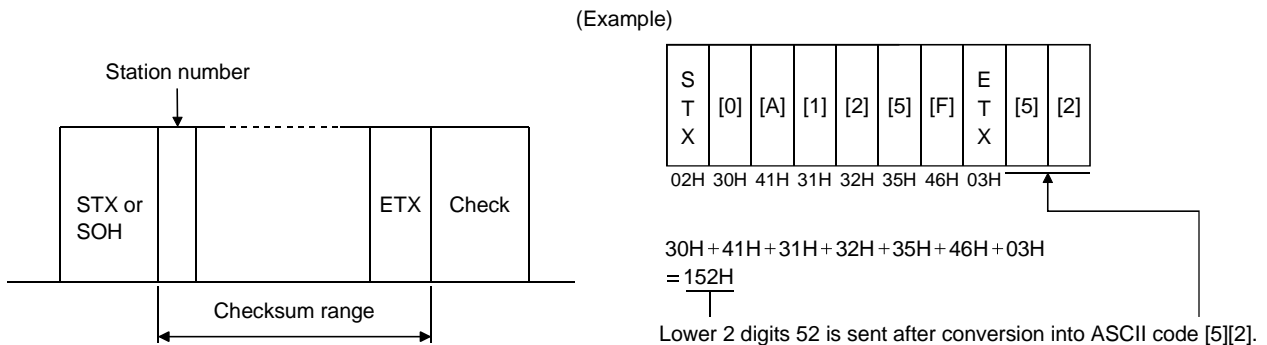
On receipt of data from the master station, the slave station sends the error code corresponding to that data to the master station.

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	Description	Remarks
Servo normal	Servo alarm			
[A]	[a]	Normal operation	Data transmitted was processed properly.	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	Character not existing in the specifications was transmitted.	
[E]	[e]	Command error	Command not existing in the specifications was transmitted.	
[F]	[f]	Data No. error	Data No. not existing in the specifications was transmitted.	

13.3.4 Checksum

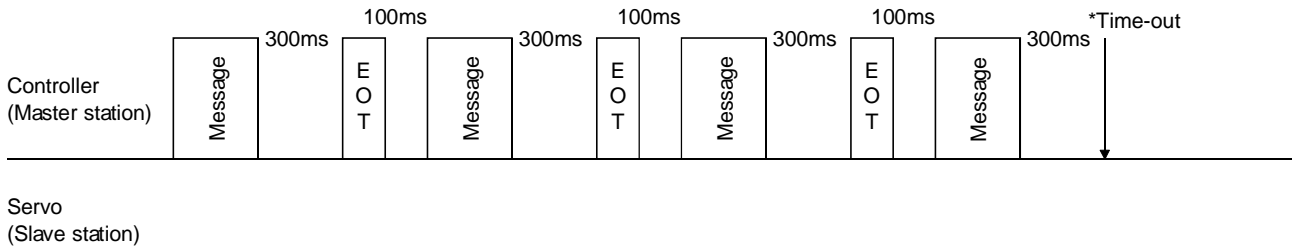
The check sum is a ASCII-coded hexadecimal representing the lower two digits of the sum of ASCII-coded hexadecimal numbers up to ETX, with the exception of the first control code (STX or SOH).



13. COMMUNICATION FUNCTION

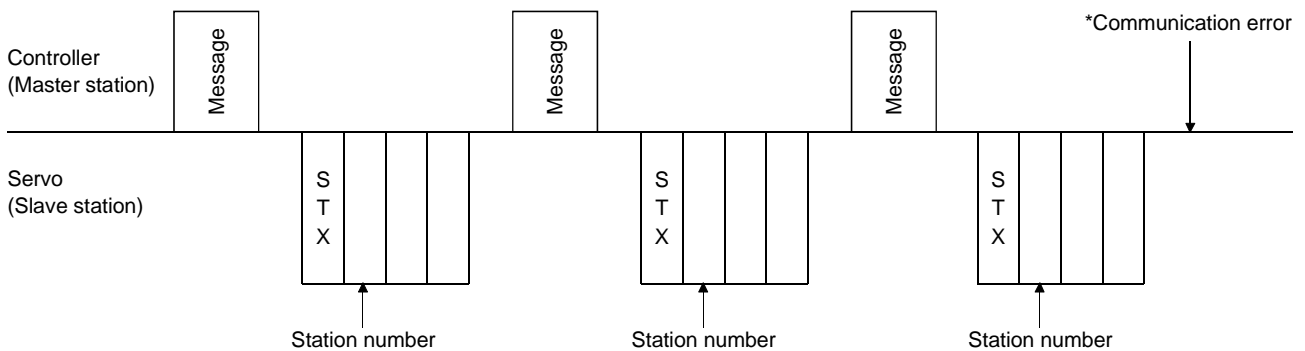
13.3.5 Time-out operation

The master station transmits EOT when the slave station does not start reply operation (STX is not received) 300[ms] after the master station has ended communication operation. 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 operation three times. (Communication error)



13.3.6 Retry operation

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 operation). A communication error occurs if the above operation 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 operation is performed three times.

13. COMMUNICATION FUNCTION

13.3.7 Initialization

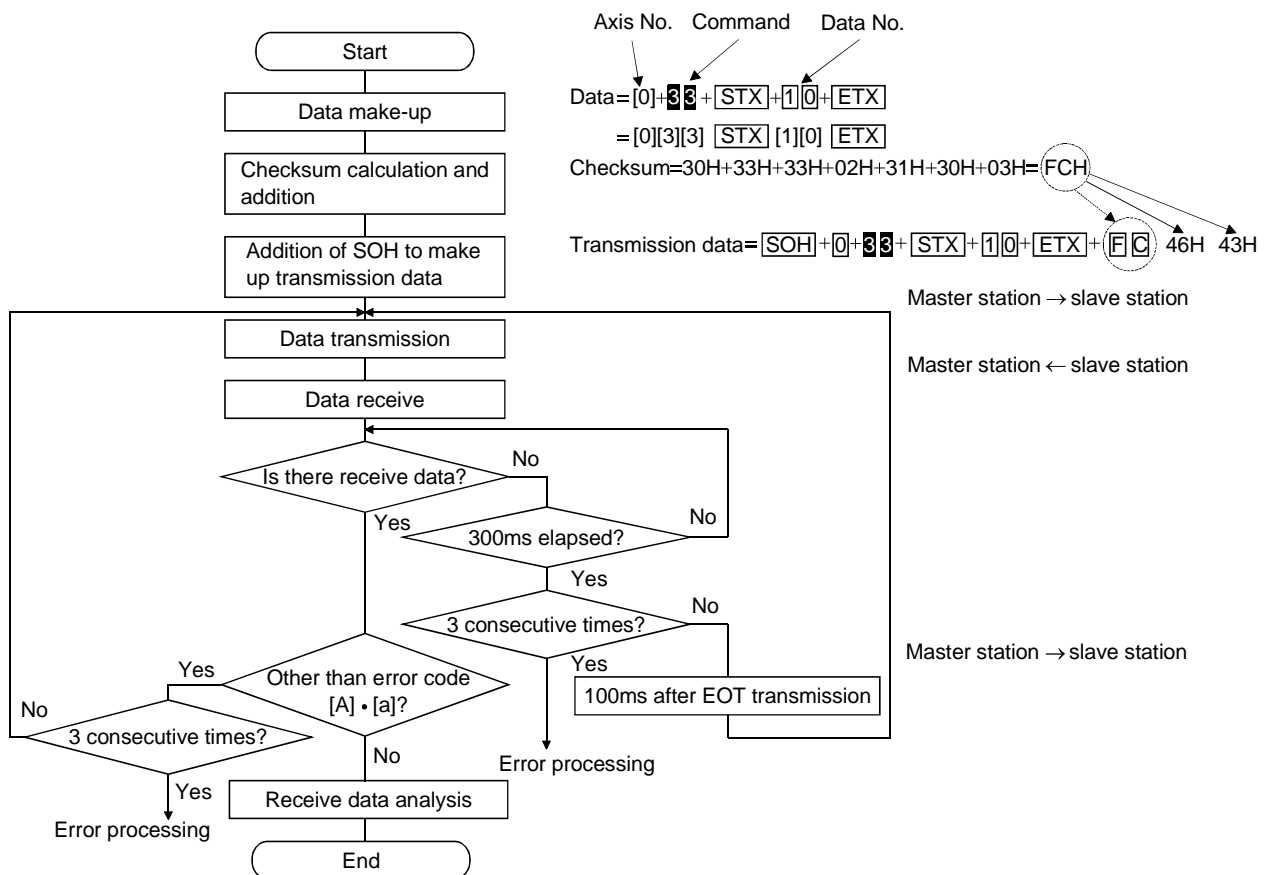
After the slave station is switched on, it cannot reply to communication until the internal initialization processing terminates. Hence, at power-on, ordinary communication should be started after:

- (1) 1s or more time has elapsed after the slave station is switched on; and
- (2) Making sure that normal communication can be made by reading the parameter or other data which does not pose any safety problems.

13.3.8 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 number	0	Servo amplifier station 0
Command	33	Read command
Data No.	10	Alarm history (last alarm)



13. COMMUNICATION FUNCTION

13.4 Command and Data No. List

POINT	
▪ If the command and data No. are the same, the description may be different from that of the other servo amplifier.	

13.4.1 Read commands

(1) Status display (Command [0][1])

Command	Data No.	Description	Display Item	Frame Length
[0][1]	[0][0]	Status display name and unit	Cumulative feedback pulse	16
	[0][1]		Servo motor speed	
	[0][2]		Droop pulse	
	[0][3]		Cumulative command pulse	
	[0][4]		Command pulse frequency	
	[0][5]		Analog speed command voltage	
			Analog speed limit voltage	
	[0][6]		Analog torque command voltage	
			Analog torque limit voltage	
	[0][7]		Regenerative load ratio	
	[0][8]		Effective load ratio	
	[0][9]		Peak load ratio	
	[0][A]		Instantaneous torque	
	[0][B]		Within one-revolution position	
	[0][C]		ABS counter	
	[0][D]		Load inertia moment ratio	
	[0][E]		Bus voltage	
	[8][0]	Status display data value and processing information	Cumulative feedback pulse	12
	[8][1]		Servo motor speed	
	[8][2]		Droop pulse	
	[8][3]		Cumulative command pulse	
	[8][4]		Command pulse frequency	
	[8][5]		Analog speed command voltage	
			Analog speed limit voltage	
	[8][6]		Analog torque command voltage	
			Analog torque limit voltage	
	[8][7]		Regenerative load ratio	
	[8][8]		Effective load ratio	
	[8][9]		Peak load ratio	
	[8][A]		Instantaneous torque	
	[8][B]		Within one-revolution position	
	[8][C]		ABS counter	
	[8][D]		Load inertia moment ratio	
	[8][E]		Bus voltage	

13. COMMUNICATION FUNCTION

(2) Parameters (Command [0][4] · [0][5] · [0][6] · [0][7] · [0][8] · [0][9])

Command	Data No.	Description	Frame Length
[0][4]	[0][1]	Parameter group read 0000: Basic setting parameter (No.PA□□) 0001: Gain filter parameter (No.PB□□) 0002: Extension setting parameter (No.PC□□) 0003: I/O setting parameter (No.PD□□)	4
[0][5]	[0][0] 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 number.	8
[0][6]	[0][0] 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 number.	8
[0][7]	[0][0] 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 number.	8
[0][8]	[0][0] to [F][F]	Abbreviations of parameters Reads the abbreviations of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading the abbreviations, 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 number.	12
[0][9]	[0][0] to [F][F]	Write enable/disable of parameters Reads write enable/disable of the parameters in the parameter group specified with the command [8][5] + data No. [0][0]. Before reading write enable/disable, therefore, always specify the parameter group with the command [8][5] + data No. [0][0]. 0000: Write enabled 0001: Write 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	

13. COMMUNICATION FUNCTION

(4) Alarm history (Command [3][3])

Command	Data No.	Description	Alarm Occurrence Sequence	Frame Length
[3] [3]	[1] [0]	Alarm number 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	
	[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	

(5) Current alarm (Command [0][2] • [3][5])

Command	Data No.	Description	Frame Length
[0] [2]	[0] [0]	Current alarm number	4
	[0] [1]	Current alarm symbol	12
	[0] [8]	Concurrent alarm number	4
	[0] [9]	Concurrent alarm symbol	12

13. COMMUNICATION FUNCTION

Command	Data No.	Description	Display Item	Frame Length
[3][5]	[0][0]	Status display name and unit at alarm occurrence	Cumulative feedback pulse	16
	[0][1]		Servo motor speed	
	[0][2]		Droop pulse	
	[0][3]		Cumulative command pulse	
	[0][4]		Command pulse frequency	
	[0][5]		Analog speed command voltage	
			Analog speed limit voltage	
	[0][6]		Analog torque command voltage	
			Analog torque limit voltage	
	[0][7]		Regenerative load ratio	
	[0][8]		Effective load ratio	
	[0][9]		Peak load ratio	
	[0][A]		Instantaneous torque	
	[0][B]		Within one-revolution position	
	[0][C]		ABS counter	
	[0][D]		Load inertia moment ratio	
	[0][E]		Bus voltage	
	[8][0]	Status display data value and processing information at alarm occurrence	Cumulative feedback pulse	12
	[8][1]		Servo motor speed	
	[8][2]		Droop pulse	
	[8][3]		Cumulative command pulse	
	[8][4]		Command pulse frequency	
	[8][5]		Analog speed command voltage	
			Analog speed limit voltage	
	[8][6]		Analog torque command voltage	
			Analog torque limit voltage	
	[8][7]		Regenerative load ratio	
	[8][8]		Effective load ratio	
	[8][9]		Peak load ratio	
	[8][A]		Instantaneous torque	
	[8][B]		Within one-revolution position	
	[8][C]		ABS counter	
	[8][D]		Load inertia moment ratio	
	[8][E]		Bus voltage	

13. COMMUNICATION FUNCTION

(6) Test operation mode (Command [0][0])

Command	Data No.	Description	Frame Length
[0] [0]	[1] [2]	Test operation mode read 0000: Normal mode (not test operation mode) 0001: JOG operation 0002: Positioning operation 0003: Motorless operation 0004: Output signal (DO) forced output	4
[0] [0]	[2] [1]	Reads the status during test operation mode (positioning operation). 0000: Positioning completion (waiting for start signal) 0001: During positioning operation 0002: During temporary stop	4

(7) Others

Command	Data No.	Description	Frame Length
[0] [2]	[9] [0]	Servo motor end pulse unit absolute position	8
	[9] [1]	Command unit absolute position	8
	[7] [0]	Software version	16

13. COMMUNICATION FUNCTION

13.4.2 Write commands

(1) Status display (Command [8][1])

Command	Data No.	Description	Setting Range	Frame Length
[8] [1]	[0] [0]	Status display data erasure	1EA5	4

(2) Parameters (Command [8][4] · [8][5])

Command	Data No.	Description	Setting Range	Frame Length
[8] [4]	[0] [0] to [F] [F]	Write of parameters 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 number.	Depending on the parameter	8
[8] [5]	[0] [0]	Parameter group write 0000: Basic setting parameter (No. PA□□) 0001: Gain filter parameter (No. PB□□) 0002: Extension setting parameter (No. PC□□) 0003: I/O setting parameter (No. PD□□)	0000 to 0003	4

(3) External I/O signal (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 erasure	1EA5	4

(5) Current alarm (Command [8][2])

Command	Data No.	Description	Setting Range	Frame Length
[8] [2]	[0] [0]	Alarm erasure	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 EMG, LSP and LSN, independently of the external ON/OFF status.	1EA5	4
	[0] [3]	Changes the output device into the value of command [8][B] or command [A][0] + data No. [0][1].	1EA5	4
	[1] [0]	Cancels the prohibition of the input device, external analog input signal or pulse train input, except EMG, LSP and LSN.	1EA5	4
	[1] [3]	Cancels the prohibition of the output device.	1EA5	4

13. COMMUNICATION FUNCTION

(7) Operation mode selection (Command [8][B])

Command	Data No.	Description	Setting Range	Frame Length
[8] [B]	[0] [0]	Operation mode switching 0000: Test operation mode cancel 0001: JOG operation 0002: Positioning operation 0003: Motorless operation 0004: Output signal (DO) forced output	0000 to 0004	4

(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 13.5.7.	8
	[A] [0]	Forced output of signal pin	Refer to Section 13.5.9.	8
[A] [0]	[1] [0]	Writes the speed in the test operation mode (JOG operation, positioning operation).	0000 to 7FFF	4
	[1] [1]	Writes the acceleration/deceleration time constant in the test operation mode (JOG operation, positioning operation).	00000000 to 7FFFFFFF	8
	[2] [0]	Cancels the acceleration/deceleration time constant in the test operation mode (JOG operation, positioning operation).	00000000 to 7FFFFFFF	8
	[2] [1]	Selects the positioning direction of test operation (positioning operation). 0000: Forward rotation direction 0001: Reverse rotation direction	0000 to 0001	4
	[4] [0]	Test operation (positioning operation) start command.	1EA5	4
	[4] [1]	Used to make a temporary stop during test operation (positioning operation). <input type="checkbox"/> in the data indicates a blank. STOP: Temporary stop G0 <input type="checkbox"/> <input type="checkbox"/> : Restart for remaining distance CLR <input type="checkbox"/> : Remaining distance clear.	STOP G0 <input type="checkbox"/> <input type="checkbox"/> CLR <input type="checkbox"/>	4

13. COMMUNICATION FUNCTION

13.5 Detailed explanations of commands

13.5.1 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 reply or data according to 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 according to 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.

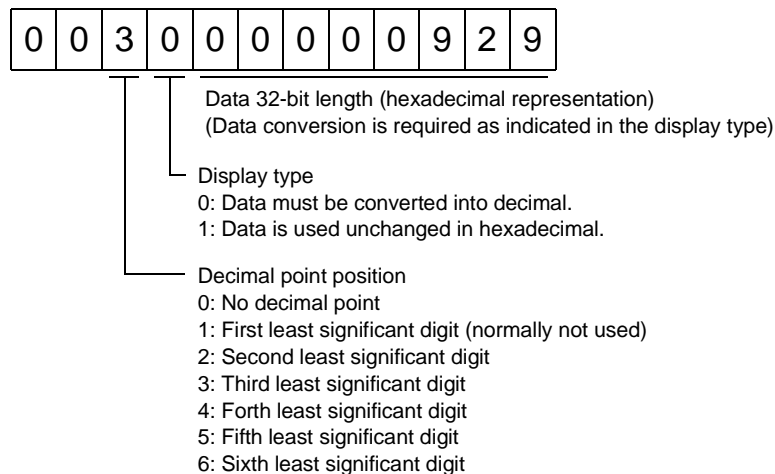
(1) Processing the read data

When the display type is 0, the eight-character data is converted from hexadecimal to decimal and a decimal point is placed according to the decimal point position information.

When the display type is 1, the eight-character data is used 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, the hexadecimal data is converted into decimal.

00000929H→2345

As the decimal point position is "3", a decimal point is placed in the third least significant digit.

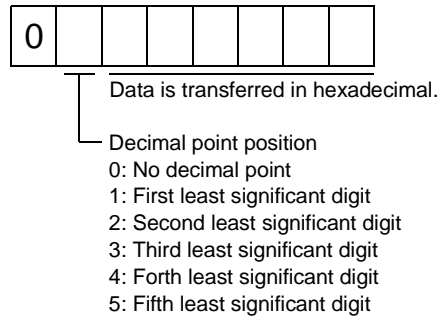
Hence, "23.45" is displayed.

13. COMMUNICATION FUNCTION

(2) Writing the 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.



By way of 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 digit, the decimal point position data is "2".

As the data to be sent is hexadecimal, the decimal data is converted into hexadecimal.

155→9B

Hence, "0200009B" is transmitted.

13. COMMUNICATION FUNCTION

13.5.2 Status display

(1) Reading the status display name and unit

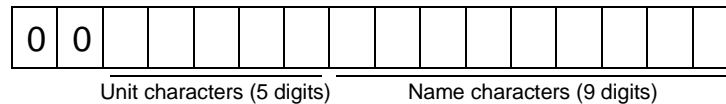
Read the status display name and unit.

(a) Transmission

Transmit command [0][1] and the data No. corresponding to the status display item to be read, [0][0] to [0][E]. (Refer to Section 13.4.1.)

(b) Reply

The slave station sends back the status display name and unit requested.



(2) Status display data read

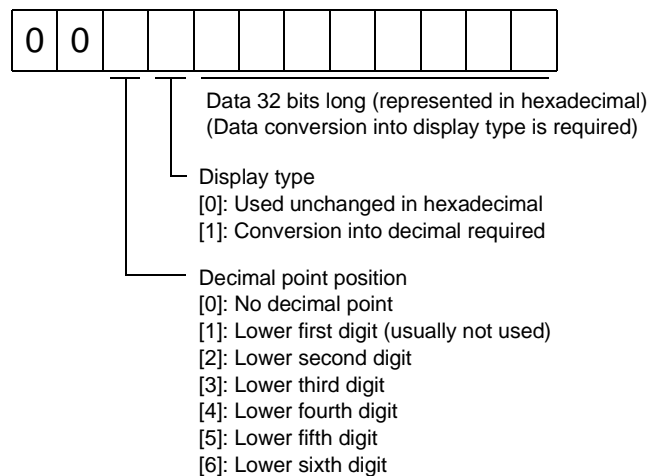
Read the status display data and processing information.

(a) Transmission

Transmit command [0][1] and the data No. corresponding to the status display item to be read.
Refer to Section 13.4.1.

(b) Reply

The slave station sends back the status display data requested.



(3) Status display data clear

The cumulative feedback pulse data of the status display is cleared. Send this command immediately after reading the status display item. The data of the status display item transmitted is cleared to zero.

Command	Data No.	Data
[8][1]	[0][0]	[1][E][A][5]

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 zero.

13. COMMUNICATION FUNCTION

13.5.3 Parameters

(1) Specify the parameter group

The group of the parameters to be operated must be specified in advance to read or write the parameter settings, etc. Write data to the servo amplifier as described below to specify the parameter group to be operated.

Command	Data No.	Transmission Data	Parameter Group
[8] [5]	[0] [0]	0000	Basic setting parameter (No.PA□□)
		0001	Gain filter parameter (No.PB□□)
		0002	Extension setting parameter (No.PC□□)
		0003	I/O setting parameter (No.PD□□)

(2) Reading the symbol

Read the parameter name. Specify the parameter group in advance (refer to (1) in this section).

(a) Transmission

Transmit command [0][8] and the data No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to Section 13.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the name of the parameter No. requested.

0	0	0									
---	---	---	--	--	--	--	--	--	--	--	--

Name characters (9 digits)

13. COMMUNICATION FUNCTION

(3) Reading the setting

Read the parameter setting. Specify the parameter group in advance (refer to (1) in this section).

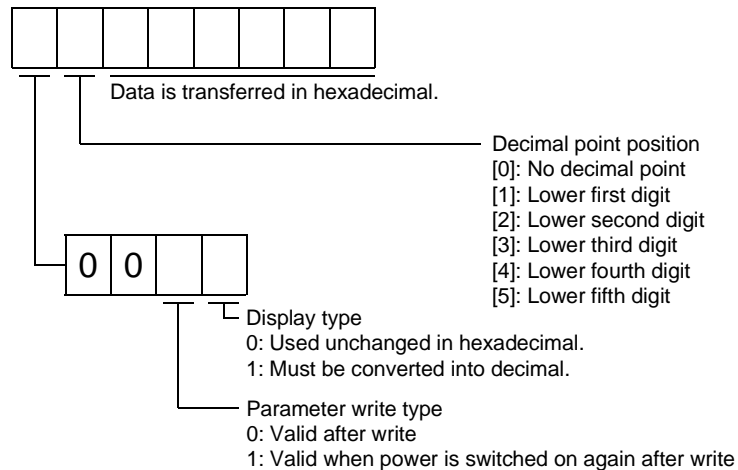
(a) Transmission

Transmit command [0][5] and the data No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to Section 13.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the data and processing information of the parameter No. requested.



For example, data "1200270F" means 999.9 (decimal display format) and data "0003ABC" 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 "01FFF053" means 053 (special hexadecimal display format).

"000000" is transferred when the parameter that was read is the one inaccessible for write/reference in the parameter write disable setting of parameter No. 19.

(4) Reading the setting range

Read the parameter setting range. Specify the parameter group in advance (refer to (1) in this section).

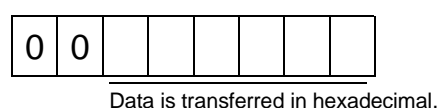
(a) Transmission

When reading the upper limit value, transmit command [0][6] and the data No. corresponding to the parameter No., [0][0] to [F][F]. When reading the lower limit value, transmit command [0][7] and the data No. corresponding to the parameter No., [0][0] to [F][F]. (Refer to Section 13.4.1.)

The data No. is expressed in hexadecimal. The decimal equivalent of the data No. value corresponds to the parameter number.

(b) Reply

The slave station sends back the data and processing information of the parameter No. requested.



For example, data "10FFFFEC" means -20.

13. COMMUNICATION FUNCTION

(5) Parameter write

POINT
▪ The number of parameter write times is restricted to 100,000 times.

Write the parameter setting into EEPROM of the servo amplifier. Specify the parameter group in advance (refer to (1) in this section).

Write the value within the setting enabled range. For the setting enabled range, refer to Chapter 5 or read the setting range by performing operation in (3) of this section.

Transmit command [8][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 number.

When the data to be written is handled as decimal, the decimal point position must be specified. If it is not specified, data cannot be written. When the data is handled as hexadecimal, specify 0 as the decimal point position.

Write the data after making sure that it is within the upper/lower limit value range.

Read the parameter data to be written, confirm the decimal point position, and create transmission data to prevent error occurrence. On completion of write, read the same parameter data to verify that data has been written correctly.

Command	Data No.	Set data
[8][4]	[0][0] to [F][F]	See below.

--	--	--	--	--	--	--	--

Data is transferred in hexadecimal.

Decimal point position

0: No decimal point

1: Lower first digit

2: Lower second digit

3: Lower third digit

4: Lower fourth digit

5: Lower fifth digit

Write mode

0: Write to EEPROM

3: Write to RAM

When the parameter data is changed frequently through communication, set "3" to the write 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 EEPROM.

13. COMMUNICATION FUNCTION

13.5.4 External I/O signal statuses (DI0 diagnosis)

(1) Reading of input device statuses

Read the statuses of the input devices.

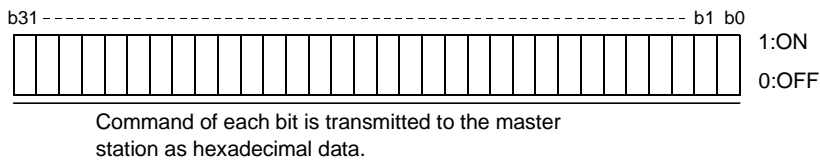
(a) Transmission

Transmit command [1][2] and data No. [0][0].

Command	Data No.
[1][2]	[0][0]

(b) Reply

The slave station sends back the statuses of the input pins.



bit	Abbreviation
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

bit	Abbreviation
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

bit	Abbreviation
16	
17	
18	
19	
20	STAB2
21	
22	
23	

bit	Abbreviation
24	
25	
26	
27	CDP
28	
29	
30	
31	

(2) External input pin status read

Read the ON/OFF statuses of the external output pins.

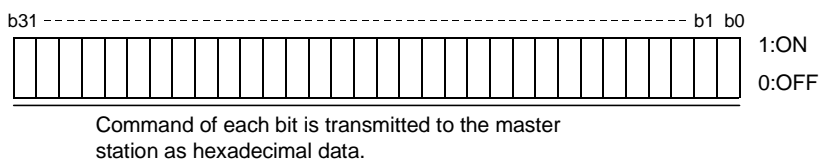
(a) Transmission

Transmit command [1][2] and data No. [4][0].

Command	Data No.
[1][2]	[4][0]

(b) Reply

The ON/OFF statuses of the input pins are sent back.



bit	CN1 connector pin
0	43
1	44
2	42
3	15
4	19
5	41
6	16
7	17

bit	CN1 connector pin
8	18
9	45
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	

13. COMMUNICATION FUNCTION

(3) Read of the statuses of input devices switched on through communication

Read the ON/OFF statuses of the input devices switched on through communication.

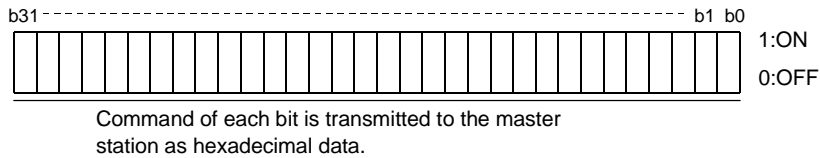
(a) Transmission

Transmit command [1][2] and data No. [6][0].

Command	Data No.
[1][2]	[6][0]

(b) Reply

The slave station sends back the statuses of the input pins.



bit	Abbreviation
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

bit	Abbreviation
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

bit	Abbreviation
16	
17	
18	
19	
20	STAB2
21	
22	
23	

bit	Abbreviation
24	
25	
26	
27	CDP
28	
29	
30	
31	

(4) External output pin status read

Read the ON/OFF statuses of the external output pins.

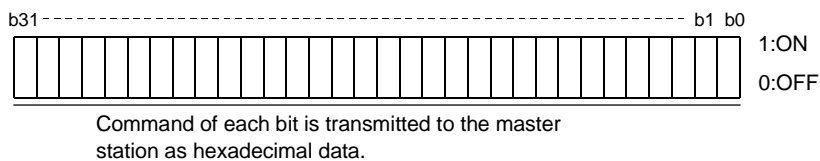
(a) Transmission

Transmit command [1][2] and data No. [C][0].

Command	Data No.
[1][2]	[C][0]

(b) Reply

The slave station sends back the ON/OFF statuses of the output pins.



bit	CN1 connector pin
0	49
1	24
2	23
3	25
4	22
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	

13. COMMUNICATION FUNCTION

(5) Read of the statuses of output devices

Read the ON/OFF statuses of the output devices.

(a) Transmission

Transmit command [1][2] and data No. [8][0].

Command	Data No.
[1][2]	[8][0]

(b) Reply

The slave station sends back the statuses of the output devices.



Command of each bit is transmitted to the master station as hexadecimal data.

bit	Abbreviation
0	RD
1	SA
2	ZSP
3	TLC
4	VLC
5	INP
6	
7	WNG

bit	Abbreviation
8	ALM
9	OP
10	MBR
11	
12	ACD0
13	ACD1
14	ACD2
15	BWNG

bit	Abbreviation
16	
17	
18	
19	
20	
21	
22	
23	

bit	Abbreviation
24	
25	CHGS
26	
27	ABSV
28	
29	
30	
31	

13.5.5 Device ON/OFF

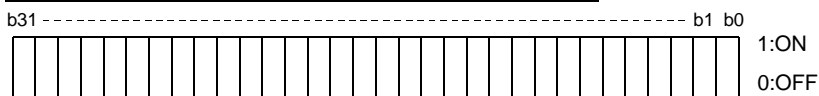
POINT

- The ON/OFF states of all devices in the servo amplifier are the states of the data received last. Hence, when there is a device which must be kept ON, send data which turns that device ON every time.

Each input device can be switched on/off. However, when the device to be switched off exists in the external input signal, also switch off that input signal.

Send command [9][2], data No. [6][0] and data.

Command	Data No.	Set data
[9][2]	[6][0]	See below.



Command of each bit is transmitted to the slave station as hexadecimal data.

bit	Abbreviation
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

bit	Abbreviation
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

bit	Abbreviation
16	
17	
18	
19	
20	STAB2
21	
22	
23	

bit	Abbreviation
24	
25	
26	
27	CDP
28	
29	
30	
31	

13. COMMUNICATION FUNCTION

13.5.6 Disable/enable of I/O devices (DIO)

Inputs can be disabled independently of the I/O devices ON/OFF. When inputs are disabled, the input signals (devices) are recognized as follows. Among the input devices, EMG, LSP and LSN cannot be disabled.

Signal	Status
Input devices (DI)	OFF
External analog input signals	0V
Pulse train inputs	None

- (1) Disabling/enabling the input devices (DI), external analog input signals and pulse train inputs with the exception of EMG, LSP and LSN.

Transmit the following communication commands:

- (a) Disable

Command	Data No.	Data
[9][0]	[0][0]	1EA5

- (b) Enable

Command	Data No.	Data
[9][0]	[1][0]	1EA5

- (2) Disabling/enabling the output devices (DO)

Transmit the following communication commands:

- (a) Disable

Command	Data No.	Data
[9][0]	[0][3]	1EA5

- (b) Enable

Command	Data No.	Data
[9][0]	[1][3]	1EA5

13.5.7 Input devices ON/OFF (test operation)

Each input devices can be turned on/off for test operation. when the device to be switched off exists in the external input signal, also switch off that input signal.

Send 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 slave station as hexadecimal data.

bit	Abbreviation
0	SON
1	LSP
2	LSN
3	TL
4	TL1
5	PC
6	RES
7	CR

bit	Abbreviation
8	SP1
9	SP2
10	SP3
11	ST1
12	ST2
13	CM1
14	CM2
15	LOP

bit	Abbreviation
16	
17	
18	
19	
20	STAB2
21	
22	
23	

bit	Abbreviation
24	
25	
26	
27	CDP
28	
29	
30	
31	

13. COMMUNICATION FUNCTION

13.5.8 Test operation mode

POINT
<ul style="list-style-type: none">▪ The test operation mode is used to confirm operation. Do not use it for actual operation.▪ If communication stops for longer than 0.5s during test operation, the servo amplifier decelerates to a stop, resulting in servo lock. To prevent this, continue communication all the time, e.g. monitor the status display.▪ Even during operation, the servo amplifier can be put in the test operation mode. In this case, as soon as the test operation mode is selected, the base circuit is shut off, coasting the servo amplifier.

(1) Preparation and cancel of test operation mode

(a) Preparation of test operation mode

Set the test operation mode type in the following procedure.

1) Selection of test operation mode

Send the command [8][B] + data No. [0][0] to select the test operation mode.

Command	Data No.	Transmission Data	Test Operation Mode Selection
[8][B]	[0][0]	00001	JOG operation
		00002	Positioning operation
		00003	Motorless operation
		00004	DO forced output (Note)

Note. Refer to Section 13.5.9 for DO forced output.

2) Confirmation of test operation mode

Read the test operation mode set for the slave station, and confirm that it is set correctly.

a. Transmission

Send the command [0][0] + data No. [1][2].

Command	Data No.
[0][0]	[1][2]

b. Return

The slave station returns the set test operation mode.

0	0	0	
---	---	---	--

└ Test operation mode read
0: Normal mode (not test operation mode)
1: JOG operation
2: Positioning operation
3: Motorless operation
4: DO forced output

(b) Cancel of test operation mode

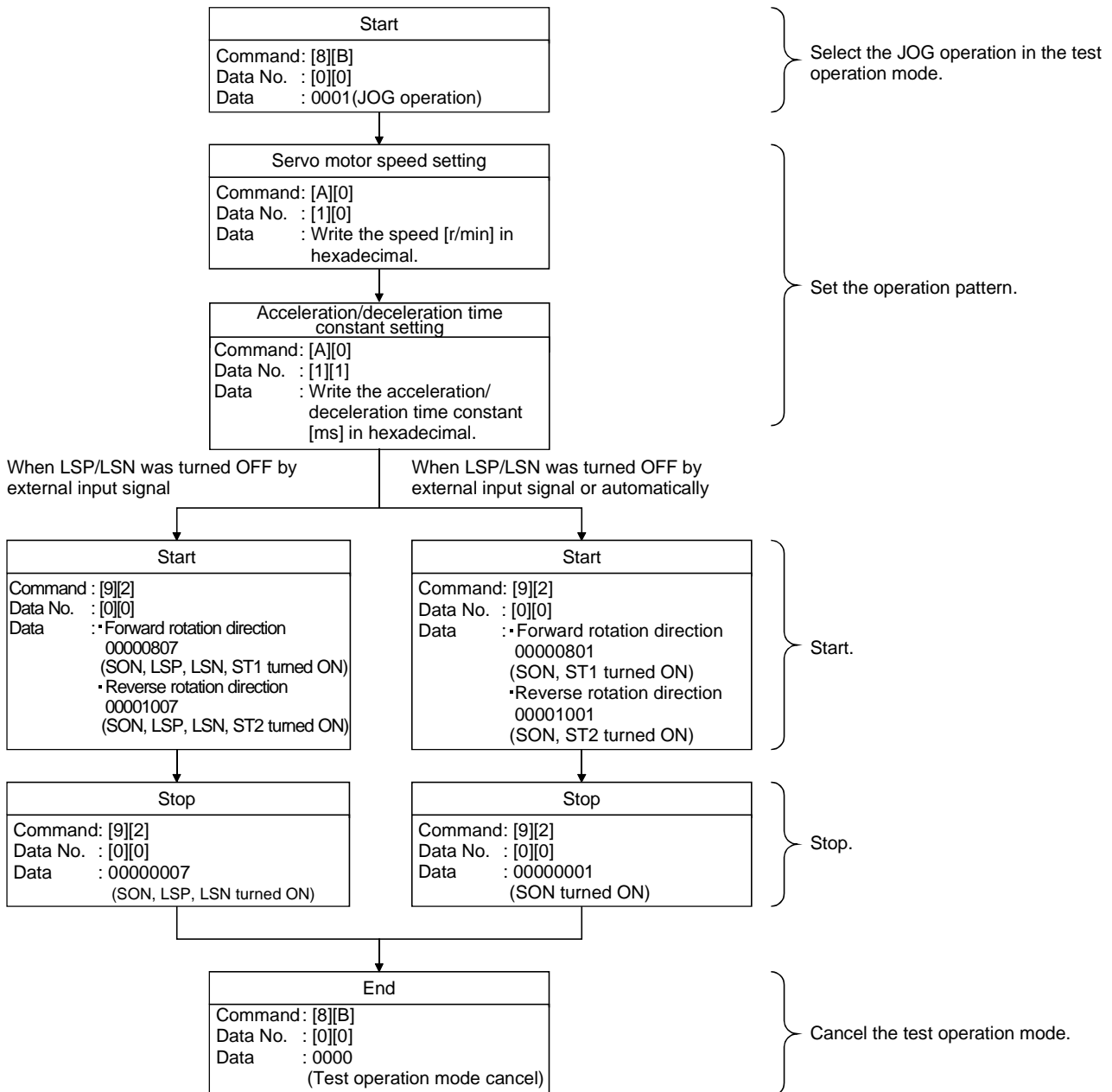
To terminate the test operation mode, send the command [8][B] + data No. [0][0] + data.

Command	Data No.	Transmission Data	Test Operation Mode Selection
[8][B]	[0][0]	0000	Test operation mode cancel

13. COMMUNICATION FUNCTION

(2) JOG operation

Send the command, data No. and data as indicated below to execute JOG operation.

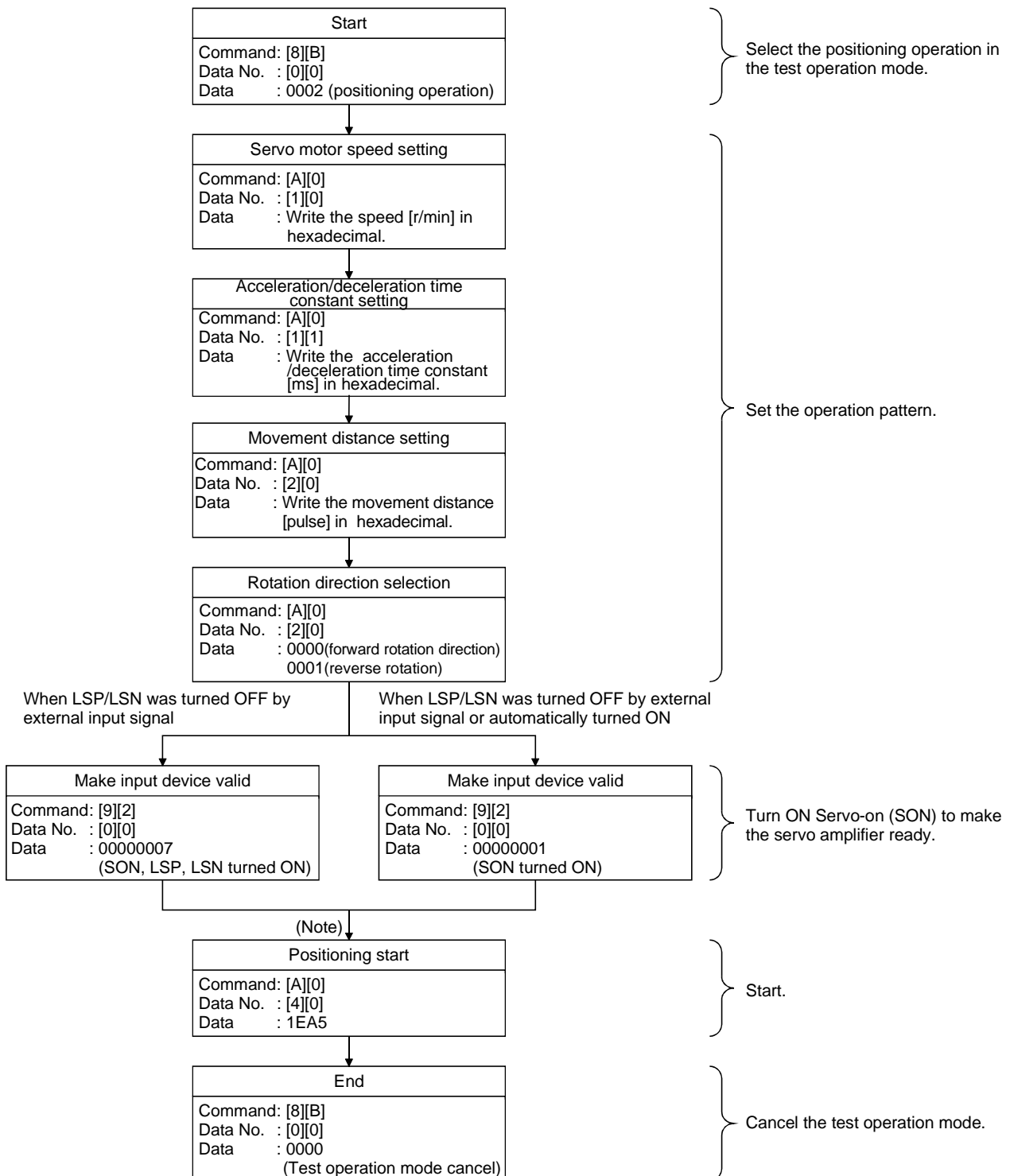


13. COMMUNICATION FUNCTION

(3) Positioning operation

(a) Operation procedure

Send the command, data No. and data as indicated below to execute positioning operation.



Note. There is a 100ms delay.

13. COMMUNICATION FUNCTION

(b) Temporary stop/restart/remaining distance clear

Send 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

Send the following command, data No. and data during a temporary stop to make a restart.

Command	Data No.	(Note) Data
[A][0]	[4][1]	GO□□

Note. □ indicates a blank.

Send the following command, data No. and data during a temporary stop to stop positioning operation and erase the remaining movement distance.

Command	Data No.	(Note) Data
[A][0]	[4][1]	CLR□

Note. □ indicates a blank.

13.5.9 Output signal pin ON/OFF output signal (DO) forced output

In the test operation mode, the output signal pins can be turned on/off independently of the servo status. Using command [9][0], disable the output signals in advance.

(1) Choosing DO forced output in test operation mode

Transmit command [8][B] + data No. [0][0] + data "0004" to choose DO forced output.

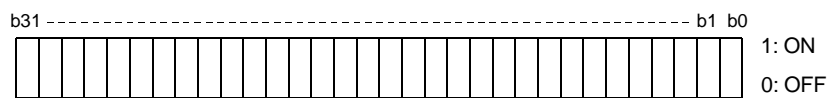
0	0	0	4
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Selection of test operation mode
4: DO forced output (output signal forced output)

(2) External output signal ON/OFF

Transmit the following communication commands:

Command	Data No.	Setting data
[9][2]	[A][0]	See below.



Command of each bit is sent to the slave station in hexadecimal.

bit	CN1 connector pin
0	49
1	24
2	23
3	25
4	22
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	

13. COMMUNICATION FUNCTION

13.5.10 Alarm history

(1) Alarm No. read

Read the alarm No. which occurred in the past. The alarm numbers and occurrence times of No. 0 (last alarm) to No. 5 (sixth alarm in the past) are read.

(a) Transmission

Send command [3][3] and data No. [1][0] to [1][5]. Refer to Section 13.4.1.

(b) Reply

The alarm No. corresponding to the data No. is provided.

0	0		
---	---	--	--

└ Alarm No. is transferred in decimal.

For example, "0032" means AL.32 and "00FF" means AL._ (no alarm).

(2) Alarm occurrence time read

Read the occurrence time of alarm which occurred in the past.

The 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

Send command [3][3] and data No. [2][0] to [2][5].

Refer to Section 13.4.1.

(b) Reply

--	--	--	--	--	--	--	--

└ The alarm occurrence time is transferred in decimal.
Hexadecimal must be converted into decimal.

For example, data "01F5" means that the alarm occurred in 501 hours after start of operation.

(3) Alarm history clear

Erase the alarm history.

Send command [8][2] and data No. [2][0].

Command	Data No.	Data
[8][2]	[2][0]	1EA5

13. COMMUNICATION FUNCTION

13.5.11 Current alarm

(1) Current alarm read

Read the alarm No. which is occurring currently.

(a) Transmission

Send command [0][2] and data No. [0][0].

Command	Data No.
[0][2]	[0][0]

(b) Reply

The slave station sends back the alarm currently occurring.

0	0		
---	---	--	--

Alarm No. is transferred in decimal.

For example, "0032" means AL.32 and "00FF" means AL._ (no alarm).

(2) Read of the status display at alarm occurrence

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 are sent back.

(a) Transmission

Send command [3][5] and any of data No. [8][0] to [8][E] corresponding to the status display item to be read. Refer to Section 13.4.1.

(b) Reply

The slave station sends back the requested status display data at alarm occurrence.

0	0										
---	---	--	--	--	--	--	--	--	--	--	--

Data 32 bits long (represented in hexadecimal)
(Data conversion into display type is required)

Display type

0: Conversion into decimal required
1: Used unchanged in hexadecimal

Decimal point position

0: No decimal point
1: Lower first digit (usually not used)
2: Lower second digit
3: Lower third digit
4: Lower fourth digit
5: Lower fifth digit
6: Lower sixth digit

(3) Current alarm clear

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

13. COMMUNICATION FUNCTION

13.5.12 Other commands

(1) Servo motor end pulse unit absolute position

Read the absolute position in the servo motor end pulse unit.

Note that overflow will occur in the position of 8192 or more revolutions from the home position.

(a) Transmission

Send command [0][2] and data No. [9][0].

Command	Data No.
[0][2]	[9][0]

(b) Reply

The slave station sends back the requested servo motor end pulses.

--	--	--	--	--	--	--	--

Absolute value is sent back in hexadecimal in the servo motor end pulse unit.
(Must be converted into decimal)

For example, data "000186A0" is 100000 [pulse] in the motor end pulse unit.

(2) Command unit absolute position

Read the absolute position in the command unit.

(a) Transmission

Send command [0][2] and data No. [9][1].

Command	Data No.
[0][2]	[9][1]

(b) Reply

The slave station sends back the requested command pulses.

--	--	--	--	--	--	--	--

Absolute value is sent back in hexadecimal in the command unit.
(Must be converted into decimal)

For example, data "000186A0" is 100000 [pulse] in the command unit.

(3) Software version

Reads the software version of the servo amplifier.

(a) Transmission

Send command [0][2] and data No.[7][0].

Command	Data No.
[0][2]	[7][0]

(b) Reply

The slave station returns the software version requested.

--	--	--	--	--	--	--	--	--	--	--	--	--	--	--

└─Space

Software version (15 digits)

This image shows a single sheet of white paper with horizontal ruling lines. The lines are evenly spaced and run across the width of the page. There are no margins, text, or other markings on the paper.

14. ABSOLUTE POSITION DETECTION SYSTEM

14. ABSOLUTE POSITION DETECTION SYSTEM



CAUTION

- If an absolute position erase alarm (AL.25) has occurred, always perform home position setting again. Not doing so can cause runaway.

POINT

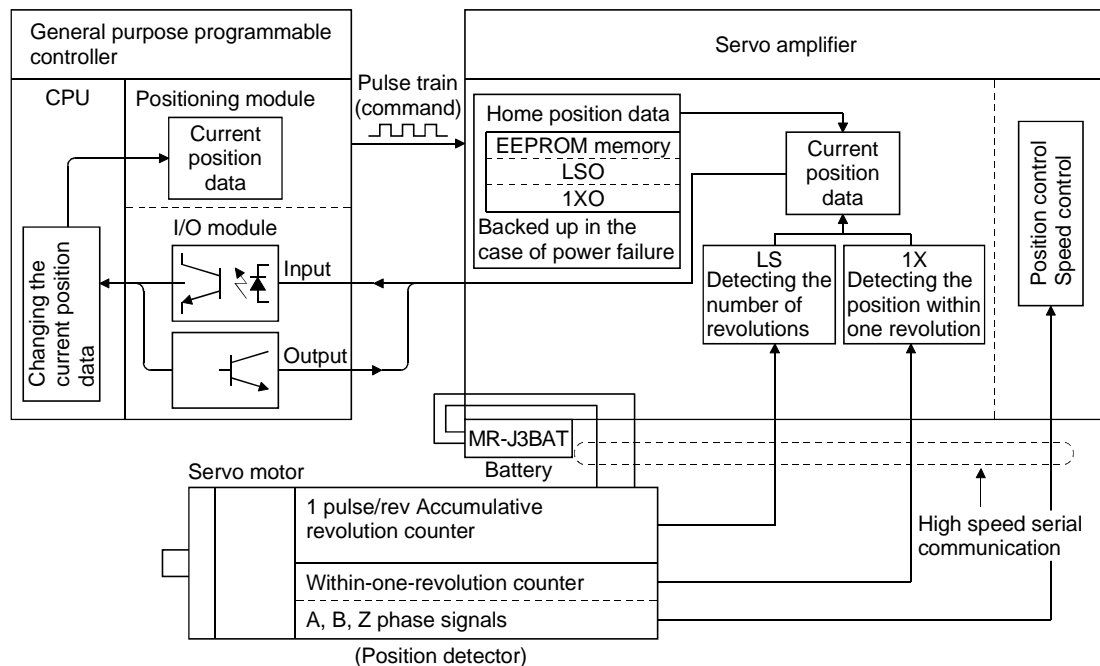
- When configuring an absolute position detection system using the QD75P/D PLC, refer to the Type QD75P/QD75D Positioning Module User's Manual QD75P1/QD75P2/QD75P4, QD75D1/QD75D2/QD75D4 (SH (NA) 080058).

14.1 Outline

14.1.1 Features

For normal operation, as shown below, the encoder consists of a detector designed to detect a position within one revolution and a cumulative revolution counter designed to detect the number of revolutions.

The absolute position detection system always detects the absolute position of the machine and keeps it battery-backed, independently of whether the general-purpose programming controller power is on or off. Therefore, once the home position is defined at the time of machine installation, home position return is not needed when power is switched on thereafter. If a power failure or a fault occurs, restoration is easy.



14.1.2 Restrictions

The absolute position detection system cannot be configured under the following conditions. Test operation cannot be performed in the absolute position detection system, either. To perform test operation, choose incremental in parameter No.PA03.

- (1) Speed control mode, torque control mode.
- (2) Control switch-over mode (position/speed, speed/torque, torque/speed).
- (3) Stroke-less coordinate system, e.g. rotary shaft, infinitely long positioning.
- (4) Changing of electronic gear after home position setting.
- (5) Use of alarm code output.

14. ABSOLUTE POSITION DETECTION SYSTEM

14.2 Specifications

POINT	
	<ul style="list-style-type: none"> Replace the battery with only the control circuit power ON. Removal of the battery with the control circuit power OFF will erase the absolute position data.

(1) Specification list

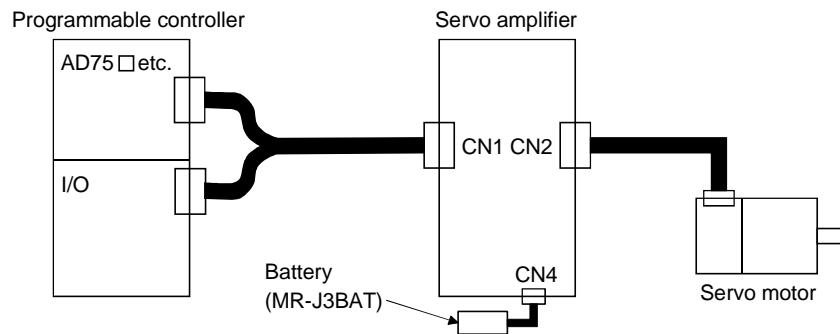
Item	Description
System	Electronic battery backup system
Battery	1 piece of lithium battery (primary battery, nominal + 3.6V) Type: MR-J3BAT
Maximum revolution range	Home position ± 32767 rev.
(Note 1) Maximum speed at power failure	3000r/min
(Note 2) Battery backup time	Approx. 10,000 hours (battery life with power off)
Battery storage period	5 years from date of manufacture

Note 1. Maximum speed available when the shaft is rotated by external force at the time of power failure or the like.

2. Time to hold data by a battery with power off. It is recommended to replace the battery in three years independently of whether power is kept on or off.

(2) Configuration

Positioning module	I/O module
AD75□ A1SD75□	AX40 · 41 · 42 AY40 · 41 · 42
FX-1PG · FX-1GM · FX-10GM	FX2-32MT



(3) Parameter setting

Set "□□□1" in parameter No. PA03 to make the absolute position detection system valid. Set "□□□2" when using the communication-based ABS transfer system. Refer to Section 14.10 for the communication-based ABS transfer system.

Parameter No. PA03

□	□	□	□
---	---	---	---

Absolute position detection system selection
 0: Used in incremental system
 1: Used in absolute position detection system
 ABS transfer by DIO
 2: Used in absolute position detection system
 ABS transfer by communication

14. ABSOLUTE POSITION DETECTION SYSTEM

14.3 Battery installation procedure



WARNING

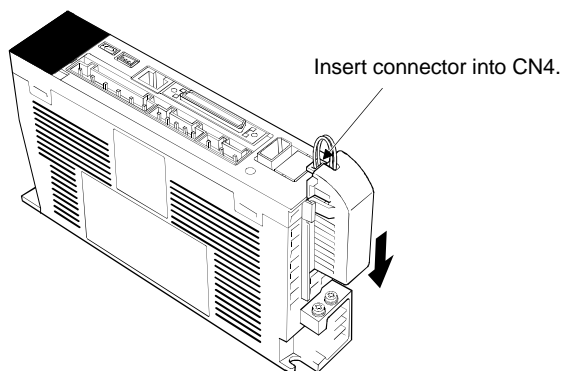
- Before starting battery installation procedure, make sure that the charge lamp is off more than 10 minutes after power-off. Then, confirm that the voltage is safe in the tester or the like. Otherwise, you may get an electric shock.

POINT

The internal circuits of the servo amplifier may be damaged by static electricity.

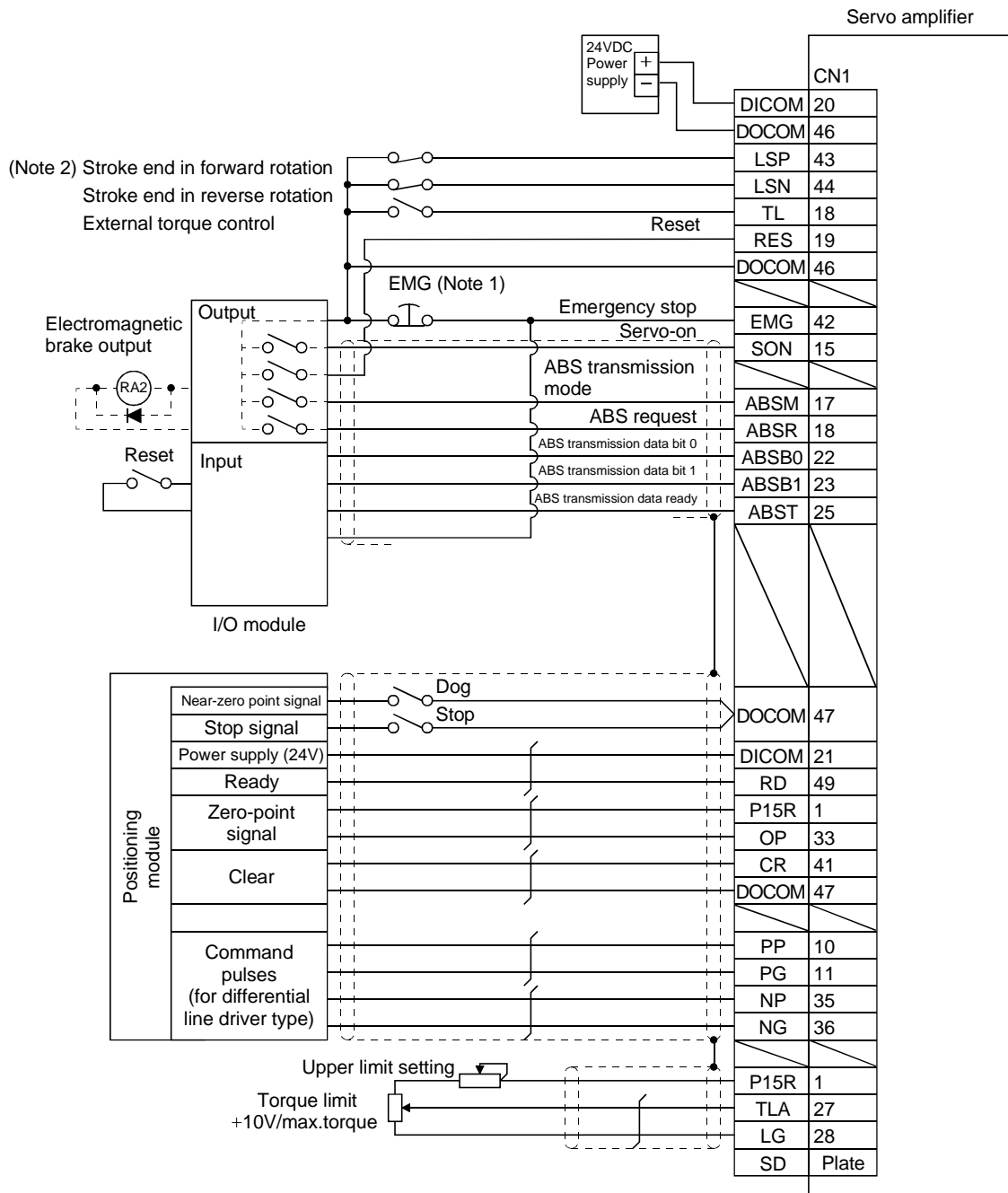
Always take the following precautions:

- Ground human body and work bench.
- Do not touch the conductive areas, such as connector pins and electrical parts, directly by hand.



14. ABSOLUTE POSITION DETECTION SYSTEM

14.4 Standard connection diagram



Note 1. Always install the emergency stop switch.

2. For operation, always turn on forward rotation stroke end (LSP)/reverse rotation stroke end (LSN).

14. ABSOLUTE POSITION DETECTION SYSTEM

14.5 Signal explanation

When the absolute position data is transferred, the signals of connector CN1 change as described in this section. They return to the previous status on completion of data transfer. The other signals are as described in Section 3.5.

For the I/O interfaces (symbols in the I/O Category column in the table), refer to Section 3.8.2.

Signal name	Code	CN1 Pin No.	Function/Application	I/O category	Control mode
ABS transfer mode	ABSM	(Note) 17	While ABSM is on, the servo amplifier is in the ABS transfer mode, and the functions of ZSP, TLC, and D01 are as indicated in this table.	DI-1	P (Position control)
ABS request	ABSR	(Note) 18	Turn on ABSR to request the ABS data in the ABS transfer mode.	DI-1	
ABS transmission data bit 0	ABSB0	22	Indicates the lower bit of the ABS data (2 bits) which is sent from the servo to the programmable controller in the ABS transfer mode. If there is a signal, D01 turns on.	DO-1	
ABS transmission data bit 1	ABSB1	23	Indicates the upper bit of the ABS data (2 bits) which is sent from the servo to the programmable controller in the ABS transfer mode. If there is a signal, ZSP turns on.	DO-1	
ABS transmission data ready	ABST	25	Indicates that the data to be sent is being prepared in the ABS transfer mode. At the completion of the ready state, TLC turns on.	DO-1	
Home position setting	CR	41	When CR is turned on, the position control counter is cleared and the home position data is stored into the non-volatile memory (backup memory).	DI-1	

Note. When "Used in absolute position detection system" is selected in parameter No.PA03, pin 17 acts as the ABS transfer mode (ABSM) and pin 18 as the ABS request (ABSR). They do not return to the original signals if data transfer ends.

14. ABSOLUTE POSITION DETECTION SYSTEM

14.6 Startup procedure

(1) Battery installation.

Refer to Section 14.3 installation of absolute position backup battery.

(2) Parameter setting

Set "□□□ 1" in parameter No.PA03 of the servo amplifier and switch power off, then on.

(3) Resetting of absolute position erase (AL.25)

After connecting the encoder cable, the absolute position erase (AL.25) occurs at first power-on. Leave the alarm as it is for a few minutes, then switch power off, then on to reset the alarm.

(4) Confirmation of absolute position data transfer

When the servo-on (SON) is turned on, the absolute position data is transferred to the programmable controller. When the ABS data is transferred properly:

(a) The ready output (RD) turns on.

(b) The programmable controller/ABS data ready contact turns on.

(c) The servo configuration software ABS data display window (refer to Section 14.11) and programmable controller side ABS data registers show the same value (at the home position address of 0).

If any warning such as ABS time-out warning (AL.E5) or programmable controller side transfer error occurs, refer to Section 14.10 or Chapter 9 and take corrective action.

(5) Home position setting

The home position must be set if:

(a) System setup is performed;

(b) The servo amplifier has been changed;

(c) The servo motor has been changed; or

(d) The absolute position erase (AL.25) occurred.

In the absolute position system, the absolute position coordinates are made up by making home position setting at the time of system setup.

The motor shaft may misoperate if positioning operation is performed without home position setting. Always make home position setting before starting operation.

For the home position setting method and types, refer to Section 14.7.3.

14. ABSOLUTE POSITION DETECTION SYSTEM

14.7 Absolute position data transfer protocol

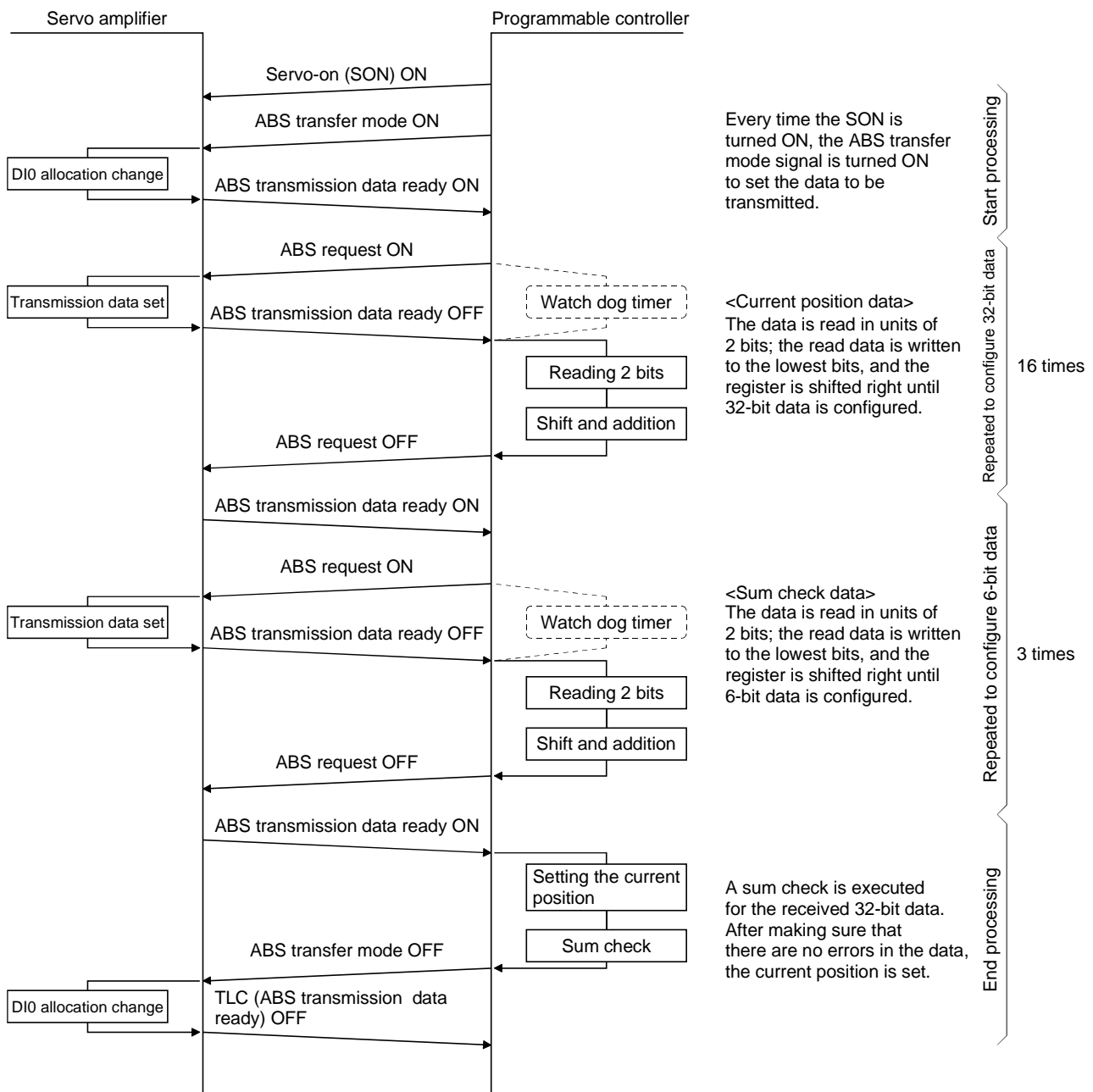
POINT

- After switching on the ABS transfer mode (ABSM), turn on the servo-on signal (SON). When the ABS transfer mode is off, turning on the servo-on signal (SON) does not switch on the base circuit.

14.7.1 Data transfer procedure

Each time the servo-on (SON) is turned ON (when the power is switched ON for example), the programmable controller reads the position data (present position) of the servo amplifier.

Time-out monitoring is performed by the programmable controller.



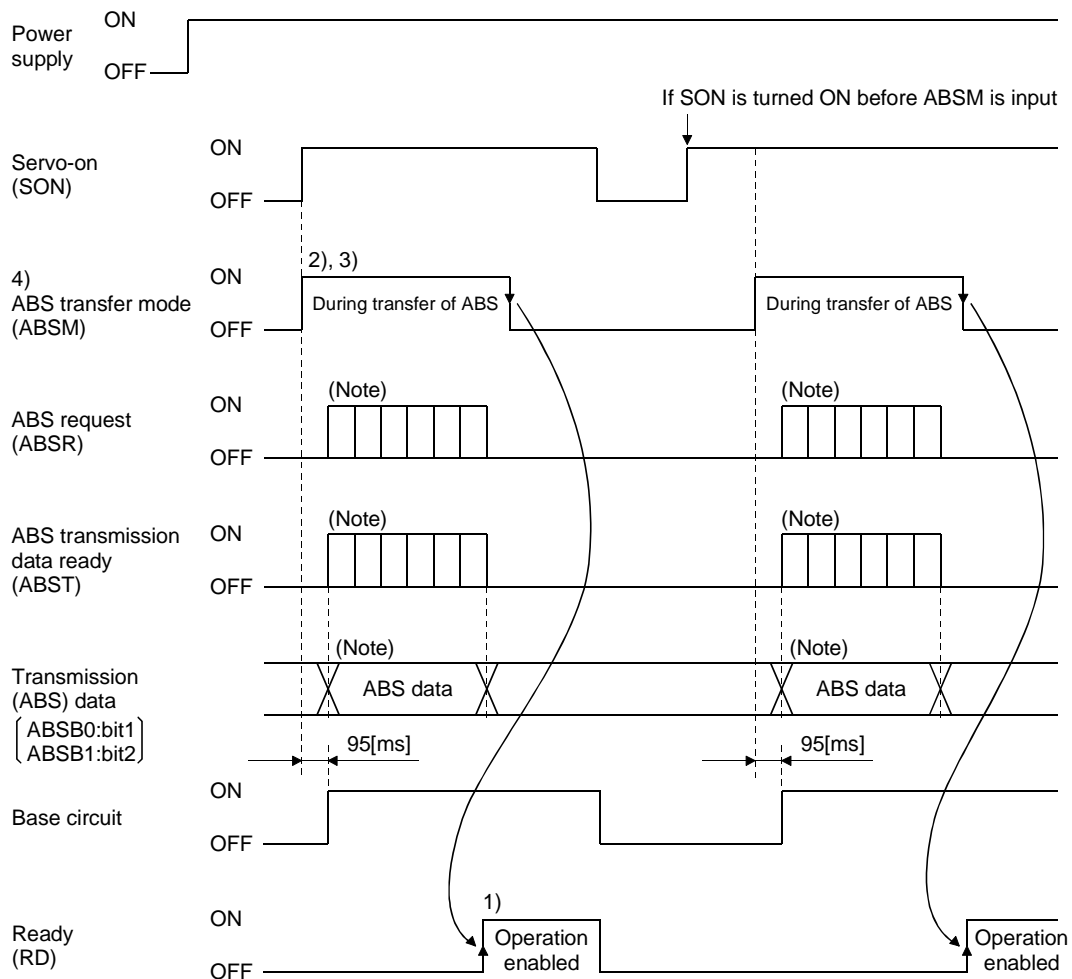
14. ABSOLUTE POSITION DETECTION SYSTEM

14.7.2 Transfer method

The sequence in which the base circuit is turned ON (servo-on) when it is in the OFF state due to the servo-on (SON) going OFF, an emergency stop (EMG), or alarm (ALM), is explained below. In the absolute position detection system, every time the servo-on (SON) is turned on, the ABS transfer mode (ABSM) should always be turned on to read the current position in the servo amplifier to the controller. The servo amplifier transmits to the controller the current position latched when the ABS transfer mode (ABSM) switches from OFF to ON. At the same time, this data is set as a position command value inside the servo amplifier. Unless the ABS transfer mode (ABSM) is turned ON, the base circuit cannot be turned ON.

(1) At power-on

(a) Timing chart



Note. For details, refer to (1) (b) in this section.

14. ABSOLUTE POSITION DETECTION SYSTEM

- 1) The ready (RD) is turned ON when the ABS transfer mode (ABSM) is turned OFF after transmission of the ABS data.

While the ready (RD) is ON, the ABS transfer mode (ABSM) input is not accepted.

- 2) Even if the servo-on (SON) is turned ON before the ABS transfer mode (ABSM) is turned ON, the base circuit is not turned ON until the ABS transfer mode (ABSM) is turned ON.

If a servo alarm has occurred, the ABS transfer mode (ABSM) is not received.

The ABS transfer mode (ABSM) allows data transmission even while a servo warning is occurring.

- 3) If the ABS transfer mode (ABSM) is turned OFF during the ABS transfer mode, the ABS transfer mode is interrupted and the time-out error (AL.E5) occurs.

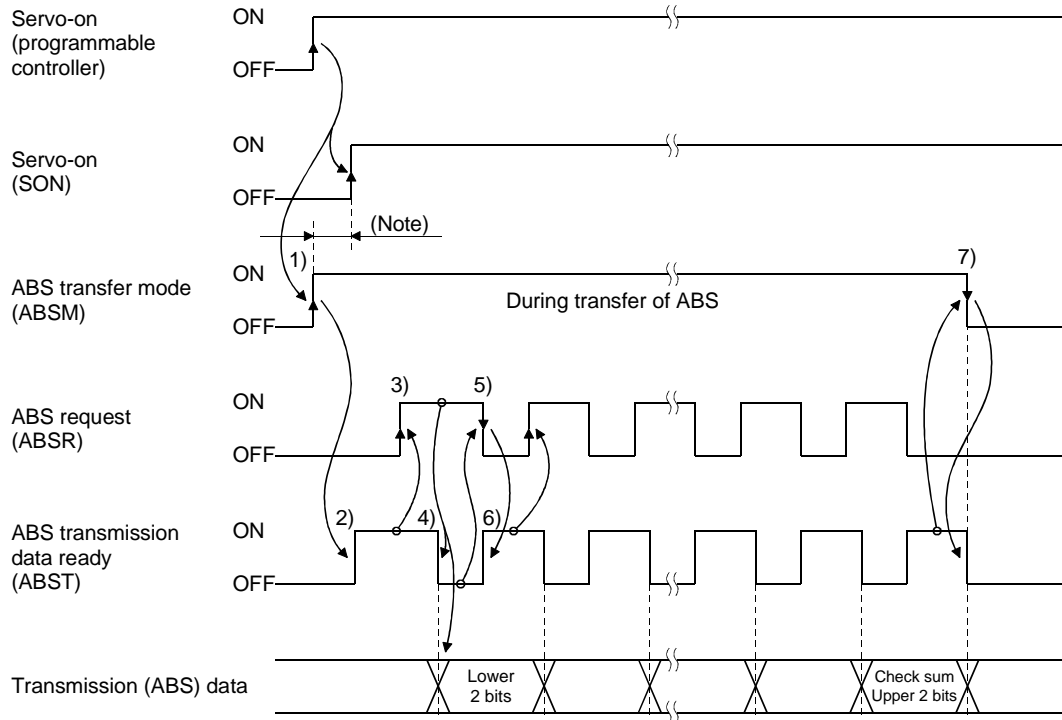
- 4) The functions of output signals such as ABST, ABSB0, and ABSB1 change depending on the ON/OFF state of the ABS transfer mode (ABSM).

Note that if the ABS transfer mode (ABSM) is turned ON for a purpose other than ABS data transmission, the output signals will be assigned the functions of ABS data transmission.

CN1 Pin No.	Output signal	
	ABS transfer mode (ABSM): OFF	ABS transfer mode (ABSM): ON
22	Positioning completion	ABS transmission data bit 0
23	Zero speed	ABS transmission data bit 1
25	During torque limit control	ABS transmission data ready

14. ABSOLUTE POSITION DETECTION SYSTEM

(b) Detailed description of absolute position data transfer



Note. If the servo-on (SON) is not turned ON within 1 second after the ABS transfer mode (ABSM) is turned ON, an SON time-out warning (AL.EA) occurs. This warning, however, does not interrupt data transmission. It is automatically cleared when the servo-on (SON) is turned ON.

- 1) The programmable controller turns ON the ABS transfer mode (ABSM) and servo-on (SON) at the leading edge of the internal servo-on (SON).
 - 2) In response to the ABS transfer mode (ABSM), the servo detects and calculates the absolute position and turns ON the ABS transmission data ready (ABST) to notify the programmable controller that the servo is ready for data transmission.
 - 3) After acknowledging that the ready to send (ABST) has been turned ON, the programmable controller turns ABS request (ABSR) ON.
 - 4) In response to ABS request (ABSR), the servo outputs the lower 2 bits of the ABS data and the ABS transmission data ready (ABST) in the OFF state.
 - 5) After acknowledging that the ABS transmission data ready (ABST) has been turned OFF, which implies that 2 bits of the ABS data have been transmitted, the programmable controller reads the lower 2 bits of the ABS data and then turns OFF the ABS request (ABSR).
 - 6) The servo turns ON the ABS transmission data ready (ABST) so that it can respond to the next request. Steps 3) to 6) are repeated until 32-bit data and the 6-bit check sum have been transmitted.
 - 7) After receiving of the check sum, the programmable controller turns the ABS transfer mode (ABSM) OFF.
- If the ABS transfer mode (ABSM) is turned OFF during data transmission, the ABS transfer mode (ABSM) is interrupted.

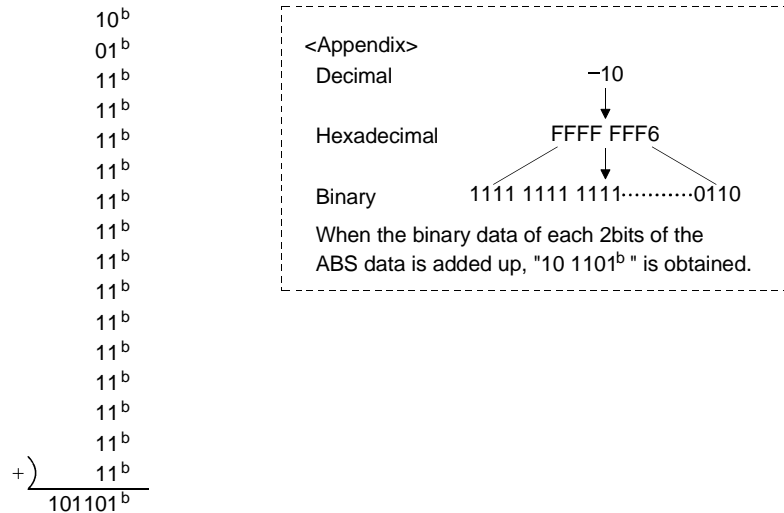
(c) Checksum

The check sum is the code which is used by the programmable controller to check for errors in the received ABS data. The 6-bit check sum is transmitted following the 32-bit ABS data.

At the programmable controller, calculate the sum of the received ABS data using the ladder program and compare it with the check sum code sent from the servo.

The method of calculating the check sum is shown. Every time the programmable controller receives 2 bits of ABS data, it adds the data to obtain the sum of the received data. The check sum is 6-bit data.

Example: ABS data: -10 (FFFFFFFF6H)



Therefore, the check sum of "—10" (ABS data) is "2D^b"

14. ABSOLUTE POSITION DETECTION SYSTEM

(2) Transmission error

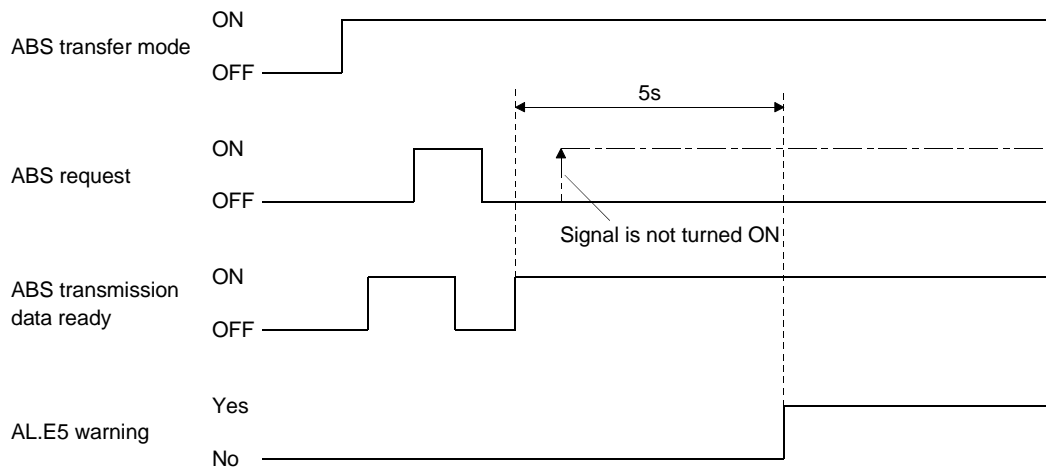
(a) Time-out warning(AL.E5)

In the ABS transfer mode, the time-out processing shown below is executed at the servo. If a time-out error occurs, an ABS time-out warning (AL.E5) is output.

The ABS time-out warning (AL.E5) is cleared when the ABS transfer mode (ABSM) changes from OFF to ON.

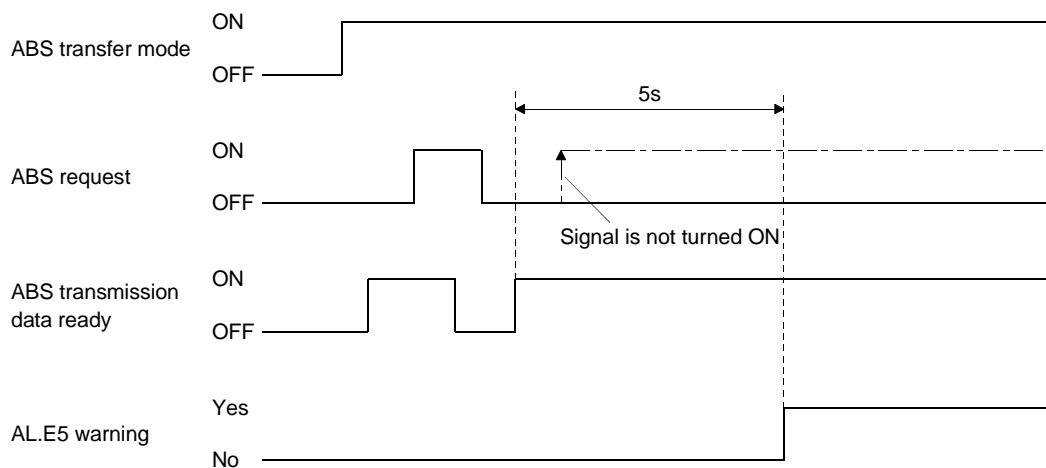
1) ABS request OFF-time time-out check (applied to 32-bit ABS data in 2-bit units + check sum)

If the ABS request signal is not turned ON by the programmable controller within 5s after the ABS transmission data ready (ABST) is turned ON, this is regarded as a transmission error and the ABS time-out warning (AL.E5) is output.



2) ABS request ON-time time-out check (applied to 32-bit ABS data in 2-bit units + check sum)

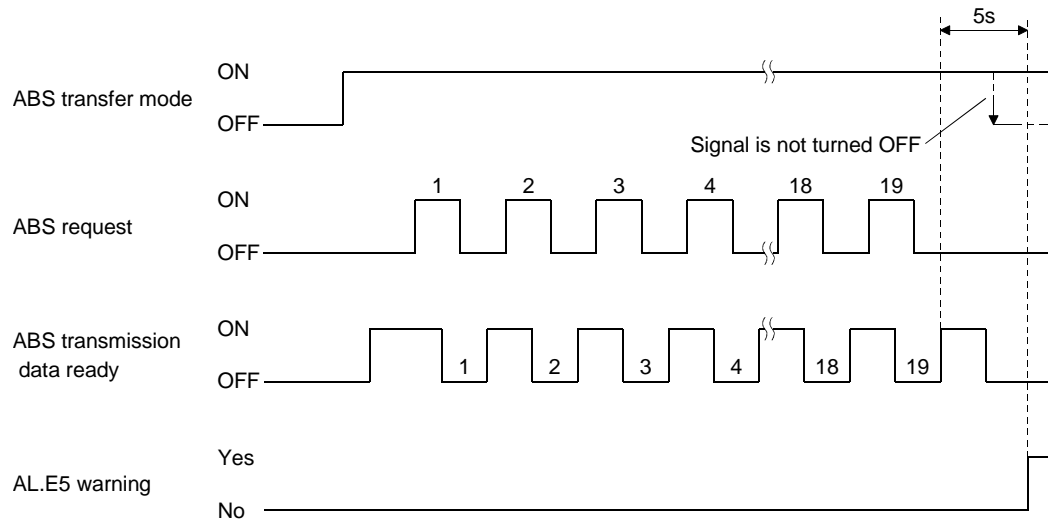
If the ABS request signal is not turned OFF by the programmable controller within 5s after the ABS transmission data ready (ABST) is turned OFF, this is regarded as the transmission error and the ABS time-out warning (AL.E5) is output.



14. ABSOLUTE POSITION DETECTION SYSTEM

3) ABS transfer mode finish-time time-out check

If the ABS transfer mode (ABSR) is not turned OFF within 5s after the last ready to send signal (19th signal for ABS data transmission) is turned ON, it is regarded as the transmission error and the ABS time-out warning (AL.E5) is output.

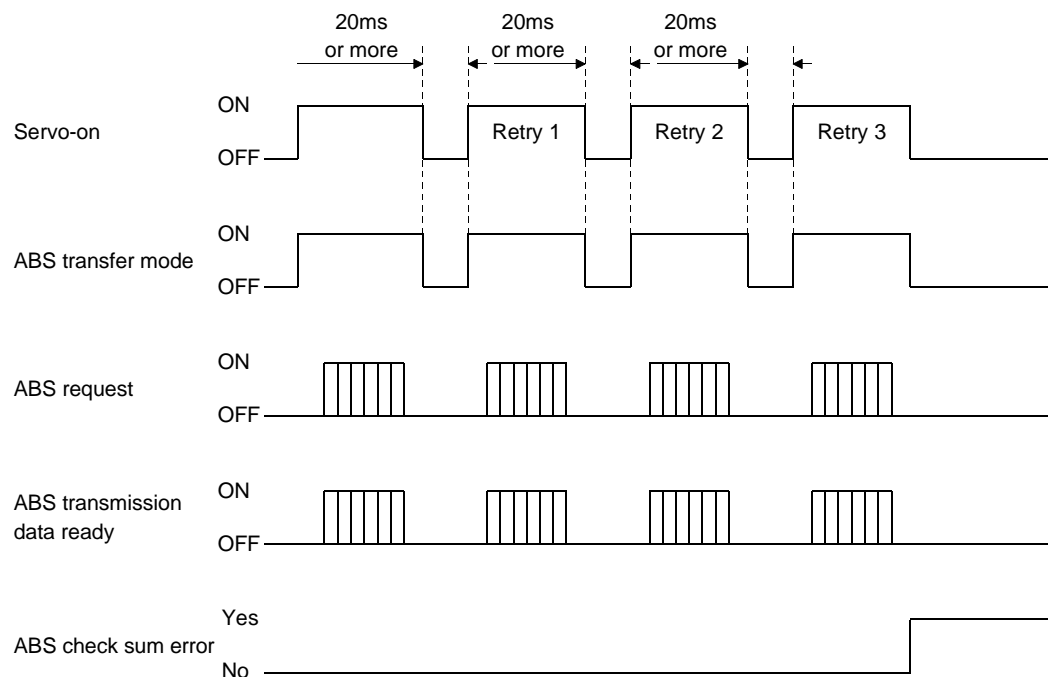


(b) Check sum error

If the check sum error occurs, the programmable controller should retry transmission of the ABS data. Using the ladder check program, turn OFF the ABS transfer mode (ABSM) and servo-on (SON) once. Turn them ON again after an OFF time of longer than 20 ms.

If the ABS data transmission fails to end normally even after retry, regard this situation as an ABS check sum error and execute error processing.

The start command should be interlocked with the ABS data ready signal to disable positioning operation when an check sum error occurs.



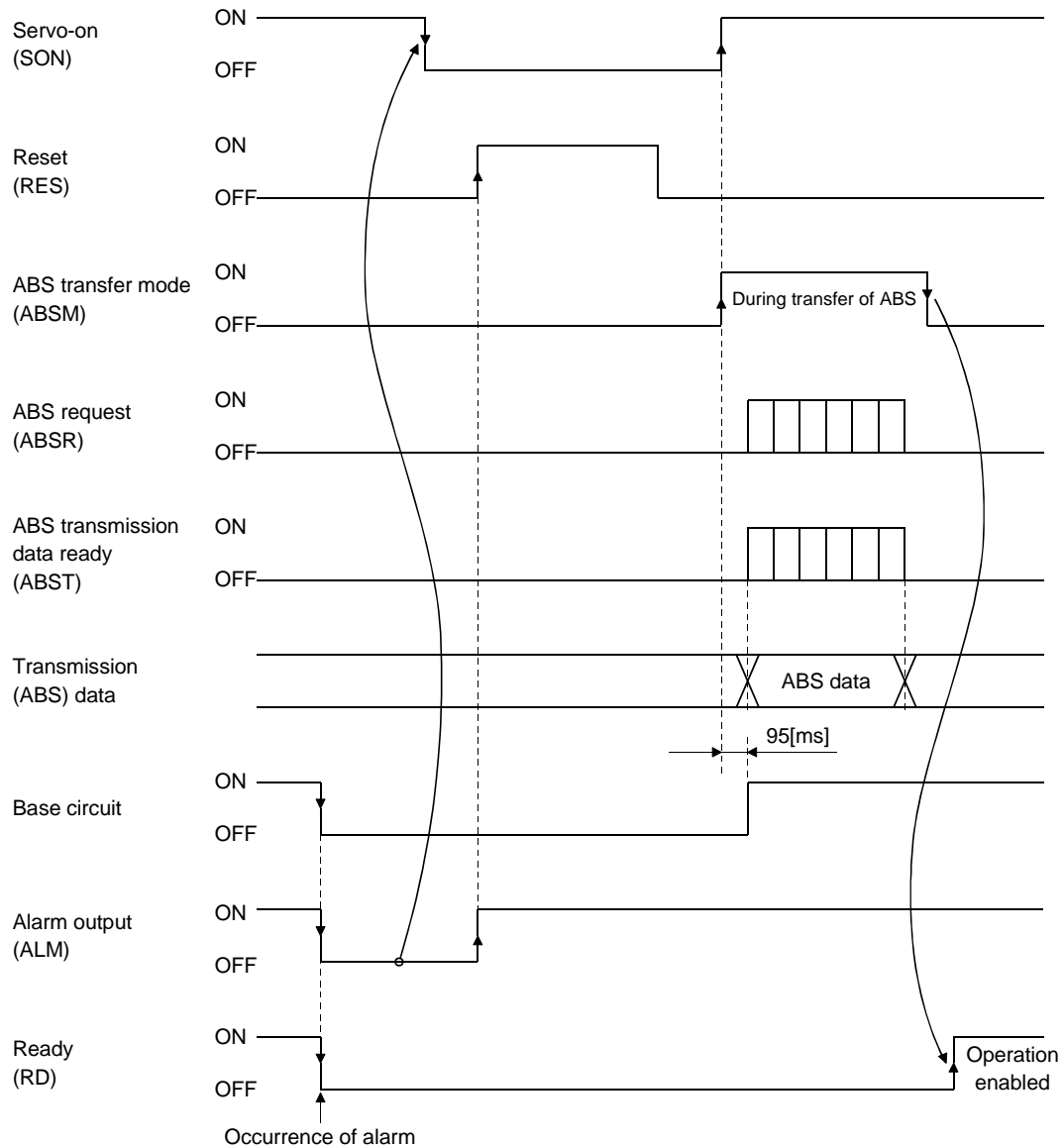
14. ABSOLUTE POSITION DETECTION SYSTEM

(3) At the time of alarm reset

If an alarm occurs, turn OFF the servo-on (SON) by detecting the alarm output (ALM).

If an alarm has occurred, the ABS transfer mode (ABSM) cannot be accepted.

In the reset state, the ABS transfer mode (ABSM) can be input.



14. ABSOLUTE POSITION DETECTION SYSTEM

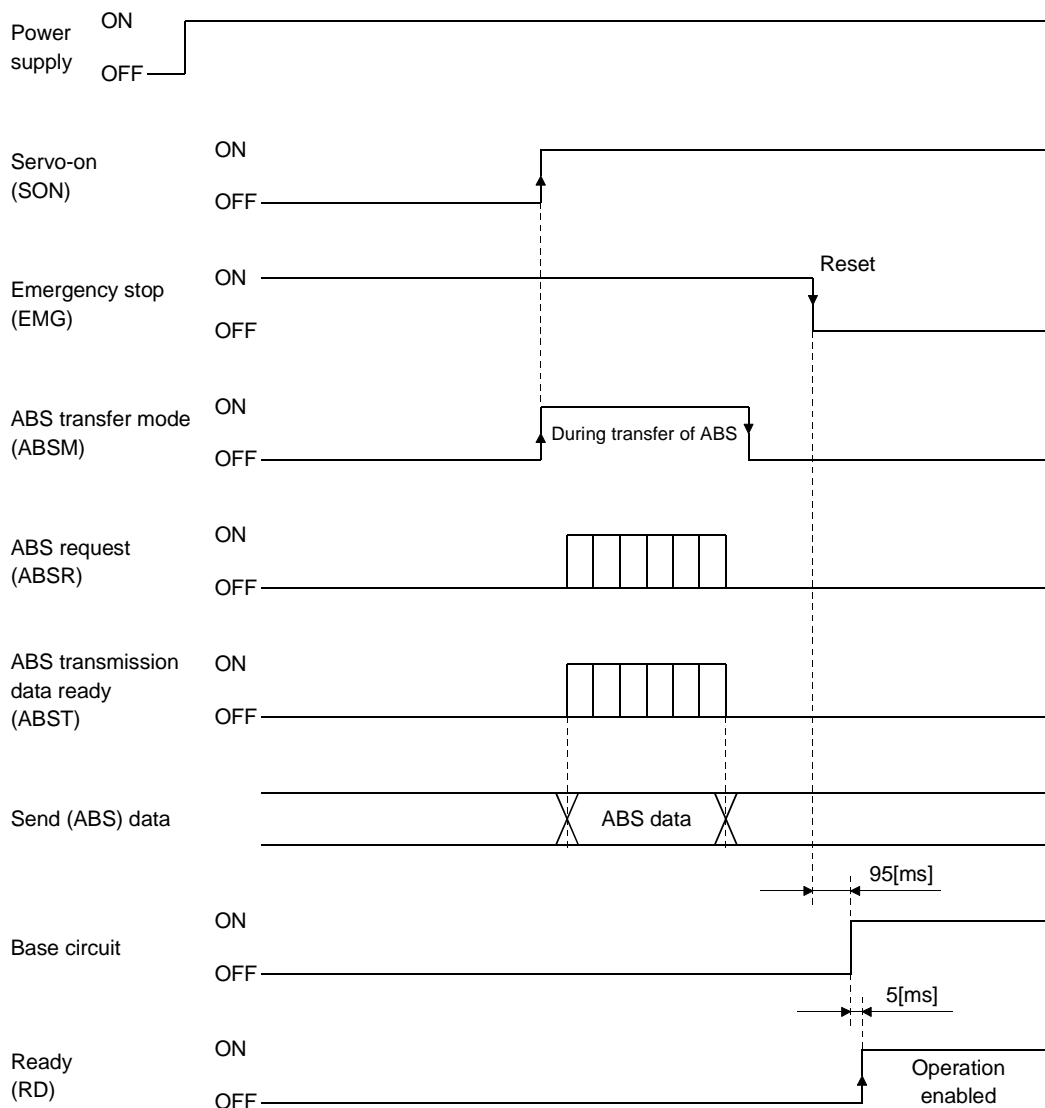
(4) At the time of emergency stop reset

(a) If the power is switched ON in the emergency stop state

The emergency stop state can be reset while the ABS data is being transferred.

If the emergency stop state is reset while the ABS data is transmitted, the base circuit is turned ON 95[ms] after resetting. If the ABS transfer mode (ABSM) is OFF when the base circuit is turned ON, the ready (RD) is turned ON 5[ms] after the turning ON of the base circuit. If the ABS transfer mode (ABSM) is ON when the base circuit is turned ON, it is turned OFF and then the ready (RD) is turned ON. The ABS data can be transmitted after the emergency stop state is reset.

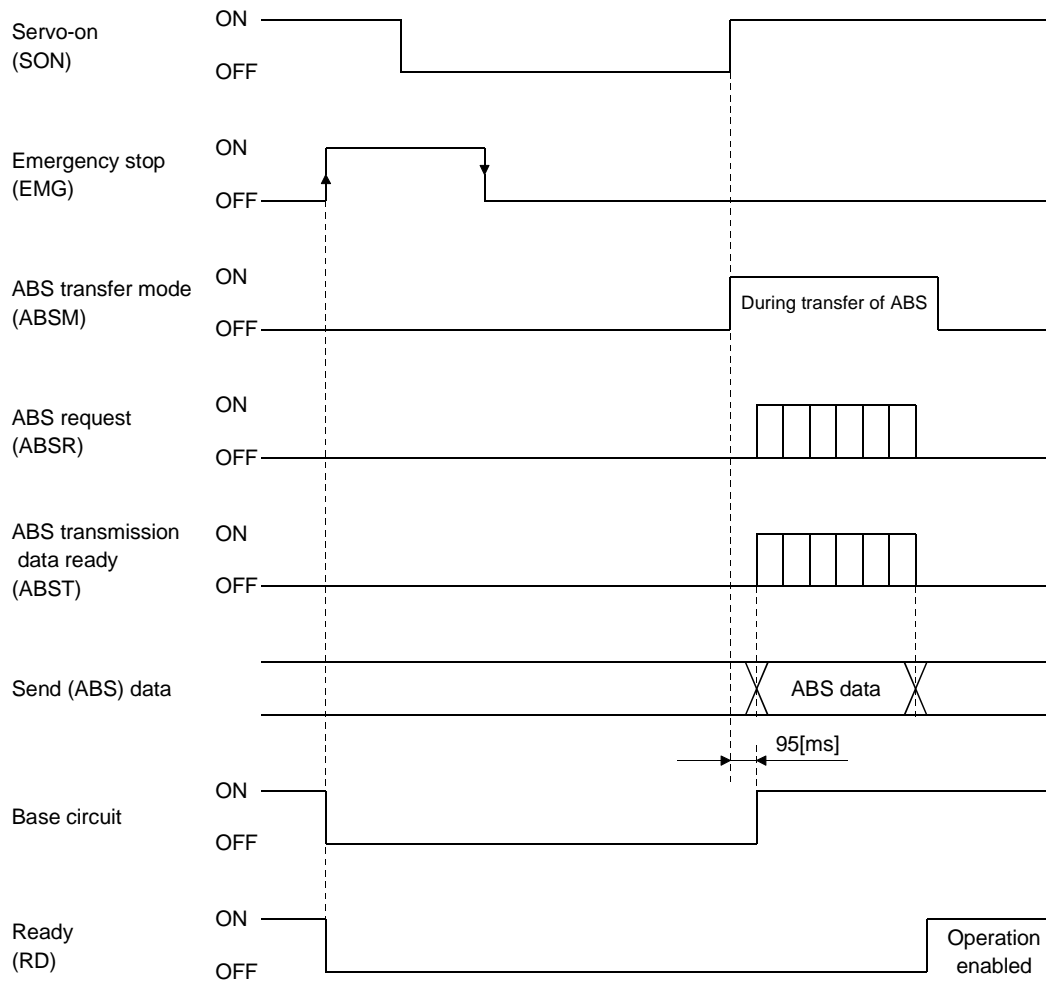
The current position in the servo amplifier is updated even during an emergency stop. When servo-on (SON) and ABS transfer mode (ABSM) are turned ON during an emergency stop as shown below, the servo amplifier transmits to the controller the current position latched when the ABS transfer mode (ABSM) switches from OFF to ON, and at the same time, the servo amplifier sets this data as a position command value. However, since the base circuit is OFF during an emergency stop, the servo-lock status is not encountered. Therefore, if the servo motor is rotated by external force or the like after the ABS transfer mode (ABSM) is turned ON, this travel is accumulated in the servo amplifier as droop pulses. If the emergency stop is cleared in this status, the base circuit turns ON and the motor returns to the original position rapidly to compensate for the droop pulses. To avoid this status, reread the ABS data before clearing the emergency stop.



14. ABSOLUTE POSITION DETECTION SYSTEM

(b) If emergency stop is activated during servo-on

The ABS transfer mode (ABSM) is permissible while in the emergency stop state. In this case, the base circuit and the ready (RD) are turned ON after the emergency stop state is reset.



14. ABSOLUTE POSITION DETECTION SYSTEM

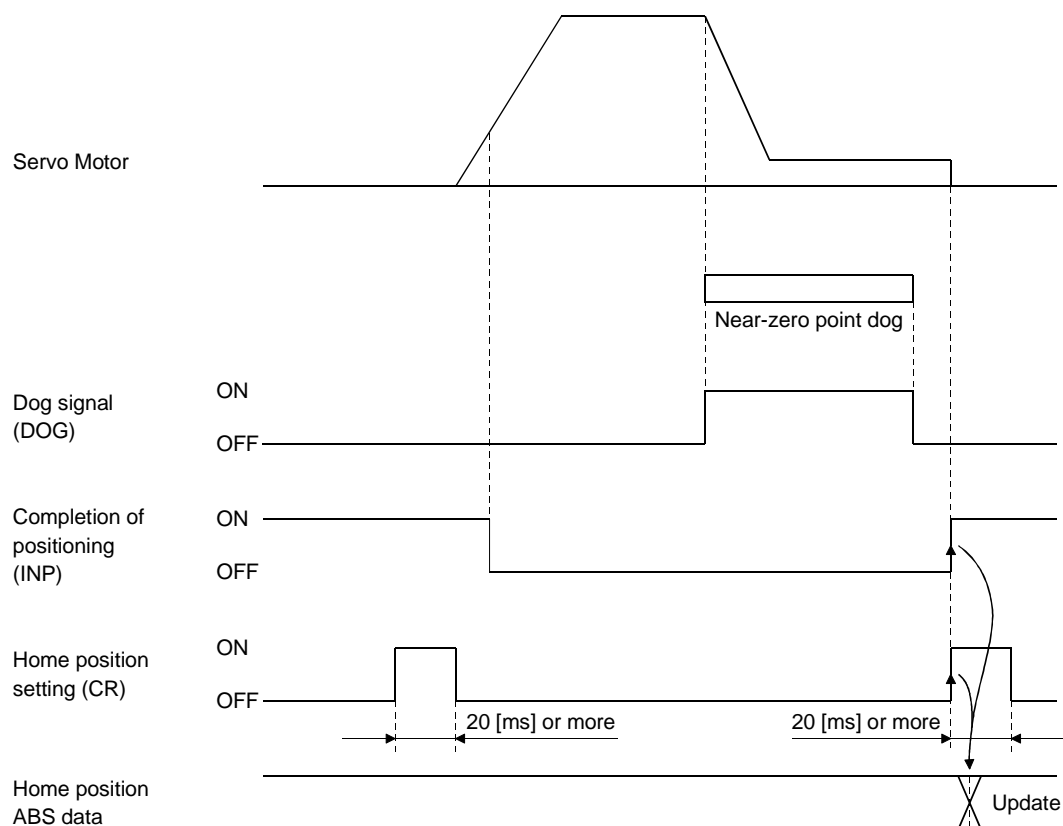
14.7.3 Home position setting

(1) Dog type home position return

Preset a home position return creep speed at which the machine will not be given impact. On detection of a zero pulse, the home position setting (CR) is turned from off to on. At the same time, the servo amplifier clears the droop pulses, comes to a sudden stop, and stores the stop position into the non-volatile memory as the home position ABS data.

The home position setting (CR) should be turned on after it has been confirmed that the in-position (INP) is on. If this condition is not satisfied, the home position setting warning (AL.96) will occur, but that warning will be reset automatically by making home position return correctly.

The number of home position setting times is limited to 1,000,000 times.



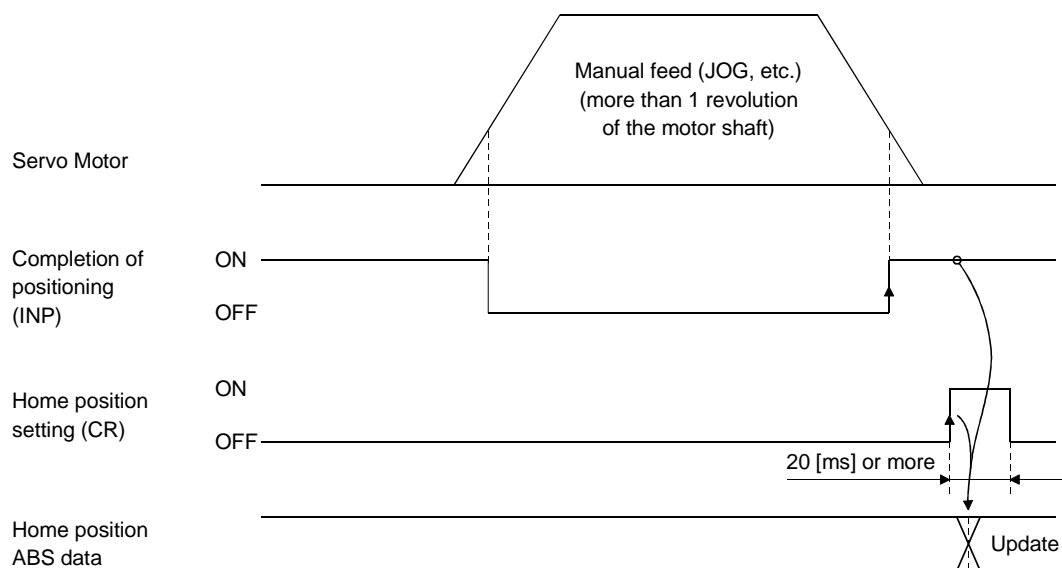
14. ABSOLUTE POSITION DETECTION SYSTEM

(2) Data set type home position return

Move the machine to the position where the home position is to be set by performing manual operation such as jog operation to turn the motor shaft more than one revolution. When the home position setting (CR) is on for longer than 20ms, the stop position is stored into the non-volatile memory as the home position ABS data.

The home position setting (CR) should be turned on after it has been confirmed that the in-position (INP) is on. If this condition is not satisfied, the home position setting warning (AL.96) will occur, but that warning will be reset automatically by making home position return correctly.

The number of home position setting times is limited to 1,000,000 times.



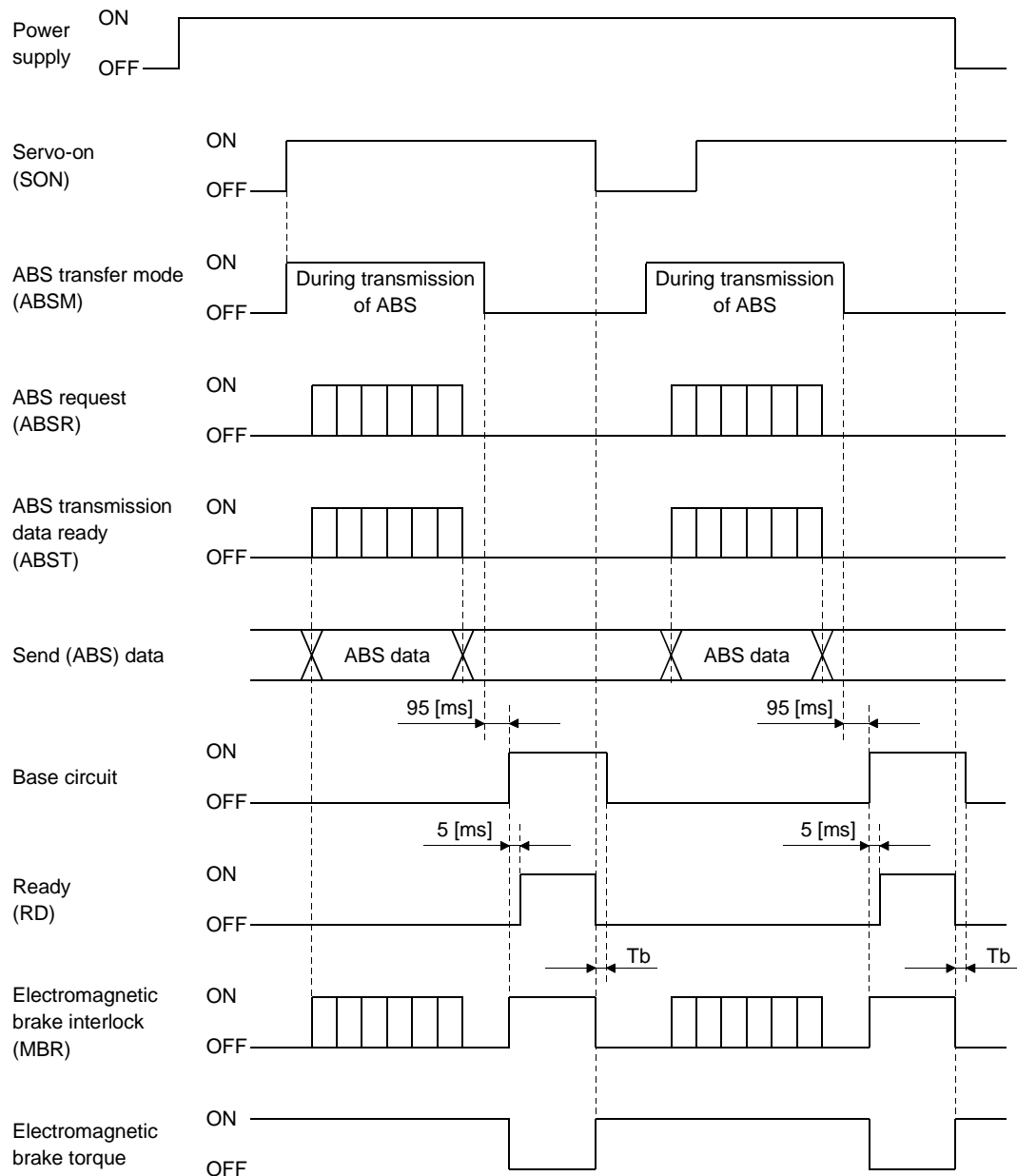
14. ABSOLUTE POSITION DETECTION SYSTEM

14.7.4 Use of servo motor with electromagnetic brake

The timing charts at power on/off and servo-on (SON) on/off are given below.

Preset parameter No. PA04/PD13 to PD16/PD18 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid. When the ABS transfer mode is ON, the electromagnetic brake interlock (MBR) set in parameter No. PA04 is used as the ABS data bit 1.

Hence, make up an external sequence which will cause the electromagnetic brake torque to be generated by the ABS mode (ABSM) and electromagnetic brake interlock (MBR).



14. ABSOLUTE POSITION DETECTION SYSTEM

14.7.5 How to process the absolute position data at detection of stroke end

The servo amplifier stops the acceptance of the command pulse when stroke end (LSP • LSN) is detected, clears the droop pulses to 0 at the same time, and stops the servo motor rapidly.

At this time, the programmable controller keeps outputting the command pulse. Since this causes a discrepancy between the absolute position data of the servo amplifier and the programmable controller, a difference will occur between the position data of the servo amplifier and that of the programmable controller. To prevent this difference in position data from occurring, do as described below. When the servo amplifier has detected the stroke end, perform jog operation or the like to clear the stroke end. After that, switch the servo-on (SON) off once, then on again, or switch the power off once, then on again. This causes the absolute position data of the servo amplifier to be transferred to the programmable controller, restoring the normal data.

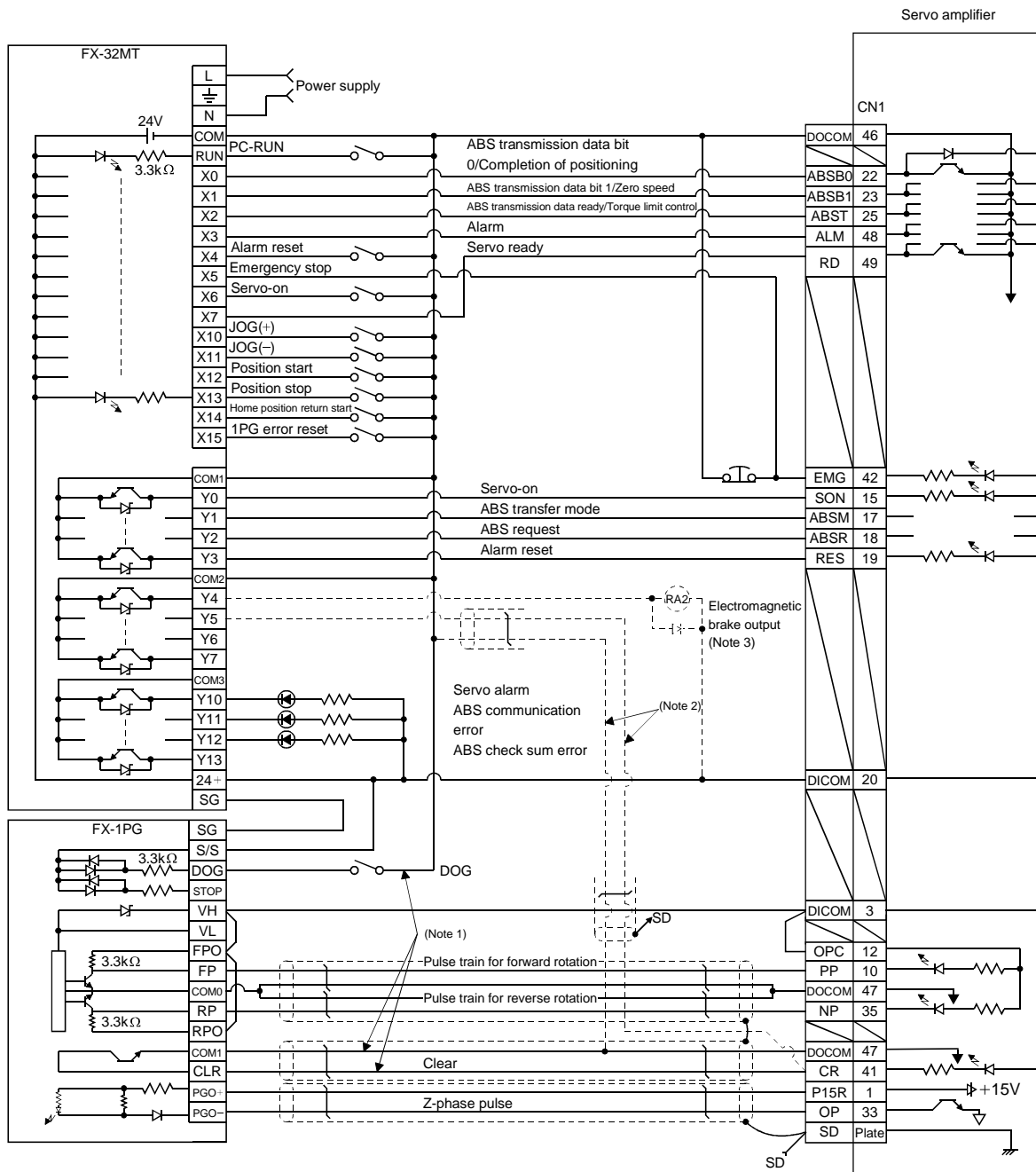
14. ABSOLUTE POSITION DETECTION SYSTEM

14.8 Examples of use

14.8.1 MELSEC FX(2N)-32MT (FX(2N)-1PG)

(1) Connection diagram

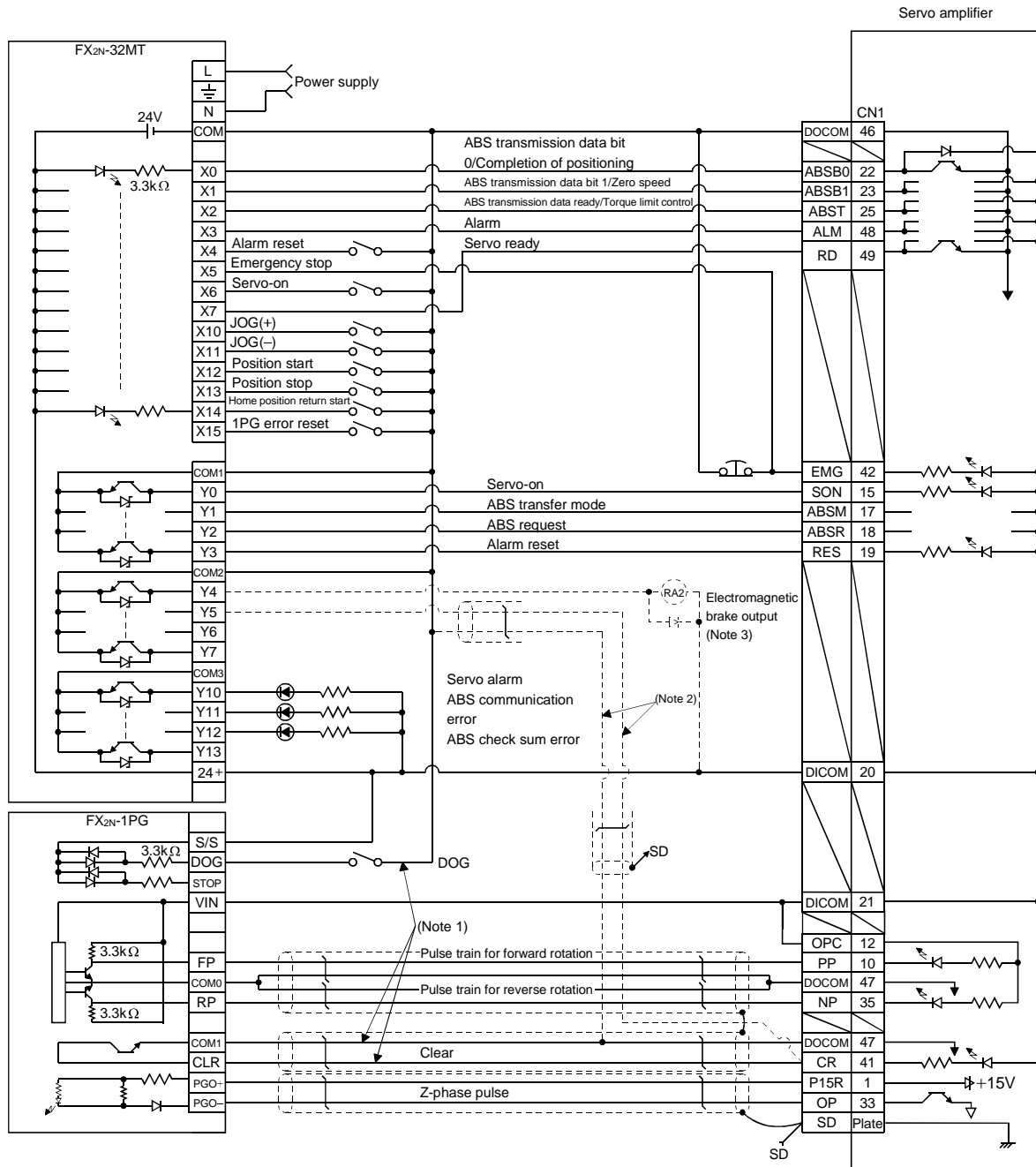
(a) FX-32MT (FX-1PG)



- Note 1. To be connected for the dog type home position setting. At this time, do not connect the portions marked (Note 2).
 Note 2. To be connected for the data set type home position setting. At this time, do not connect the portions marked (Note 1).
 Note 3. The electromagnetic brake interlock (MBR) should be controlled by connecting the programmable controller output to a relay.

14. ABSOLUTE POSITION DETECTION SYSTEM

(b) FX2N-32MT (FX2N-1PG)



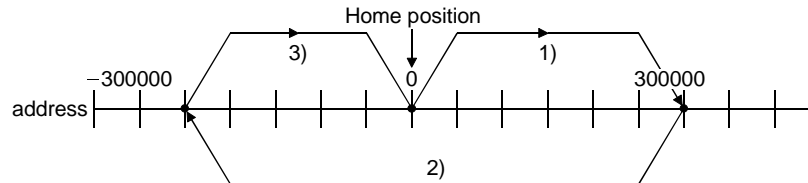
14. ABSOLUTE POSITION DETECTION SYSTEM

(2) Sequence program example

(a) Conditions

1) Operation pattern

ABS data transfer is made as soon as the servo-on pushbutton is turned on. After that, positioning operation is performed as shown below:



After the completion of ABS data transmission, JOG operation is possible using the JOG+ or JOG— pushbutton switch.

After the completion of ABS data transmission, dog type home position return is possible using the home position return pushbutton switch.

2) Buffer memory assignment

For BFM#26 and later, refer to the FX2(N)-1PG User's Manual.

BMF No.		Name and symbol	Set value	Remark
Upper 16 bits	Lower 16 bits			
-	#0	Pulse rate A	2000	Command unit: Pulses
#2	#1	Feed rate B	1000	
-	#3	Parameter	H0000	
#5	#4	Max. speed Vmax	100000PPS	
-	#6	Bias speed Vbia	0PPS	Initial value: 10
#8	#7	JOG operation Vjog	10000PPS	
#10	#9	Home position return speed (high speed) VRT	50000PPS	
-	#11	Home position return speed (creep) VCL	1000PPS	
-	#12	Home position return zero-point signal count N	2 pulses	Initial value: 100
#14	#13	Home position address HP	0	
-	#15	Acceleration/deceleration time Ta	200ms	Initial value: 10
-	#16	Not usable		
#18	#17	Target address (I) P(I)	0	
#20	#19	Operation speed (I) V(I)	100000	
#22	#21	Target address (II) P(II)	0	Initial value: 10
#24	#23	Operation speed (II) V(II)	10	
-	#25	Operation command	H0000	

3) Instructions

When the servo-on pushbutton switch and the GND of the power supply are shorted, the ABS data is transmitted when the servo amplifier power is turned ON, or at the leading edge of the RUN signal after a PC reset operation (PC-RESET). The ABS data is also transmitted when an alarm is reset, or when the emergency stop state is reset.

If check sum discrepancy is detected in the transmitted data, the ABS data transmission is retried up to three times. If the check sum discrepancy is still detected after retrying, the ABS check sum error is generated (Y12 ON).

The following time periods are measured and if the ON/OFF state does not change within the specified time, the ABS communication error is generated (Y11 ON).

ON period of ABS transfer mode (Y1)

ON period of ABS request (Y2)

OFF period of ready to send the ABS data (X2).

14. ABSOLUTE POSITION DETECTION SYSTEM

(b) Device list

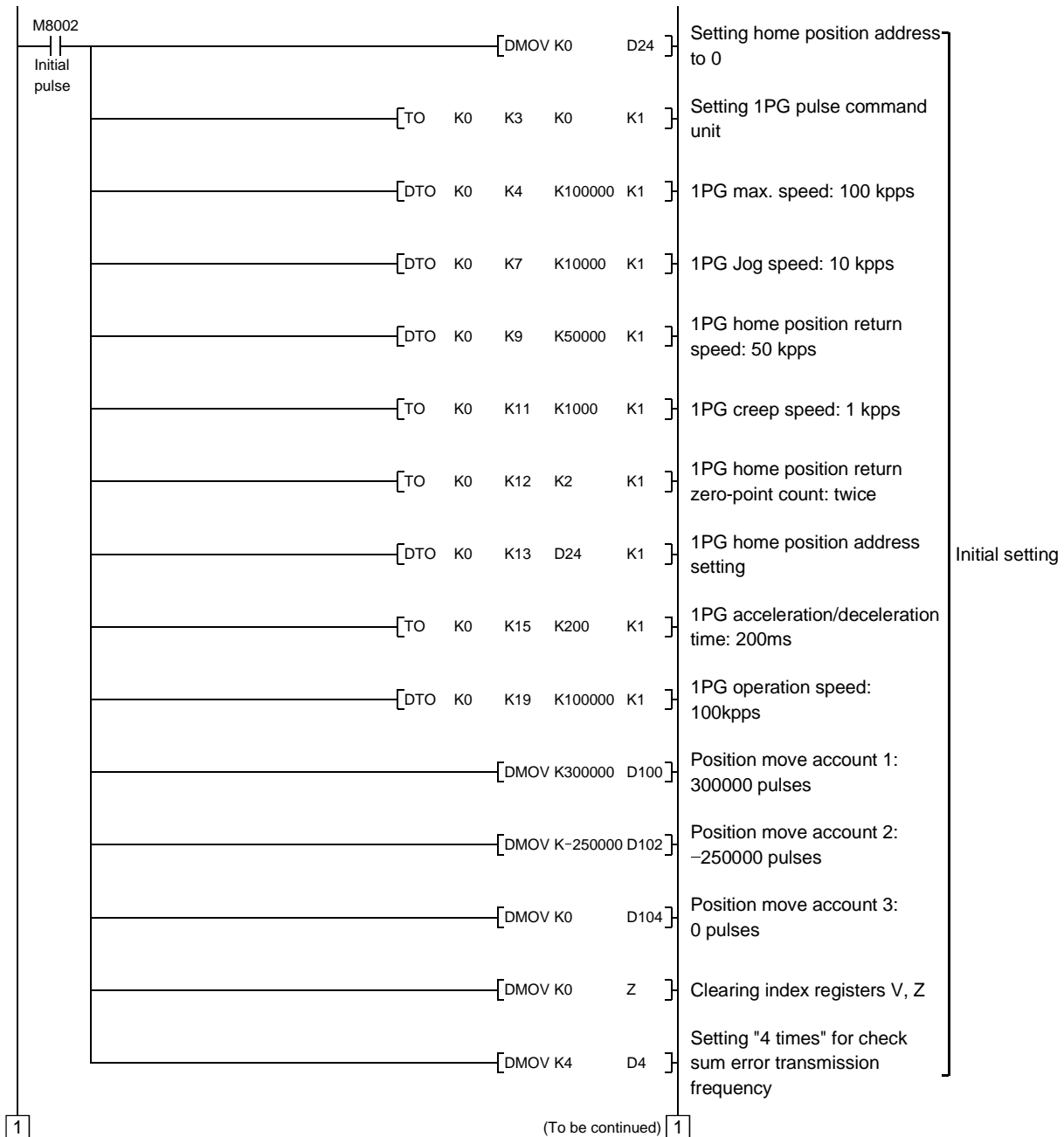
X input contact		Y output contact	
X0	Transmission data bit 0 / completion of positioning	Y0	Servo-on
X1	Transmission data bit 1 / zero speed	Y1	ABS transfer mode
X2	Send ABS transmission data ready/ torque limit control	Y2	ABS request
X3	Servo alarm	Y3	Alarm reset
X4	Alarm reset PB	Y4 (Note 2)	Electromagnetic brake output
X5	Servo emergency stop	Y5 (Note 1)	Clear
X6	Servo-on PB	Y10	Servo alarm
X7	Servo ready	Y11	ABS communication error
X10	JOG (+) PB	Y12	ABS check sum error
X11	JOG (-) PB		
X12	Position start PB		
X13	Position stop PB		
X14	Home position return start PB		
X15	1PG error reset		
D register		M contact	
D0	ABS data: Lower 16 bits	M0	Error flag
D1	ABS data: Upper 16 bits	M1	ABS data transmission start
D2	Check sum addition counter	M2	Retry command
D3	Check data in case of check sum error	M3	ABS data read
D4	Transmission retry count in check sum discrepancy	M4	Spare
D24	Home position address: Lower 16 bits	M5	Servo-on request
D25	Home position address: Upper 16 bits	M6	Retry flag
D106	1PG present position address: Lower 16 bits	M10	ABS data 2 bit receiving buffer
D107	1PG present position address: Upper 16 bits	M11	
		M12	
		M13	
		M20	ABS data 32 bit buffer
		↓	
		M51	
		M52	Check sum 6 bit buffer
		↓	
		M57	
		M58	For checksum comparison
		M59	
		M62	
		M63	Sum check discrepancy (greater) >
		M64	Sum check discrepancy =
		M70 (Note 1)	Sum check discrepancy (less) >
		M71 (Note 1)	Clear (CR) ON timer request
		M99	Data set type home position return request
			ABS data ready
T timer		C counter	
T200	Retry wait timer	C0	All data reception frequency counter (19 times)
T201	ABS transfer mode timer	C1	Check sum reception frequency counter
T202	ABS request response timer	C2	ABS data reception frequency counter (16 times)
T203	Ready to send response timer		
T204	ABS data waiting timer		
T210 (Note 1)	Clear (CR) ON timer		

Note 1. Necessary when data set type home position return is executed.

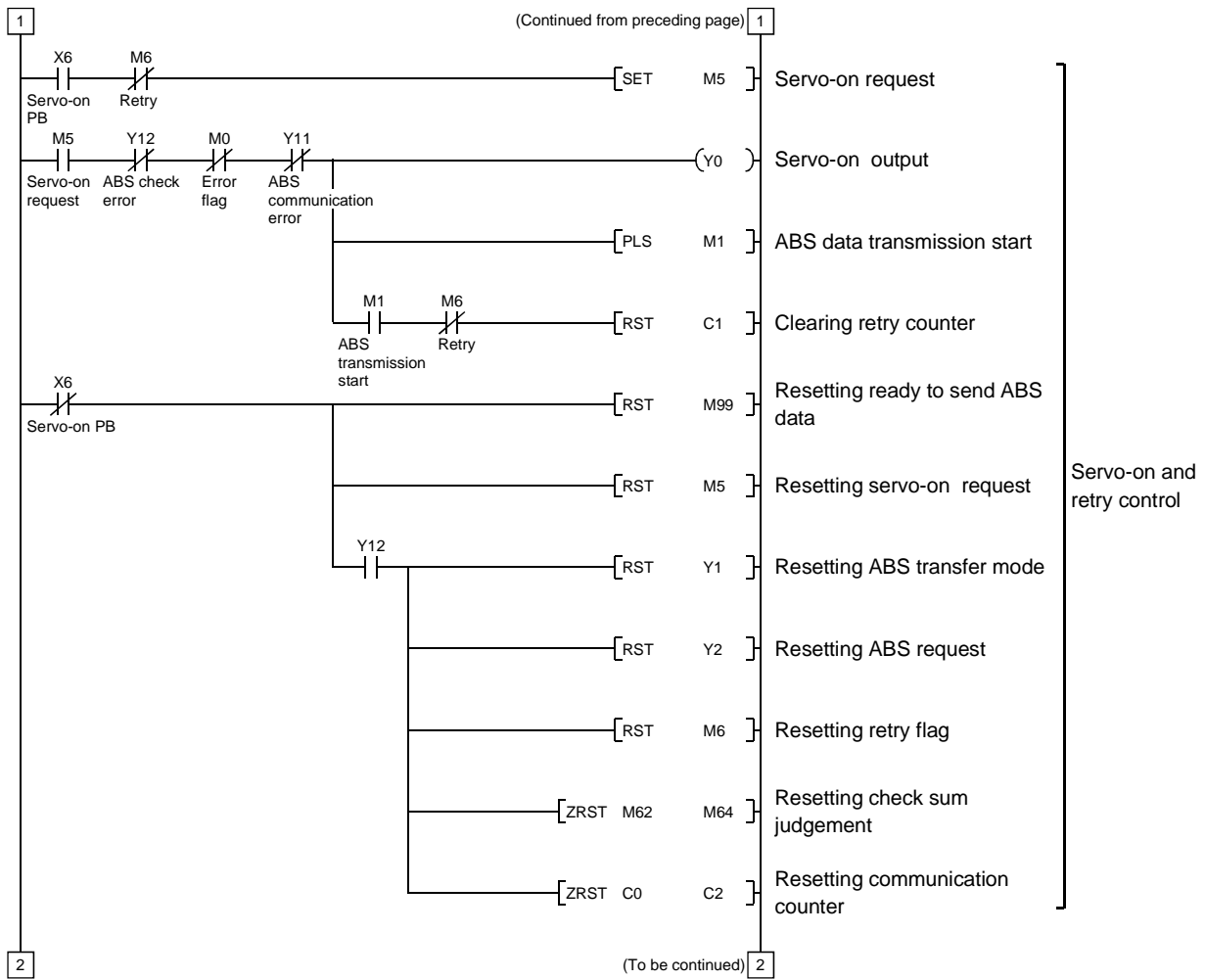
2. Necessary in the event of electromagnetic brake output.

14. ABSOLUTE POSITION DETECTION SYSTEM

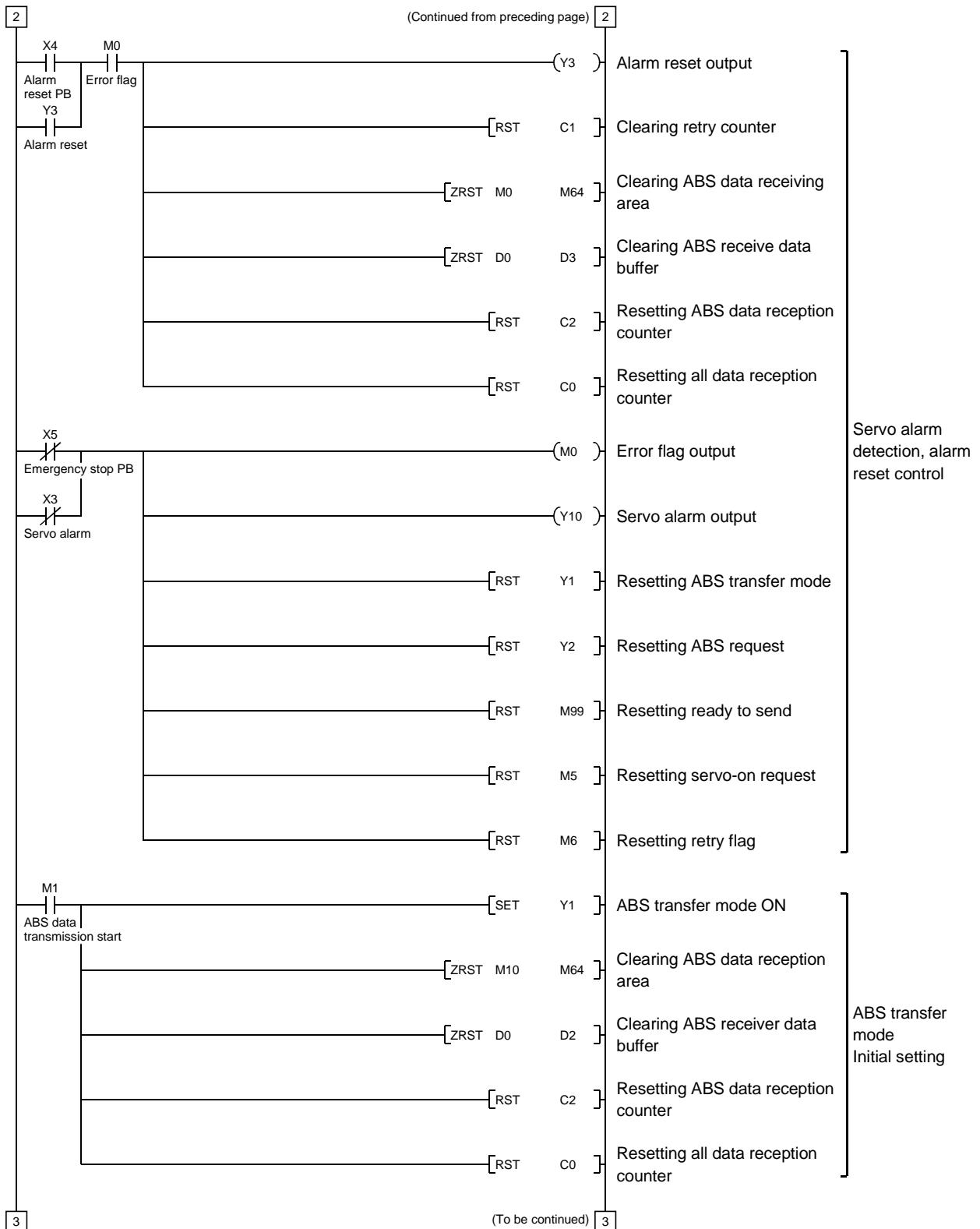
(c) ABS data transfer program for X-axis



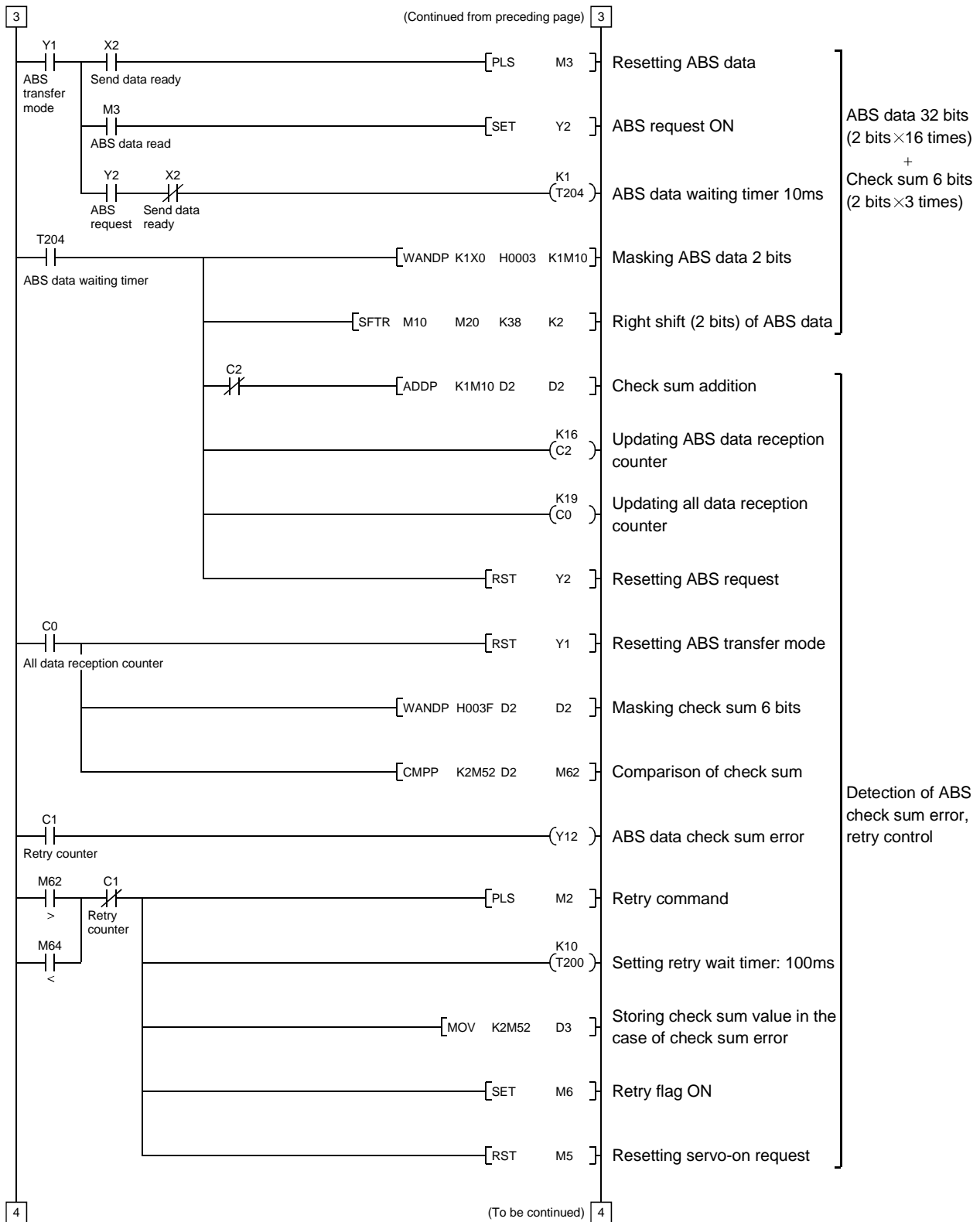
14. ABSOLUTE POSITION DETECTION SYSTEM



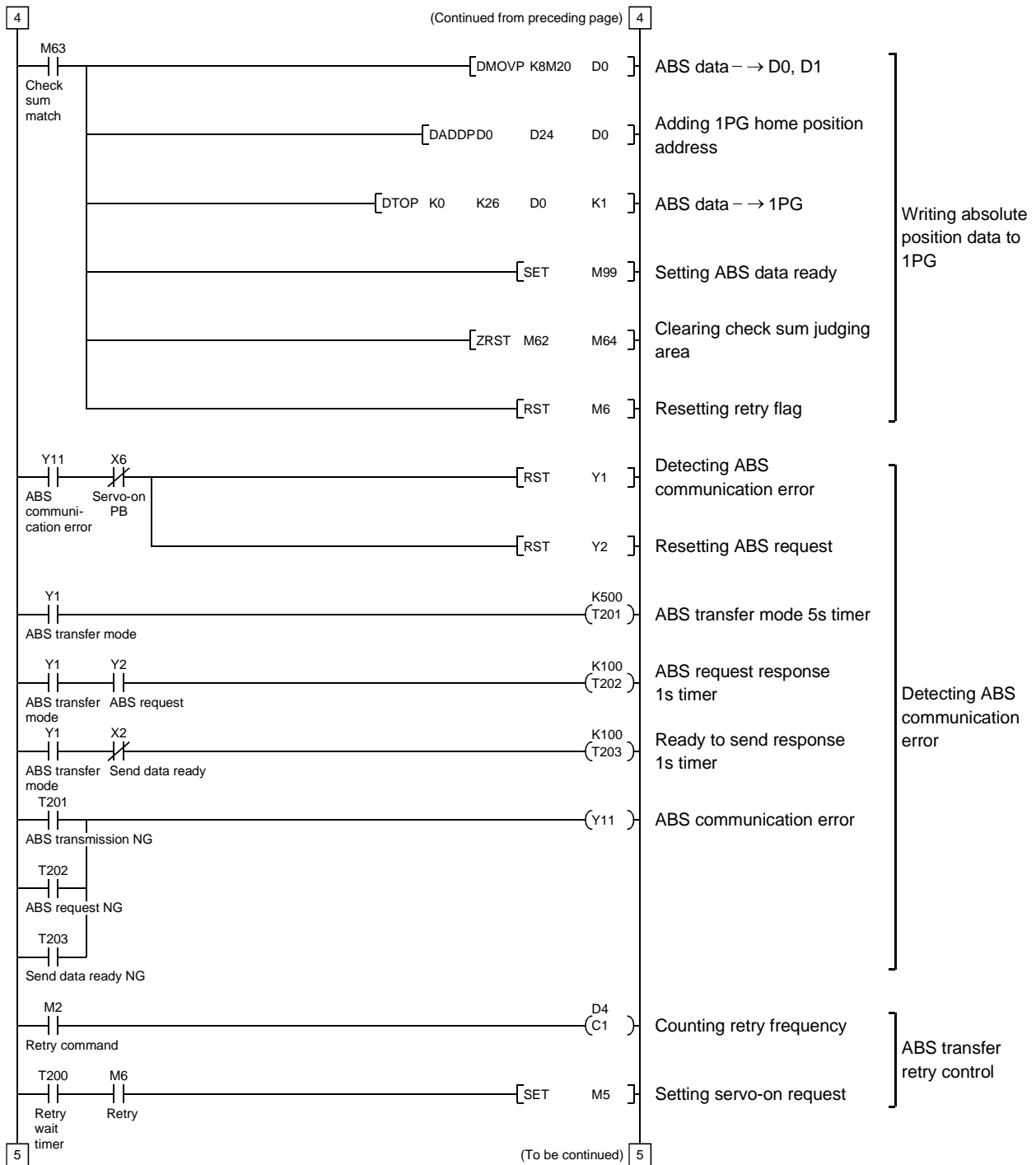
14. ABSOLUTE POSITION DETECTION SYSTEM



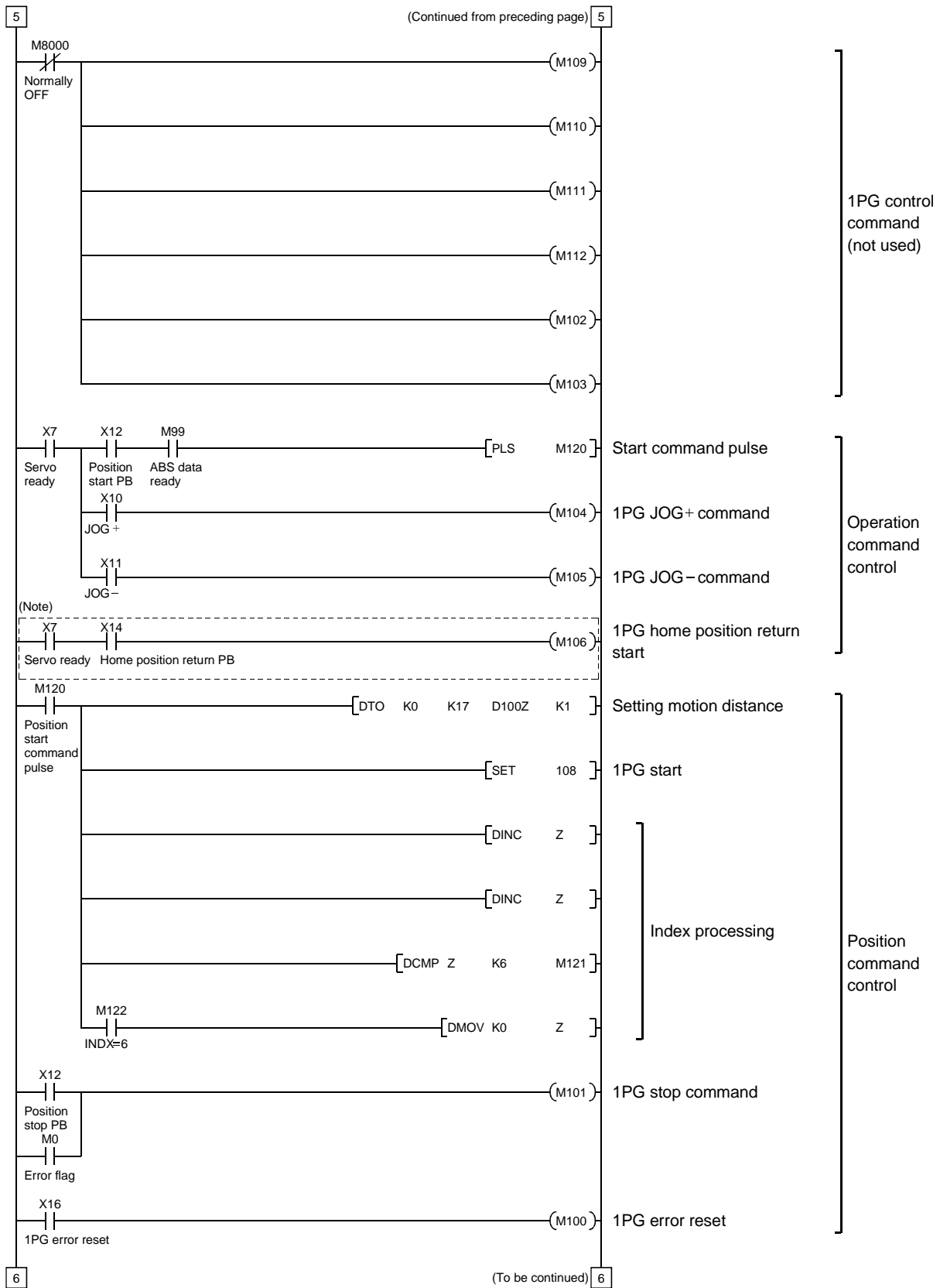
14. ABSOLUTE POSITION DETECTION SYSTEM



14. ABSOLUTE POSITION DETECTION SYSTEM

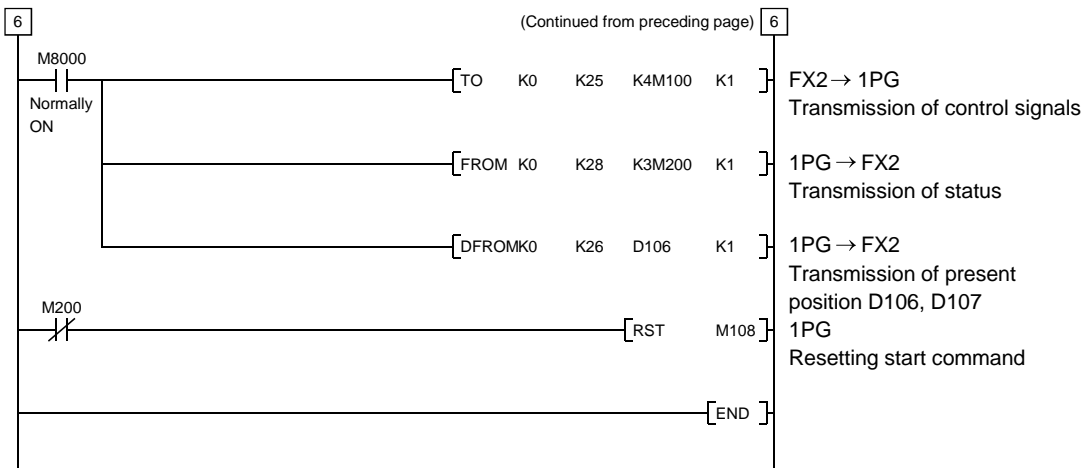


14. ABSOLUTE POSITION DETECTION SYSTEM



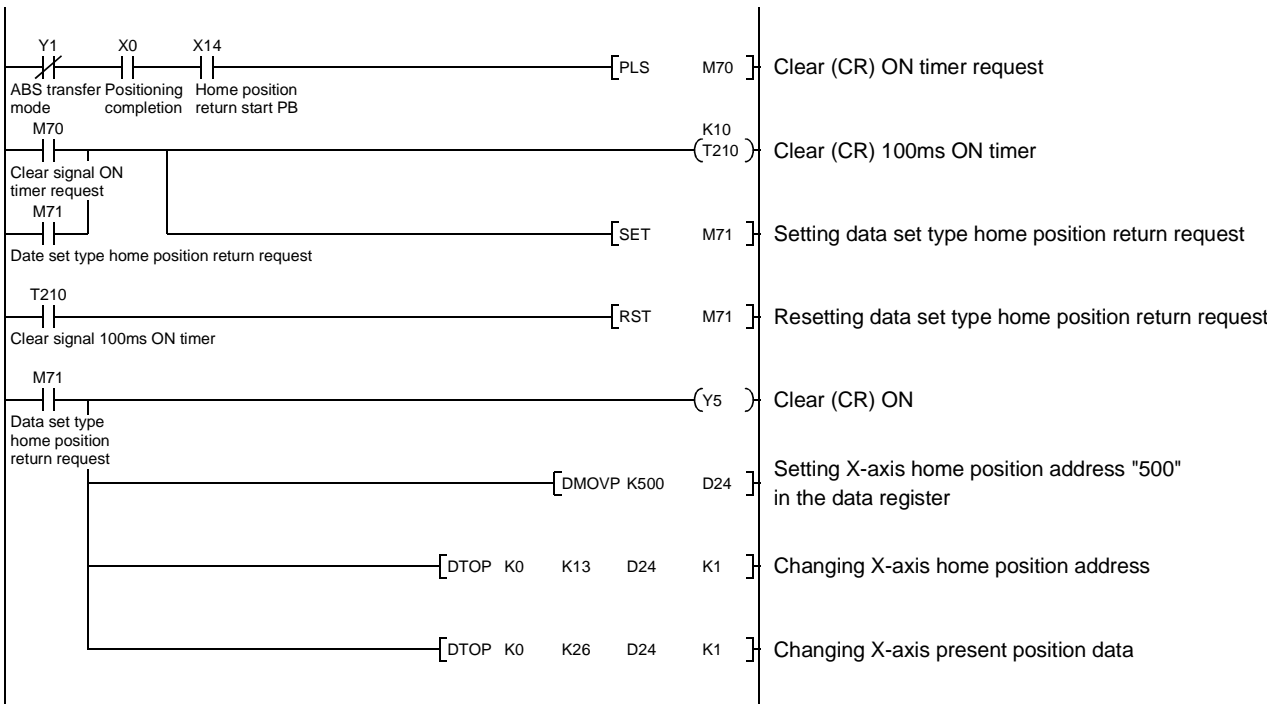
Note. Program example for the dog type home position return. For the data set type home position return, refer to the program example in (2), (d) in this section.

14. ABSOLUTE POSITION DETECTION SYSTEM



(d) Data set type home position return

After jogging the machine to the position where the home position (e.g.500) is to be set, choose the home position return mode set the home position with the home position return start (PBON). After switching power on, rotate the servo motor more than 1 revolution before starting home position return. Do not turn ON the clear (CR) (Y5) for an operation other than home position return. Turning it ON in other circumstances will cause position shift.

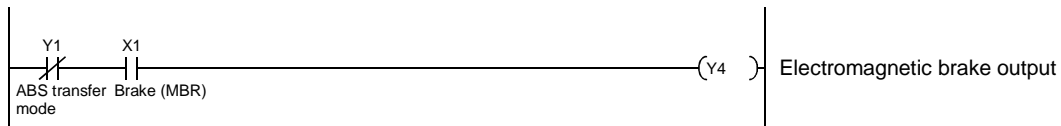


14. ABSOLUTE POSITION DETECTION SYSTEM

(e) Electromagnetic brake output

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.

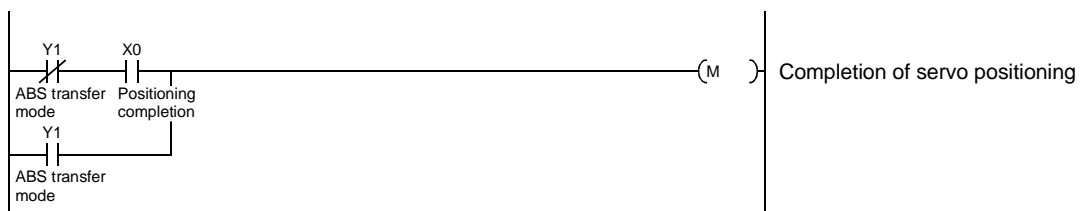
Set " ☐ ☐ ☐ 1" in parameter No. PA04 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid.



(f) Positioning completion

To create the status information for servo positioning completion.

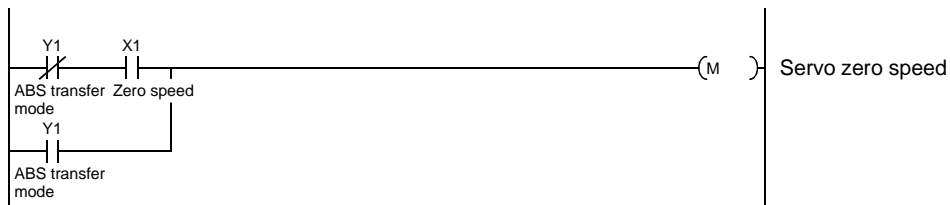
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(g) Zero speed

To create the status information for servo zero speed.

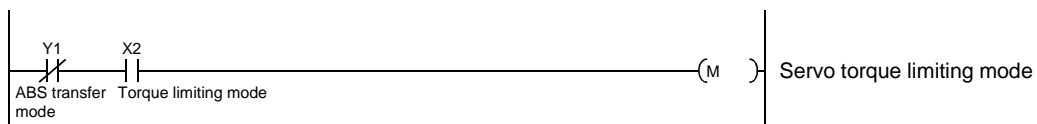
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(h) Torque limiting

To create the status information for the servo torque limiting mode.

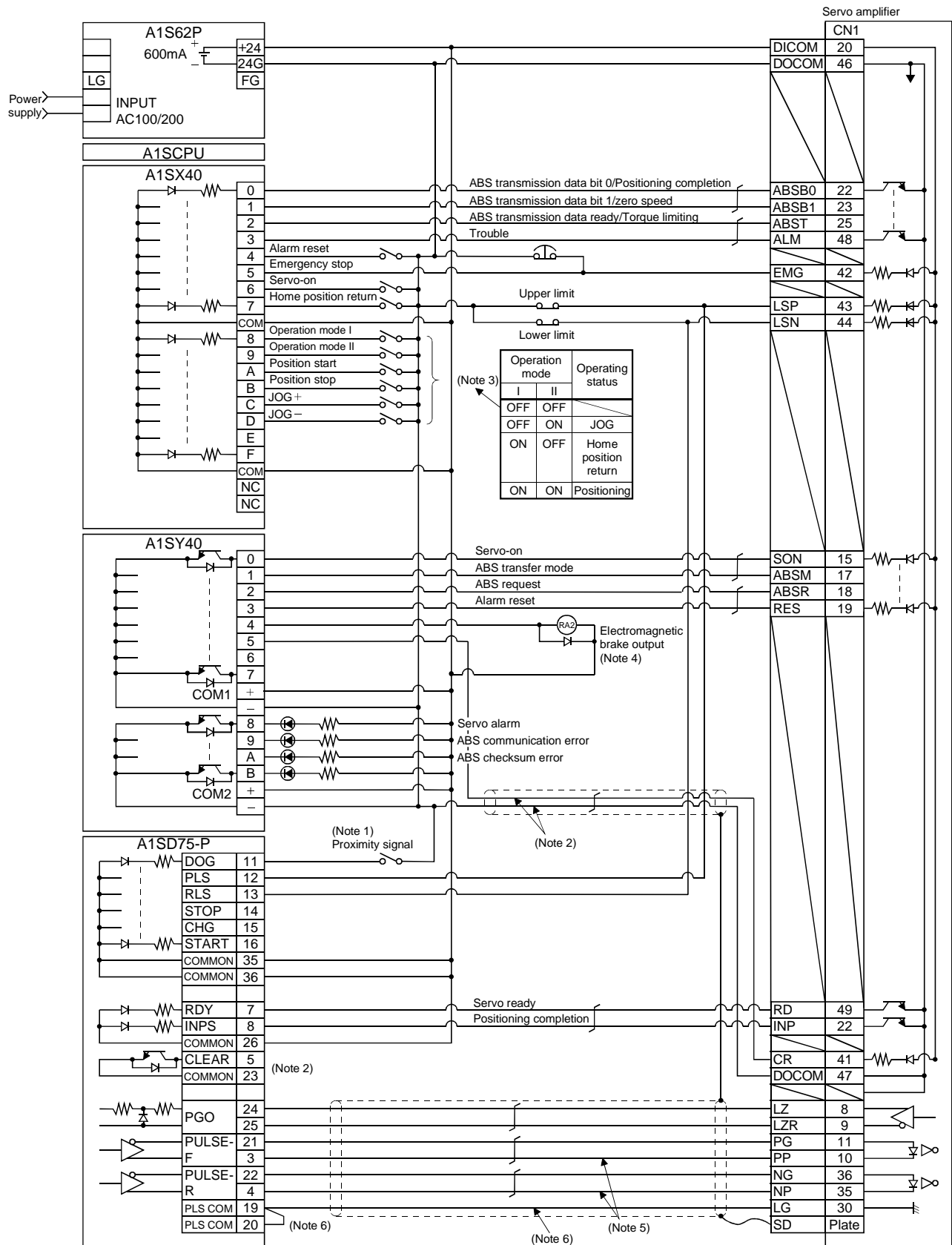
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the torque limiting must be off.



14. ABSOLUTE POSITION DETECTION SYSTEM

14.8.2 MELSEC A1SD75(AD75)

(1) Connection diagram



14. ABSOLUTE POSITION DETECTION SYSTEM

Note 1. For the dog type home position return. Need not be connected for the data set type home position return.

2. If the servo motor provided with the zero point signal is started, the A1SD75(AD75) will output the deviation counter clear (CR).
Therefore, do not connect the clear (CR) of the MR-J3-A to the A1SD75(AD75) but connect it to the output module of the programmable controller.
3. This circuit is provided for your reference.
4. The electromagnetic brake output should be controlled via a relay connected to the programmable controller output.
5. Use the differential line driver system for pulse input. Do not use the open collector system.
6. To reinforce noise suppression, connect LG and pulse output COM.

14. ABSOLUTE POSITION DETECTION SYSTEM

(2) Sequence program example

(a) Conditions

- 1) When the servo-on signal and power supply GND are shorted, the ABS data is transmitted at power-on of the servo amplifier or on the leading edge of the RUN signal after a PC reset operation (PC-RESET). The ABS data is also transmitted when an alarm is reset or when an emergency stop is reset.
- 2) If a checksum mismatch is detected in the transmitted data, data transmission is retried up to three times. If the checksum mismatch still persists after the retries, the ABS checksum error occurs (Y3A ON).
- 3) The following time periods are measured. If the ON/OFF state does not change within the specified time, the ABS communication error occurs change within the specified time, the ABS communication error occurs (Y3A ON):
 - ON period of ABS transfer mode (Y31)
 - ON period of ABS request (Y32)
 - OFF period of reading to send ABS data (X22)

(b) Device list

X input contact		Y output contact	
X20	ABS Transmission data bit 0 / positioning completion	Y30	Servo-on
X21	ABS Transmission data bit 1 / zero speed	Y31	ABS transfer mode
X22	Reading to send ABS data / limiting torque	Y32	ABS request
X23	Servo alarm	Y33	Alarm reset
X24	Alarm reset	X34 (Note 2)	Electromagnetic brake output
X25	Servo emergency stop	Y35 (Note 1)	Clear
X26	Servo-on	Y38	Servo alarm
X27	Home position return start	Y39	ABS communication error
X28	Operation mode I	Y3A	ABS checksum error
X29	Operation mode II		
D register		M contact	
D0	ABS data transmission counter	M5	ABS data transmission start
D1	Checksum transmission counter	M6	Sum check completion
D2	Checksum addition register	M7	Sum check mismatch
D3	ABS data: Lower 16 bits	M8	ABS data ready
D4	ABS data: Upper 16 bits	M9	Transmission data read enabled
D5	ABS data 2-bit receiving buffer	M10	Checksum 2 bits read completion
D6	Check data in case of checksum error	M11	ABS 2 bits read completion
D7	Number of retries	M12	ABS 2 bits request
D8	Forward rotation direction	M13	Servo-on request
D9	Home position address: Lower 16 bits	M14	Servo alarm
D10	Home position address: Upper 16 bits	M15	ABS data transmission retry start pulse
D11	Drive unit ready data	M16	Retry flag set
D12	Home position return completion data	M17	Retry flag reset
D110	Received shift data: Lower 16 bits	M18	PLS processing command
D111	Received shift data: Upper 16 bits	M20 (Note 1)	Clear (CR) ON timer request
T timer		M21 (Note 1)	Data set type home position return request
T0	ABS transmission mode timer	M22	Home position return processing instruction
T1	ABS request response timer		
T2	Retry wait timer	M23	Current position change processing instruction
T3	ABS data send reading response timer	M24	Current position change flag
T10 (Note 1)	Clear (CR) ON timer		
T200	Transmitted data read 10ms delay timer		
		C counter	
		C0	ABS data receive times counter
		C1	Checksum receive times counter
		C2	Retry counter

Note 1. Required for data set type home position return.

2. Required for electromagnetic brake output.

14. ABSOLUTE POSITION DETECTION SYSTEM

(c) ABS data transfer program for X axis

This sequence program example assumes the following conditions:

- Parameters of the A1SD75-P1 (AD75-P1) positioning module

- Unit setting :3 = pulse (PLS)
- Travel per pulse :1 = 1 pulse

To select the unit other than the pulse, conversion into the unit of the feed value per pulse is required.

Hence, add the following program to the area marked (Note) in the sequence program:

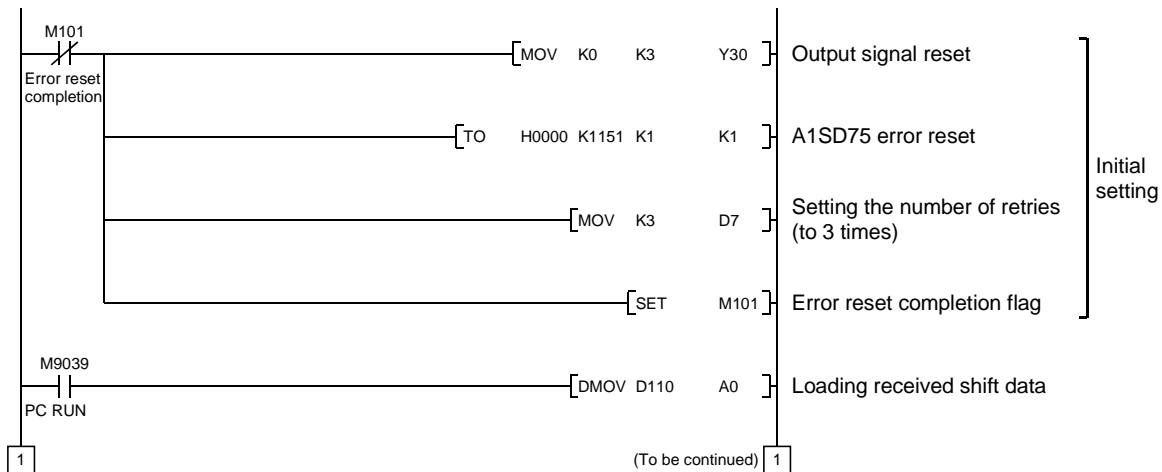
<Additional program>

—[D * P K ☐ ☐ D3 D3]

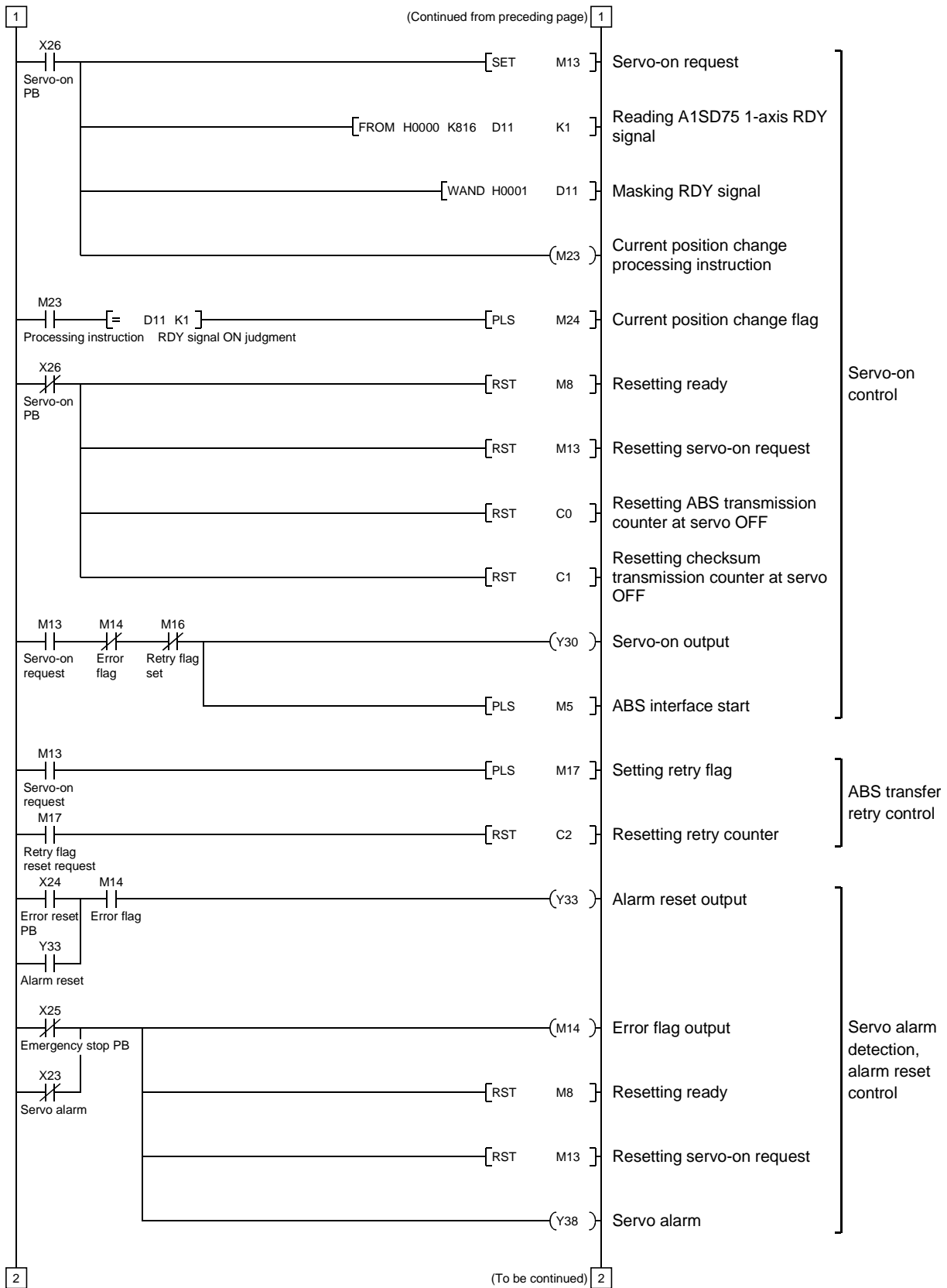
Item	mm				inch				degree				pulse
Unit setting	0				1				2				3
Travel per pulse	0.1 to	1 to	10 to	100	0.00001 to	0.0001 to	0.001 to	0.01 to	0.00001 to	0.0001 to	0.001 to	0.01 to	
Unit of travel	μm/PLS				inch/PLS				degree/PLS				PLS
Constant K for conversion into unit of travel	1 to	10 to	100 to	1000	1 to	10 to	100 to	1000	1 to	10 to	100 to	1000	None

Reference

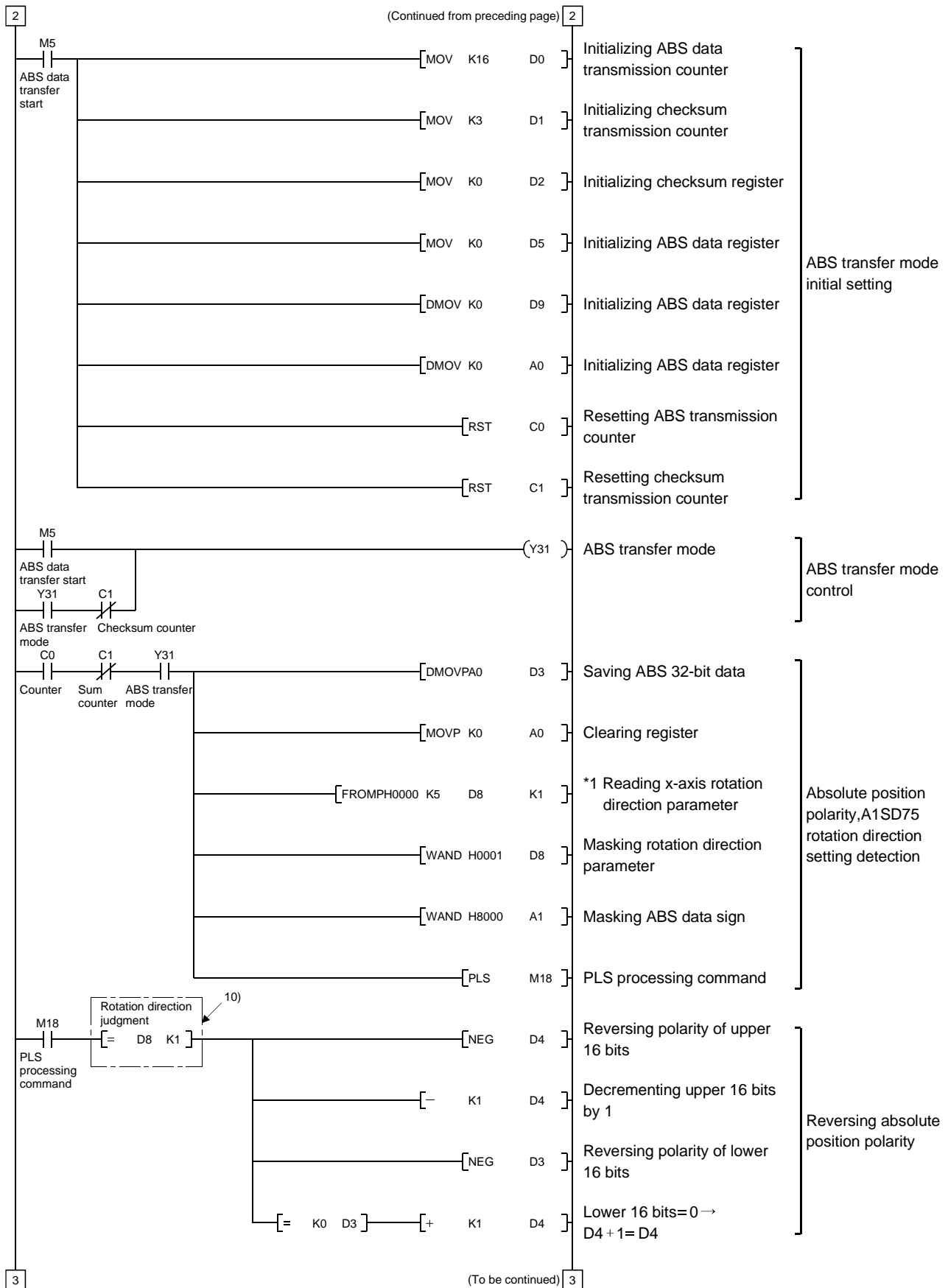
- For 1μm/PLS, set constant K to 10
- For 5μm/PLS, set constant K to 50
- The additional program is not required for the unit setting is PLS.



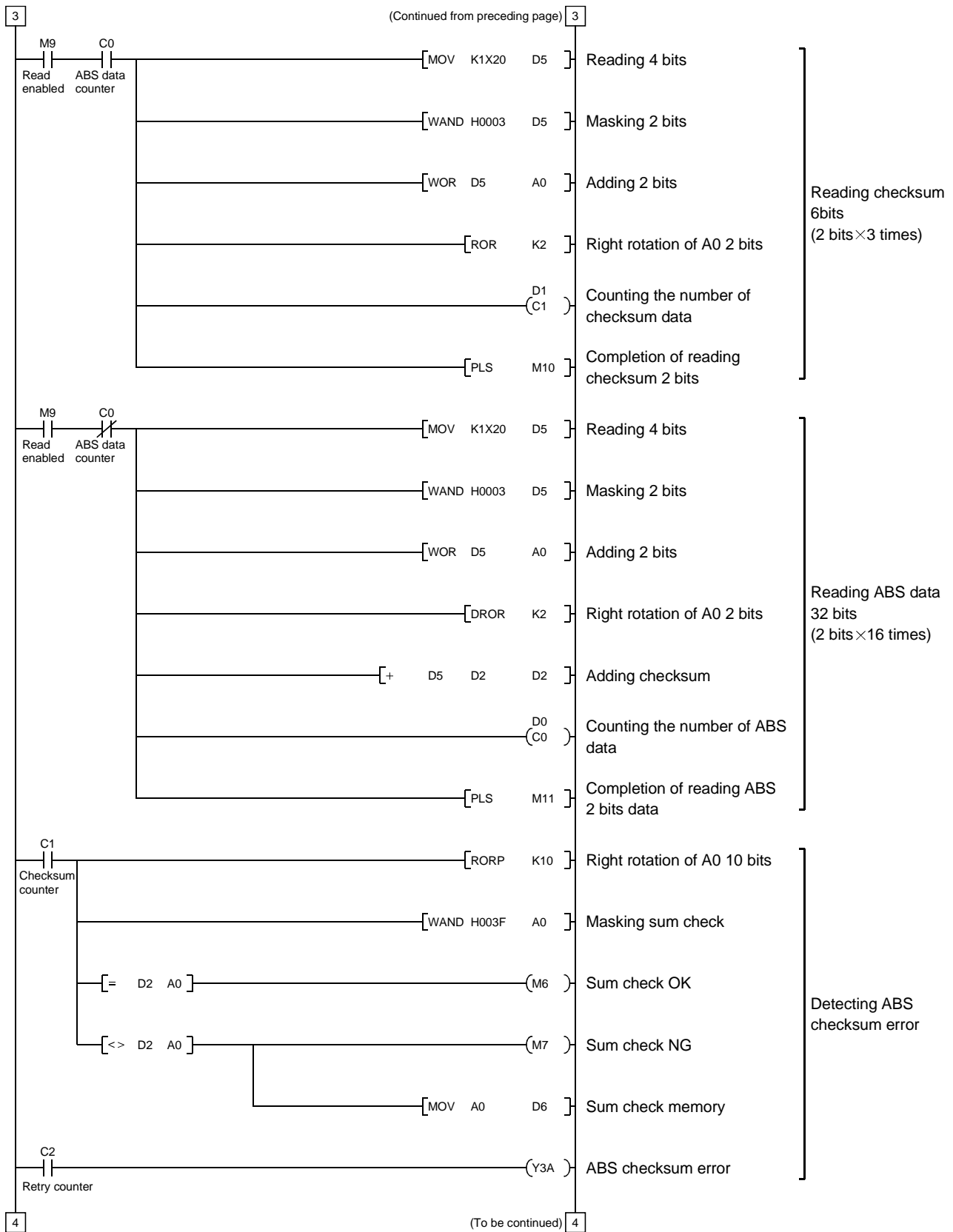
14. ABSOLUTE POSITION DETECTION SYSTEM



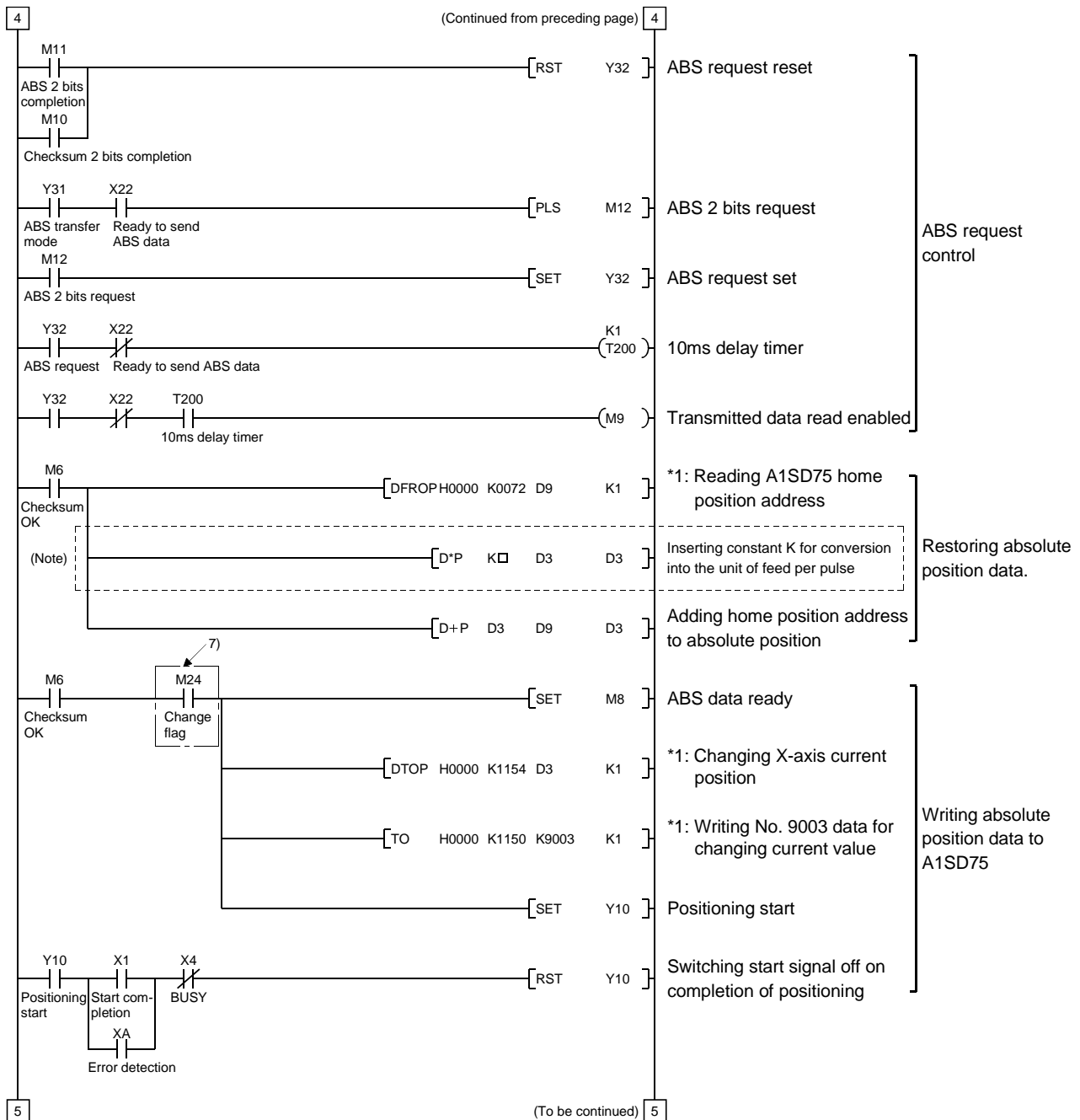
14. ABSOLUTE POSITION DETECTION SYSTEM



14. ABSOLUTE POSITION DETECTION SYSTEM



14. ABSOLUTE POSITION DETECTION SYSTEM



Note. When the unit setting parameter value of the AD75 positioning module is changed from "3" (pulse) to "0" (mm), the unit is $\times 0.1\mu\text{m}$ for the input value. To set the unit to $\times 1\mu\text{m}$, add this program to multiple the feed value by 10.

14. ABSOLUTE POSITION DETECTION SYSTEM

(d) X-axis program

Do not execute the X-axis program while the ABS ready (M10) is off.

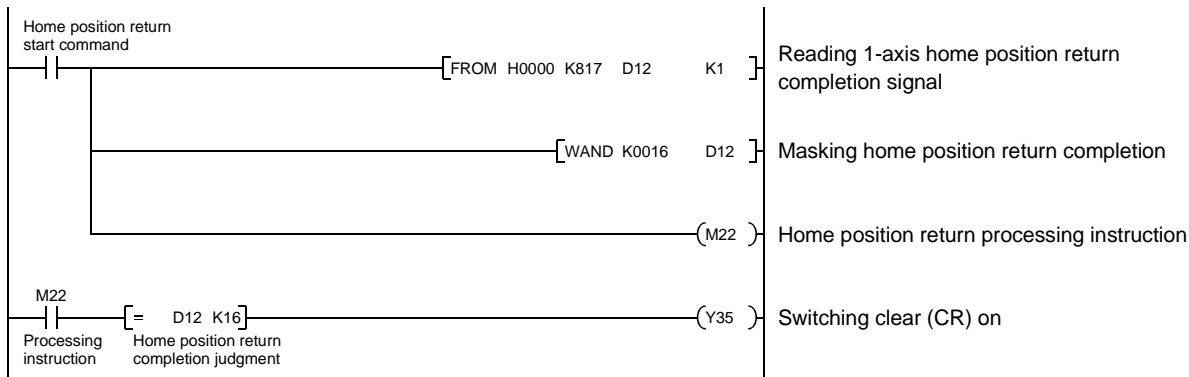


(e) Dog type home position return

Refer to the home position return program in the A1SD75 User' s Manual.

Note that this program requires a program which outputs the clear (CR) (Y35) after completion of home position return.

Add the following program:



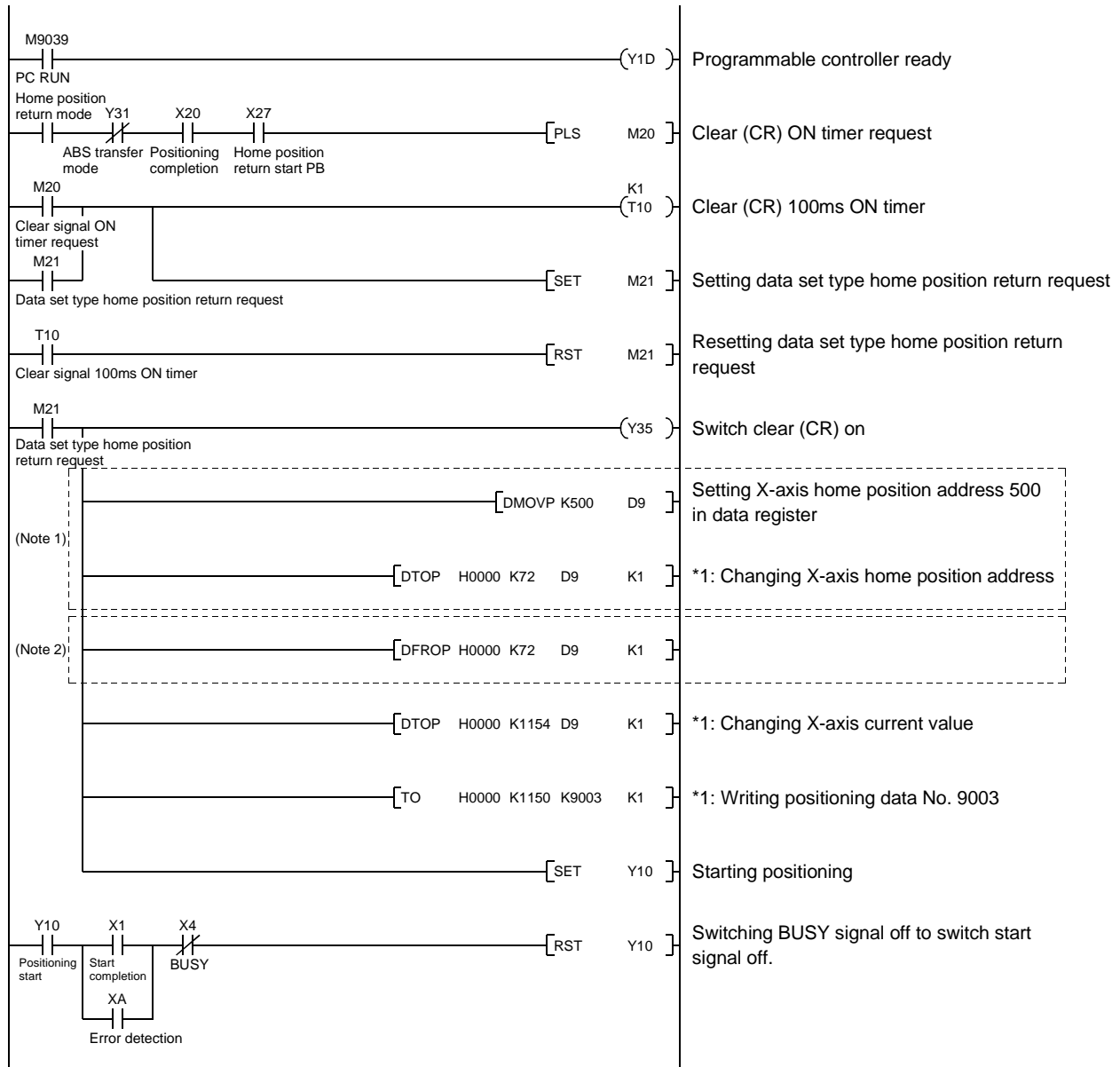
14. ABSOLUTE POSITION DETECTION SYSTEM

(f) Data set type home position return

After jogging the machine to the position where the home position (e.g. 500) is to be set, choose the home position return mode and set the home position with the home position return start (PBON).

After switching power on, rotate the servo motor more than 1 revolution before starting home position return.

Do not turn ON the clear (CR) (Y35) for an operation other than home position return. Turning it on in other circumstances will cause position shift.



Note 1. If the data of the home position address parameter is not written from the A7PHP programming tool or the like before starting the data set type home position return program, this sequence circuit (Note 1) is required and the sequence circuit (Note 2) is not required.

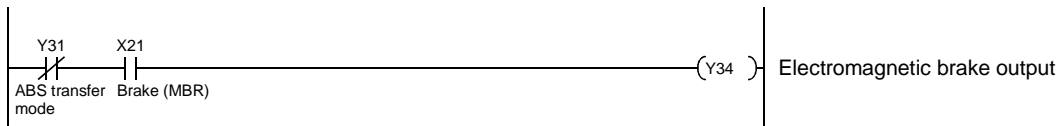
2. Contrary to above 2, if the home position address is written in the home position address parameter, the sequence circuit (Note1) is not required but this sequence circuit (Note 1) is required.

14. ABSOLUTE POSITION DETECTION SYSTEM

(g) Electromagnetic brake output

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.

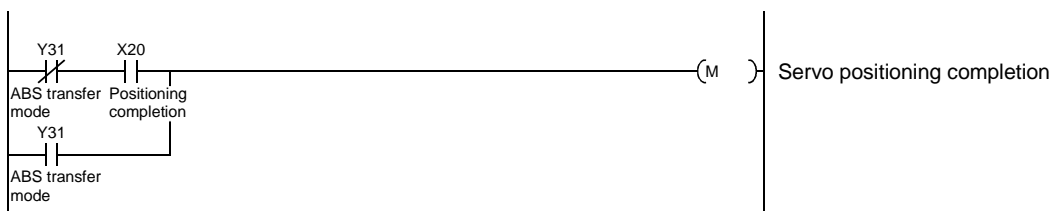
Set " ☐ ☐ ☐ 1" in parameter No. PA04 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid.



(h) Positioning completion

To create the status information for servo positioning completion.

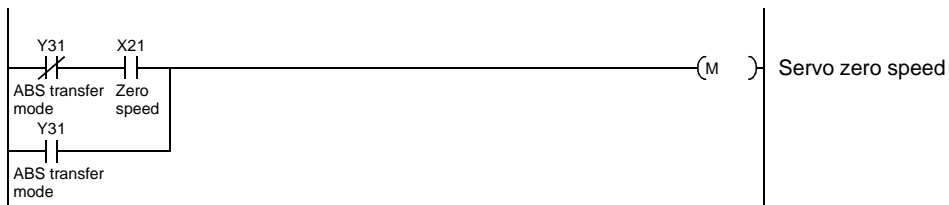
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(i) Zero speed

To create the status information for servo zero speed.

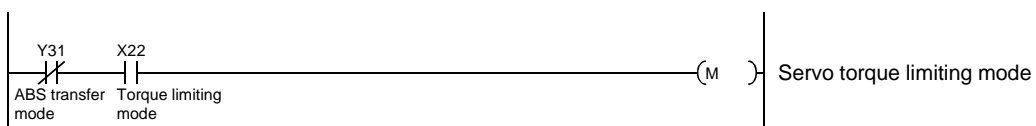
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(j) Torque limiting

To create the status information for the servo torque limiting mode.

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the torque limiting must be off.



14. ABSOLUTE POSITION DETECTION SYSTEM

(3) Sequence program - 2-axis control

The following program is a reference example for creation of an ABS sequence program for the second axis (Y axis) using a single A1SD75 module. Create a program for the third axis in a similar manner.

(a) Y-axis program

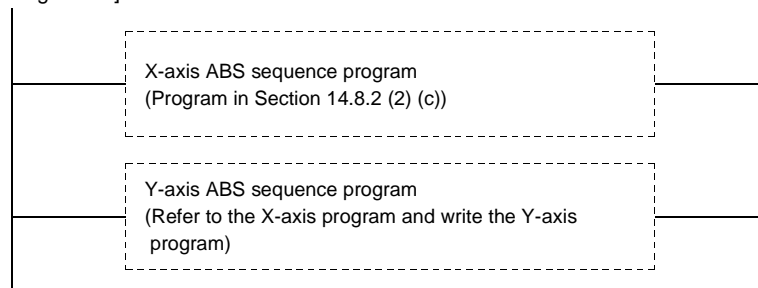
Refer to the X-axis ABS sequence program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts, T timers and C counters of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the A1SD75 differ between the X and Y axes. The instructions marked *1 in the program of Section 14.8.2 (2), (c) should be changed as indicated below for use with the Y axis:

```
[FROMP H0000 K5 D8 K1] → [FROMP H0000 K155 D8 K1]
[DFROP H0000 K0072 D9 K1] → [DFROP H0000 K222 D9 K1]
[DTOP H0000 K1154 D3 K1] → [DTOP H0000 K1204 D3 K1]
[TO H0000 K1150 K9003 K1] → [TO H0000 K1200 K9003 K1]
```

[Program configuration]



(b) Data set type home position return

Arrange the data set type home position return programs given in Section 14.8.2 (2), (f) in series to control two axes.

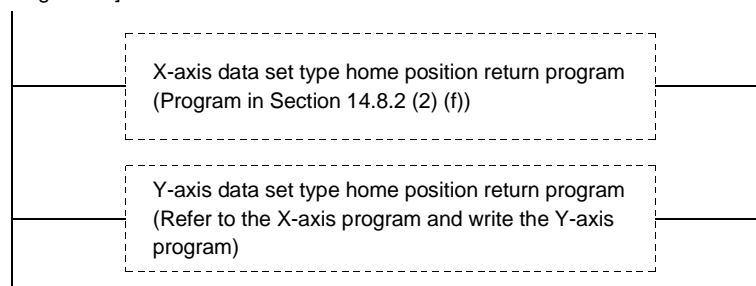
Refer to the X-axis data set type home position return program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts and T timers of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the A1SD75 differ between the X and Y axes. The instructions marked *1 in the program of Section 14.8.2 (2), (f) should be changed as indicated below for use with the Y axis:

```
[DTOP H0000 K72 D9 K1] → [DTOP H0000 K222 D9 K1]
[DTOP H0000 K1154 D9 K1] → [DTOP H0000 K1204 D3 K1]
[TO H0000 K1150 K9003 K1] → [TO H0000 K1200 K9003 K1]
```

[Program configuration]



14. ABSOLUTE POSITION DETECTION SYSTEM

Note 1. For the dog type home position return. Need not be connected for the data set type home position return.

2. For the dog type home position return, connect a QD75 deviation counter clearing signal cable. For the data set type home position return, connect a cable to the output module of the programmable logic controller.
3. This circuit is provided for your reference.
4. The electromagnetic brake output should be controlled via a relay connected to the programmable controller output.
5. Use the differential line driver system for pulse input. Do not use the open collector system.

14. ABSOLUTE POSITION DETECTION SYSTEM

(2) Sequence program example

(a) Conditions

- 1) When the servo-on signal and power supply GND are shorted, the ABS data is transmitted at power-on of the servo amplifier or on the leading edge of the RUN signal after a PC reset operation (PC-RESET). The ABS data is also transmitted when an alarm is reset or when an emergency stop is reset.
- 2) An ABS checksum error is caused (Y3AON) if checksum inconsistency is found in transferred data.
- 3) The following time periods are measured. If the ON/OFF state does not change within the specified time, the ABS communication error occurs change within the specified time, the ABS communication error occurs (Y3A ON):
 ON period of ABS transfer mode (Y31)
 ON period of ABS request (Y32)
 OFF period of reading to send ABS data (X22)

(b) Device list

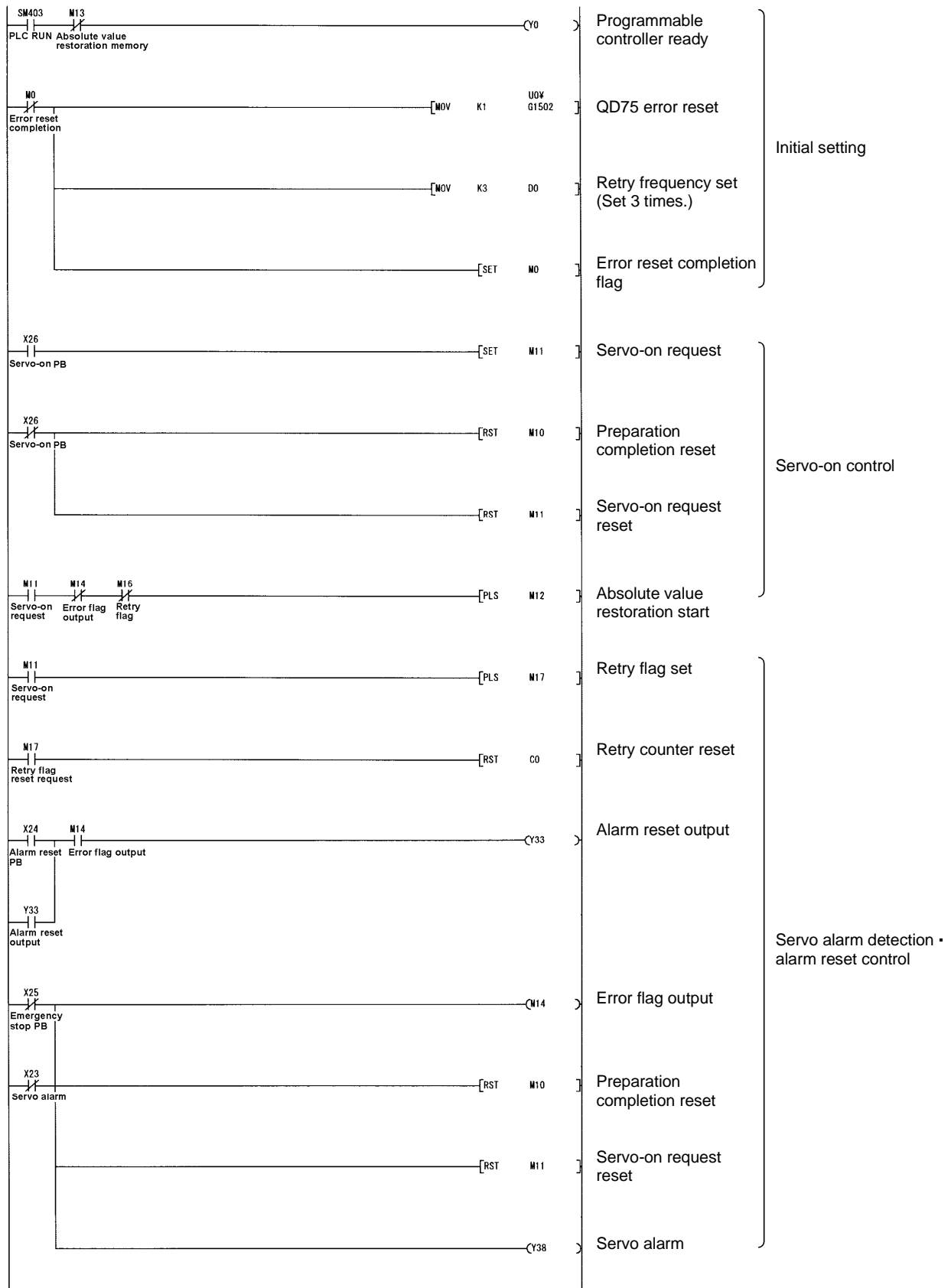
X input contact		Y output contact	
X20	ABS transmission data bit 0/Positioning completion	Y30	Servo-on
X21	ABS transmission data bit 1/zero speed	Y31	ABS transfer mode
X22	ABS transmission data ready/Torque limiting	Y32	ABS request
X23	Servo alarm	Y33	Alarm reset
X24	Alarm reset	X34 (Note 2)	Electromagnetic brake output
X25	Servo emergency stop	Y35 (Note 1)	Clear
X26	Servo-on	Y38	Servo alarm
X27	Home position return start	Y39	ABS communication error
X28	Operation mode I	Y3A	ABS checksum error
X29	Operation mode II		
D register		M contact	
D0	Number of retries	M0	End of error reset
D9	Home position address: Lower 16 bits	M10	Preparation completion
D10	Home position address: Upper 16 bits	M11	Servo-on request
D100 to D104	For special absolute value restoration instruction	M12	Absolute position restoration command
T timer		M13	Absolute value restoration memory
T0	Retry wait timer	M14	Error flag output
T10 (Note 1)	Clear (CR) ON timer	M15	Sum check NG
		M16	Retry flag
		M17	Retry flag reset request
		M20 (Note 1)	Clear (CR) ON timer request
		M21 (Note 1)	Data set type home position return request
		M100 to M101	For special absolute value restoration instruction
		C counter	
		C0	Retry counter

Note 1. Required for data set type home position return.

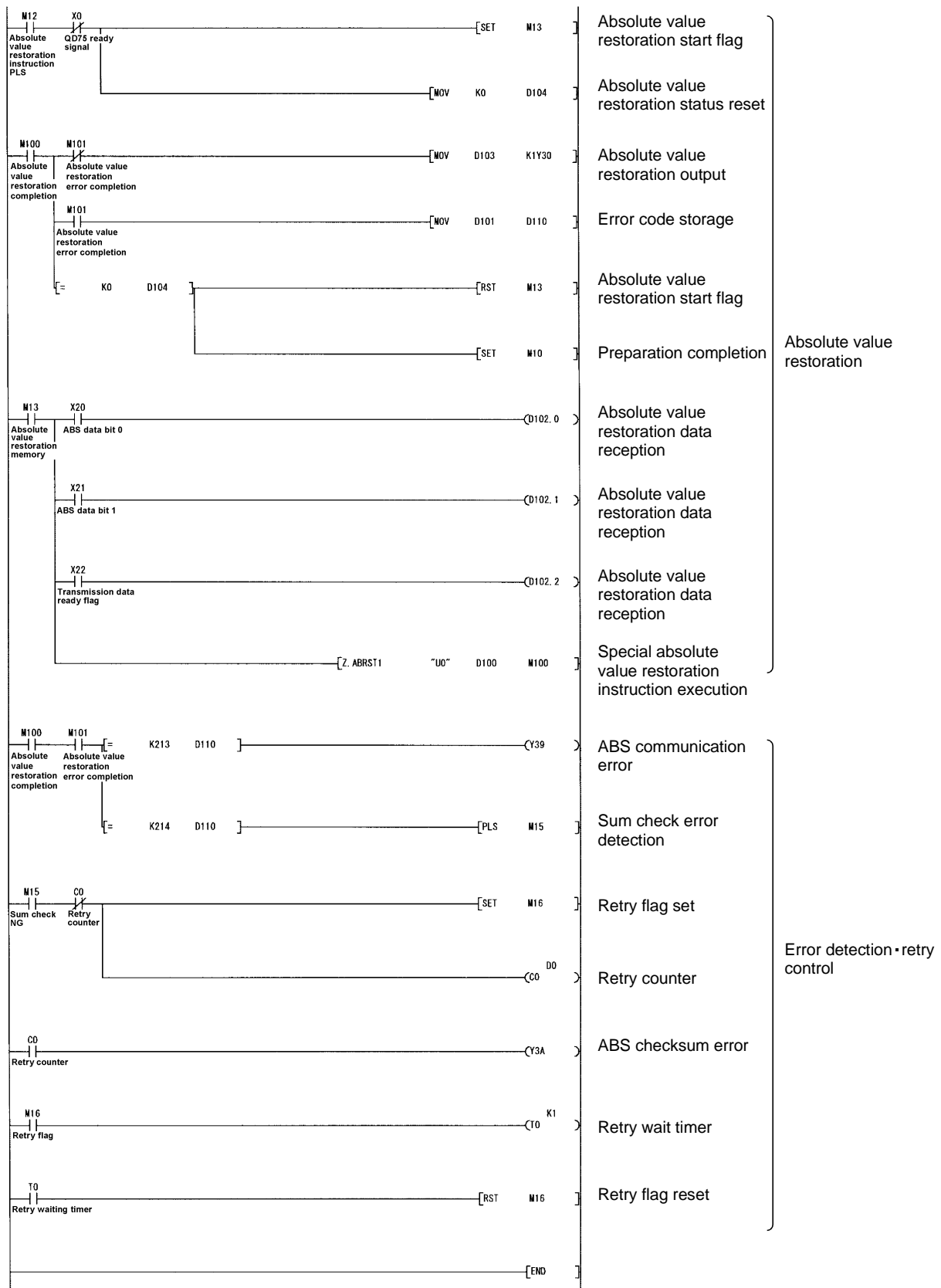
2. Required for electromagnetic brake output.

14. ABSOLUTE POSITION DETECTION SYSTEM

(c) ABS data transfer program for X axis



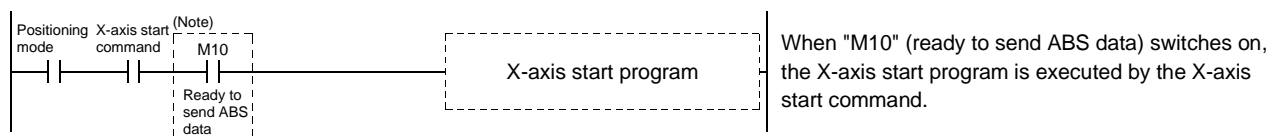
14. ABSOLUTE POSITION DETECTION SYSTEM



14. ABSOLUTE POSITION DETECTION SYSTEM

(d) X-axis program

Do not execute the X-axis program while the ABS ready (M10) is off.



(e) Dog type home position return

Refer to the home position return program in the QD75 User' s Manual.

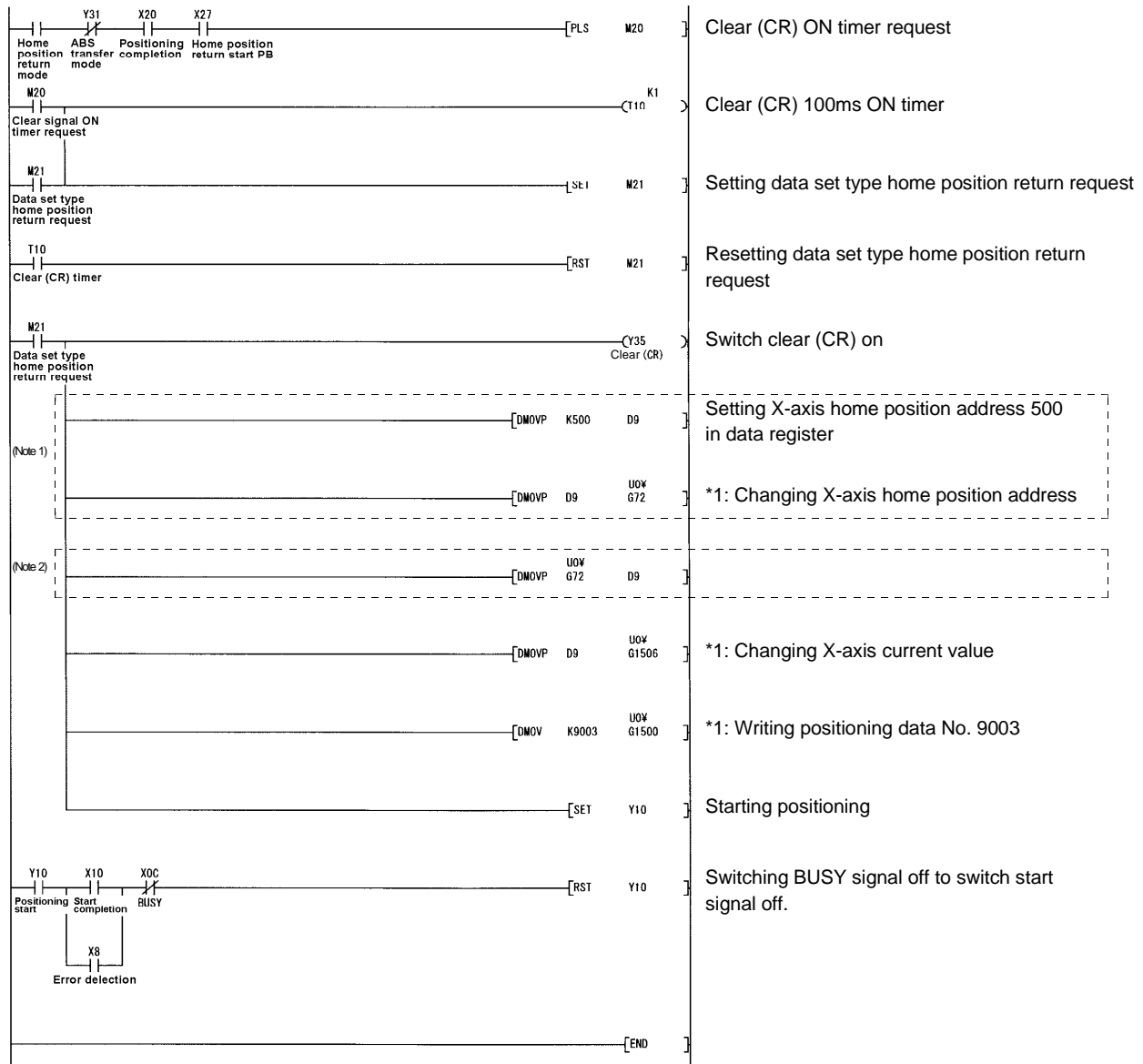
14. ABSOLUTE POSITION DETECTION SYSTEM

(f) Data set type home position return

After jogging the machine to the position where the home position (e.g. 500) is to be set, choose the home position return mode and set the home position with the home position return start (PBON).

After switching power on, rotate the servo motor more than 1 revolution before starting home position return.

Do not turn ON the clear (CR) (Y35) for an operation other than home position return. Turning it on in other circumstances will cause position shift.



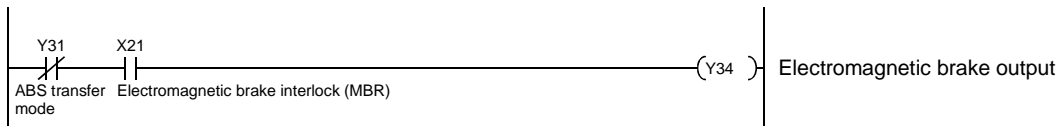
- Note 1. If the data of the home position address parameter is not written from the programming tool or the like before starting the data set type home position return program, this sequence circuit (Note 1) is required and the sequence circuit (Note 2) is not required.
2. Contrary to above 2, if the home position address is written in the home position address parameter, the sequence circuit (Note1) is not required but this sequence circuit (Note 1) is required.

14. ABSOLUTE POSITION DETECTION SYSTEM

(g) Electromagnetic brake output

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.

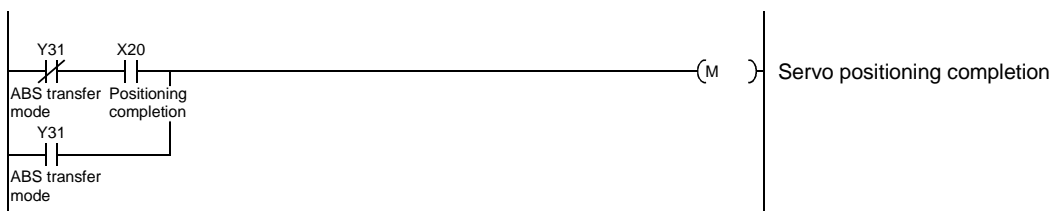
Set " ☐ ☐ ☐ 1" in parameter No. PA04 of the servo amplifier to make the electromagnetic brake interlock (MBR) valid.



(h) Positioning completion

To create the status information for servo positioning completion.

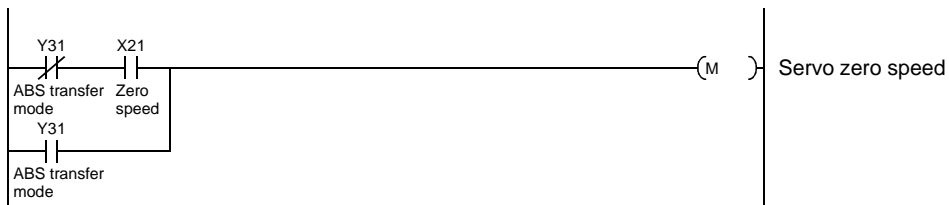
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(i) Zero speed

To create the status information for servo zero speed.

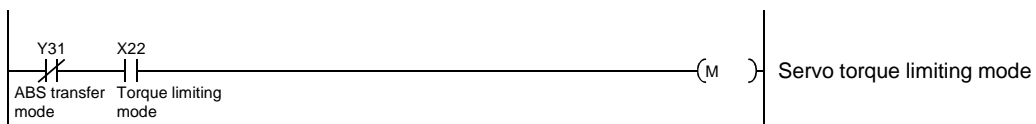
During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the servo motor must be at a stop.



(j) Torque limiting

To create the status information for the servo torque limiting mode.

During ABS data transfer (for several seconds after the servo-on (SON) is turned on), the torque limiting must be off.



14. ABSOLUTE POSITION DETECTION SYSTEM

(3) Sequence program - 2-axis control

The following program is a reference example for creation of an ABS sequence program for the second axis (Y axis) using a single QD75 module. Create a program for the third axis in a similar manner.

(a) Y-axis program

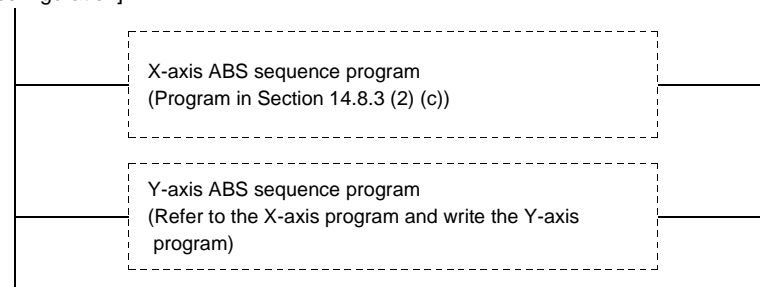
Refer to the X-axis ABS sequence program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts, T timers and C counters of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the QD75 differ between the X and Y axes. The instructions marked *1 in the program of Section 14.8.3 (2), (c) should be changed as indicated below for use with the Y axis:

[Z. ABRST1 "U0" D100 M100] → [Z. ABRST2 "U0" D100 M100]

[Program configuration]



(b) Data set type home position return

Arrange the data set type home position return programs given in Section 14.8.3 (2), (f) in series to control two axes.

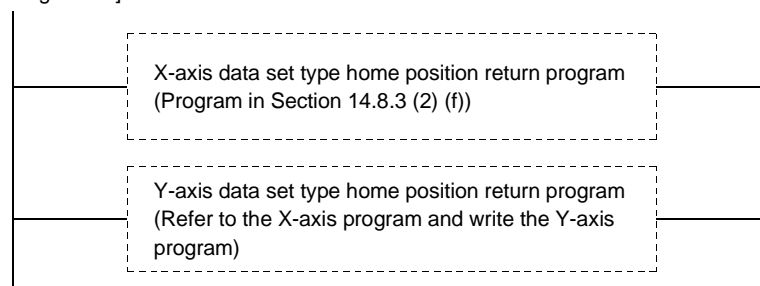
Refer to the X-axis data set type home position return program and create the Y-axis program.

Assign the X inputs, Y outputs, D registers, M contacts and T timers of the Y axis so that they do not overlap those of the X axis.

The buffer memory addresses of the QD75 differ between the X and Y axes. The instructions marked *1 in the program of Section 14.8.2 (2), (f) should be changed as indicated below for use with the Y axis:

[DMOVP D9 U0¥G72] → [DMOVP D9 U0¥G222]
[DMOVP U0¥G72 D9] → [DMOVP U0¥G222 D9]
[DMOVP D9 U0¥1506] → [DMOVP D9 U0¥1606]
[DMOVP K9003 U0¥1500] → [DMOVP D9 U0¥1600]

[Program configuration]



14. ABSOLUTE POSITION DETECTION SYSTEM

14.9 Absolute position data transfer errors

14.9.1 Corrective actions

(1) Error list

The number within parentheses in the table indicates the output coil or input contact number of the A1SD75 (AD75).

Name	Output coil		Description	Cause	Action
	AD75	1PG			
(Note) ABS communication error	Y39	Y11	1. The ABS data transfer mode signal (Y41) is not completed within 5s. 2. The ready to send signal (X32) is not turned OFF within 1s after the ABS data request signal (Y42) is turned ON. 3. The ready to send signal (X32) remains OFF for longer than 1s.	1. Wiring for ABS transfer mode signal, ABS data request signal, or ready to send signal is disconnected or connected to the DOCOM terminal.	Correct the wiring.
				2. PC ladder program wrong.	Correct the ladder.
				3. Faulty PLC output or input module.	Change the input or output module.
				4. Faulty printed board in the servo amplifier.	Change the amplifier
				5. Power supply to the servo amplifier is OFF.	Turn on the power to the servo amplifier.
ABS data check sum error	Y3A	Y12	• ABS data sumcheck resulted in mismatch four times consecutively.	1. Wiring for the ABS data signal (ABS bit 0 (PF), bit 1 (ZSP)) is disconnected or connected to the SG terminal.	Correct the wiring.
				2. PC ladder program wrong.	Correct the ladder.
				3. Faulty PLC input module.	Change the input module.
				4. Faulty printed board in the servo amplifier.	Change the amplifier.
Servo alarm	Y38	Y10	• Alarm occurred in the servo amplifier.	1. Emergency stop (EMG) of the servo amplifier was turned off.	After ensuring safety, turn EMG on.
				2. Trouble (ALM) of the servo amplifier was turned on.	Refer to Chapter 9 and take action.

Note. Refer to (2) in this section for details of error occurrence definitions.

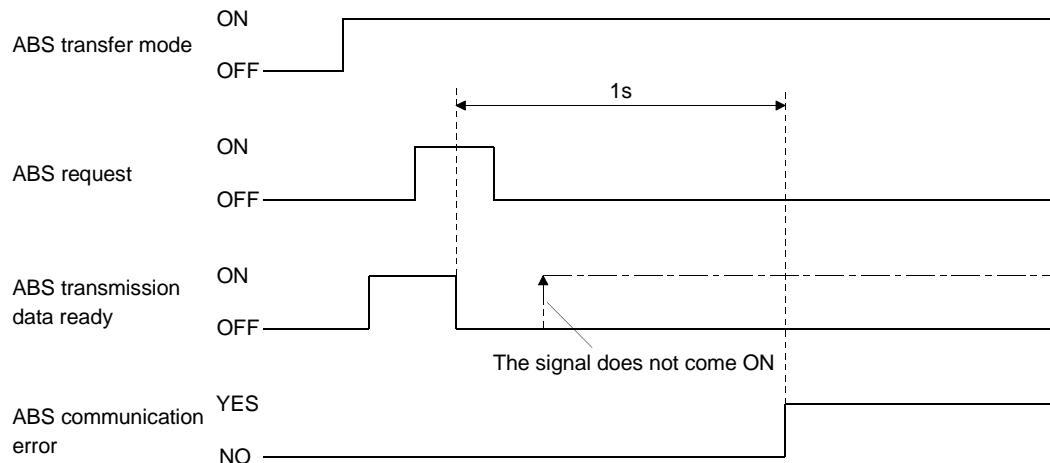
14. ABSOLUTE POSITION DETECTION SYSTEM

(2) ABS communication error

- (a) The OFF period of the ABS transmission data ready signal output from the servo amplifier is checked.

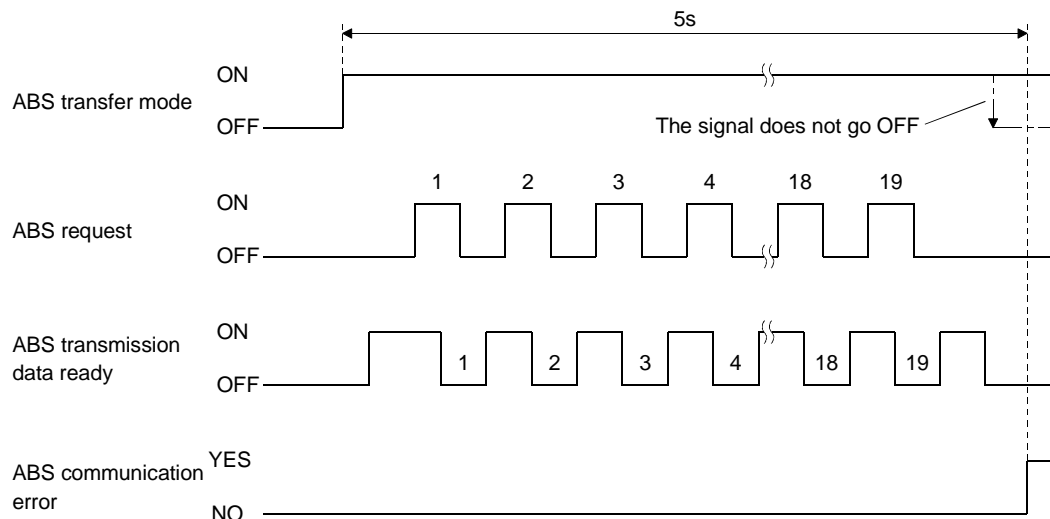
If the OFF period is 1s or longer, this is regarded as a transfer fault and the ABS communication error is generated.

The ABS communication error occurs if the ABS time-out warning (AL.E5) is generated at the servo amplifier due to an ABS request ON time time-out.



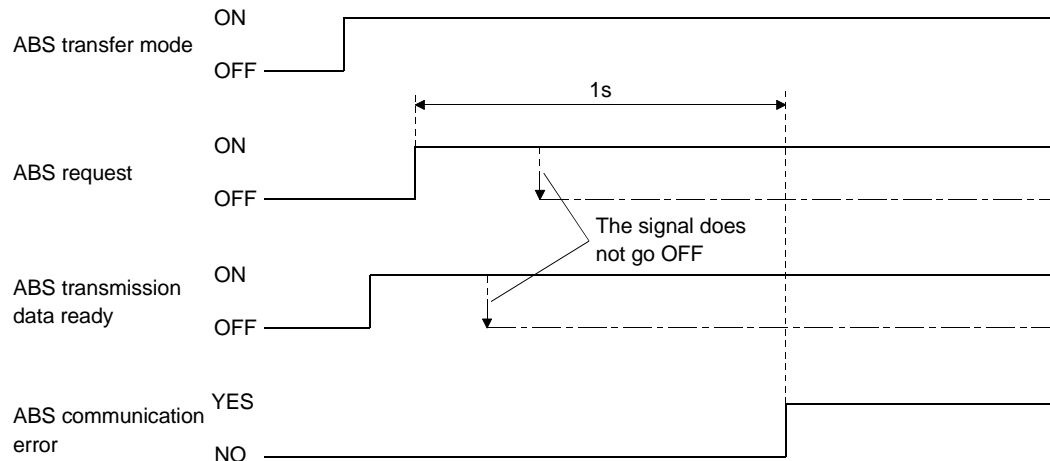
- (b) The time required for the ABS transfer mode signal to go OFF after it has been turned ON (ABS transfer time) is checked.

If the ABS transfer time is longer than 5s, this is communication error occurs if the ABS time-out warning (AL.E5) is generated at the servo amplifier due to an ABS transfer mode completion time time-out.



14. ABSOLUTE POSITION DETECTION SYSTEM

- (c) To detect the ABS time-out warning (AL.E5) at the servo amplifier, the time required for the ABS request signal to go OFF after it has been turned ON (ABS request time) is checked. If the ABS request remains ON for longer than 1s, it is regarded that an fault relating to the ABS request signal or the ABS transmission data ready (ABST) has occurred, and the ABS communication error is generated. The ABS communication error occurs if the ABS time-out warning (AL.E5) is generated at the servo amplifier due to an ABS request OFF time time-out.



14.9.2 Error resetting conditions

Always remove the cause of the error before resetting the error.

Name	Output coil		Servo status	Resetting condition
	AD75	1PG		
ABS communication error	Y39	Y11	Ready (RD) off	Reset when servo-on (SON) PB (X26) signal turns off.
ABS checksum error	Y3A	Y12	Ready (RD) on	For AD75 Reset when servo-on (SON) PB (X26) signal turns from off to on.
				For FX-1PG Reset when servo-on (SON) PB (X26) signal turns off.
Servo alarm	Y38	Y10	Ready (RD) on	Reset when alarm reset PB turns on or power switches from off to on.

14. ABSOLUTE POSITION DETECTION SYSTEM

14.10 Communication-based ABS transfer system

14.10.1 Serial communication command

The following commands are available for reading absolute position data using the serial communication function. When reading data, take care to specify the correct station number of the drive unit from where the data will be read.

When the master station sends the data No. to the slave station (servo amplifier), the slave station returns the data value to the master station.

(1) Transmission

Transmit command [0][2] and data No. [9][1].

(2) Reply

The absolute position data in the command pulse unit is returned in hexadecimal.

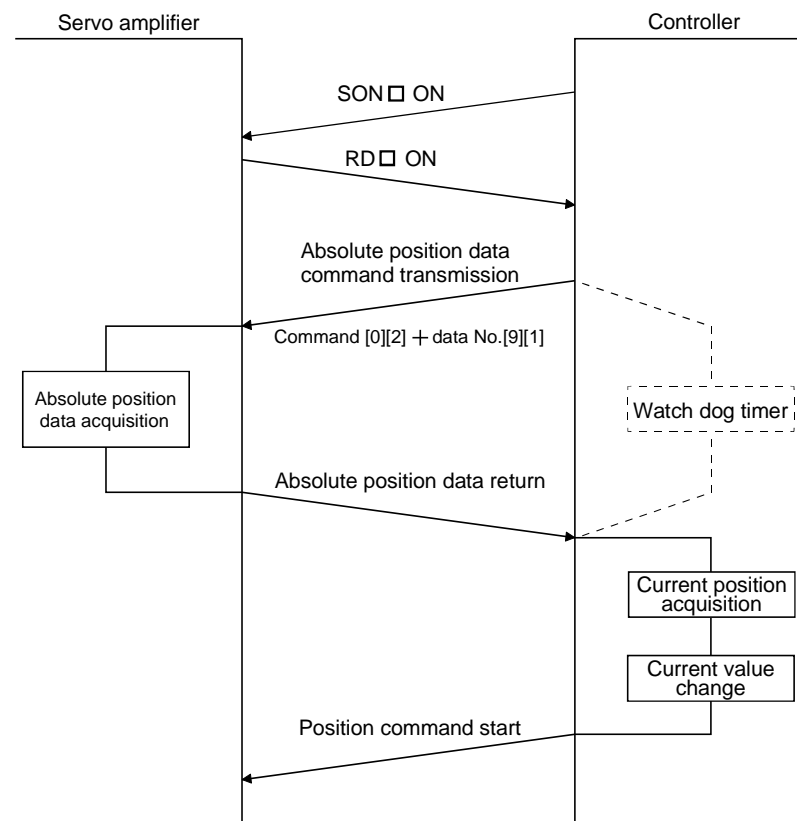


Data 32-bit length (hexadecimal representation)

14.10.2 Absolute position data transfer protocol

(1) Data transfer procedure

Every time the servo-on (SON) turns on at power-on or like, the controller must read the current position data in the servo amplifier. Not performing this operation will cause a position shift. Time-out monitoring is performed by the controller.

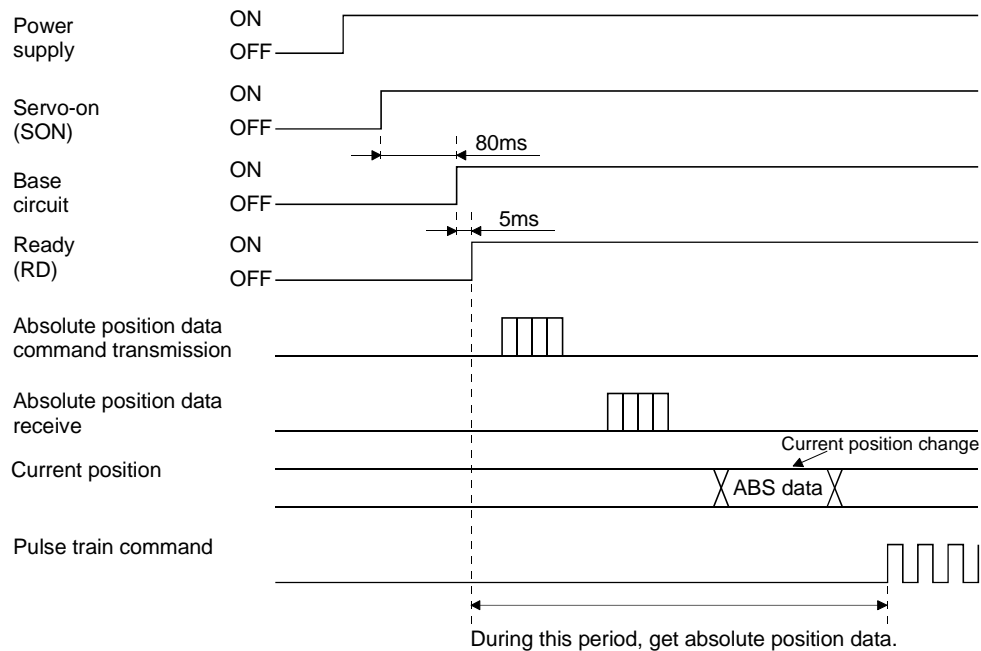


14. ABSOLUTE POSITION DETECTION SYSTEM

(2) Transfer method

The sequence in which the base circuit is turned ON (servo-on) when it is in the OFF state due to the servo-on (SON) going OFF, an emergency stop, or alarm, is explained below. In the absolute position detection system, always give the serial communication command to read the current position in the servo amplifier to the controller every time the ready (RD) turns on. The servo amplifier sends the current position to the controller on receipt of the command. At the same time, this data is set as a position command value in the servo amplifier.

(a) Sequence processing at power-on



- 1) 95ms after the servo-on (SON) has turned on, the base circuit turns on.
- 2) After the base circuit has turned on, the ready (RD) turns on.
- 3) After the ready (RD) turned on and the controller acquired the absolute position data, give command pulses to the drive unit. Providing command pulses before the acquisition of the absolute position data can cause a position shift.

(b) Communication error

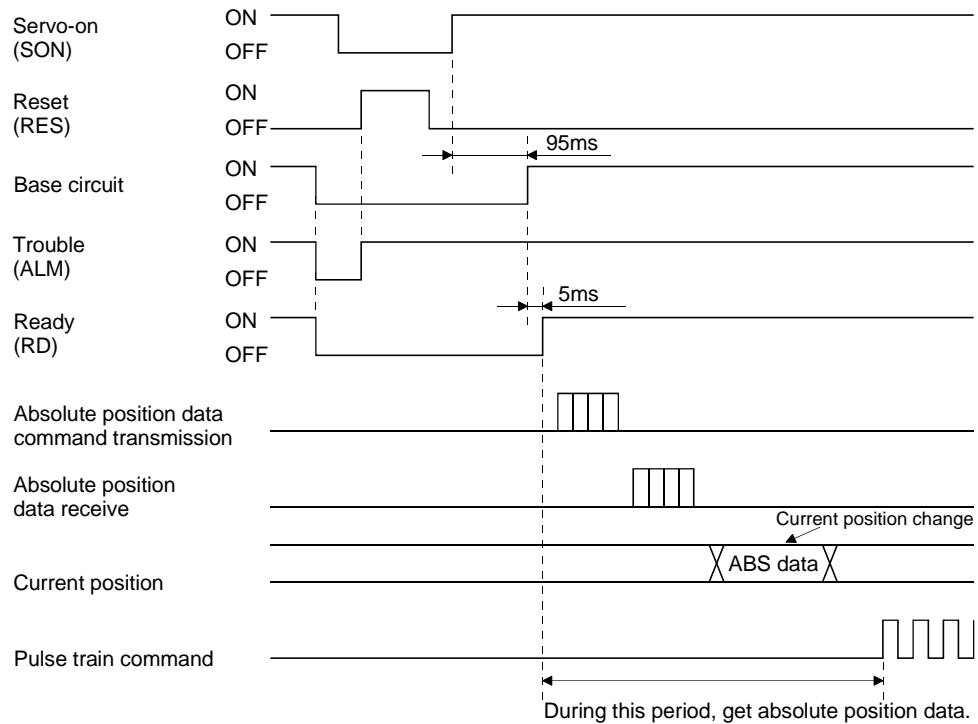
If a communication error occurs between the controller and servo amplifier, the servo amplifier sends the error code. The definition of the error code is the same as that of the communication function. Refer to Section 13.3.3 for details.

If a communication error has occurred, perform retry operation. If several retries do not result in a normal termination, perform error processing.

14. ABSOLUTE POSITION DETECTION SYSTEM

(c) At the time of alarm reset

If an alarm has occurred, detect the trouble (ALM) and turn off the servo-on (SON). After removing the alarm occurrence factor and deactivating the alarm, get the absolute position data again from the servo amplifier in accordance with the procedure in (a) of this section.

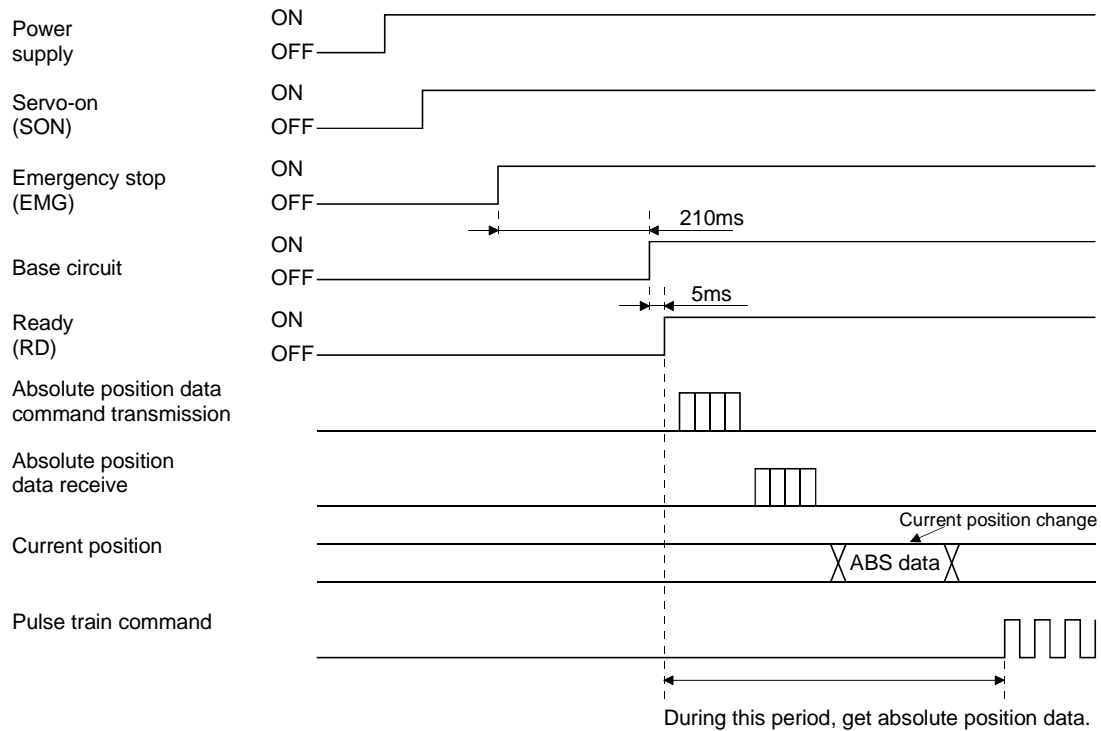


14. ABSOLUTE POSITION DETECTION SYSTEM

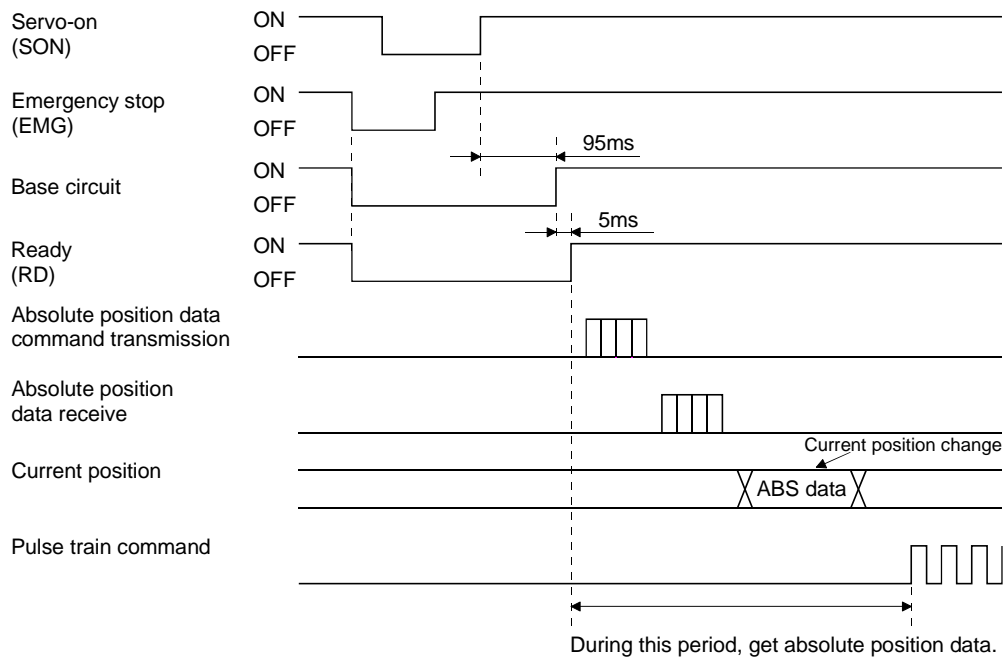
(d) At the time of forced stop reset

210ms after the forced stop is deactivated, the base circuit turns on, and further 5ms after that, the ready (RD) turns on. Always get the current position data from when the ready (RD) is triggered until before the position command is issued.

1) When power is switched on in a forced stop status



2) When a emergency stop is activated during servo on

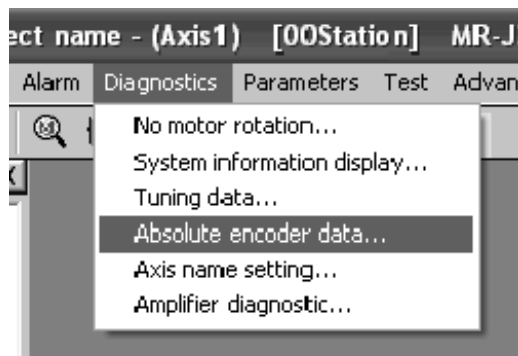


14. ABSOLUTE POSITION DETECTION SYSTEM

14.11 Confirmation of absolute position detection data

You can confirm the absolute position data with MR Configurator (servo configuration software).
Choose "Diagnostics" and "Absolute Encoder Data" to open the absolute position data display screen.

(1) Choosing "Diagnostics" in the menu opens the sub-menu as shown below:



(2) By choosing "Absolute Encoder Data" in the sub-menu, the absolute encoder data display window appears.

Absolute encoder data	
Absolute position data	Command pulse value
Value of each motor edge pulse	Command pulse value *
-156501673	-156501673
*Value of each command pulse = (CDV/CMX) X Value of each motor edge pulse	
Encoder data	<Current position>
Absolute encoder data(pulse)	Absolute encoder data
CYC(Motor edge pulse value)	CYC0(Motor edge pulse value)
6487	0
Number of motor rotations(rev)	Number of motor rotations
ABS	ABS0
-19105	0
*Convert to starting point by the following expressions.	
Value of each motor edge pulse = ABS X Encoder one revolution counts + (CYC-CYC0)	
Close	

(3) Press the "Close" button to close the absolute encoder data display window.

Appendix

App 1. Parameter list

POINT

- For any parameter whose symbol is preceded by *, set the parameter value and switch power off once, then switch it on again to make that parameter setting valid.

Basic setting parameters (PA □ □)			
No.	Symbol	Name	Control mode
PA01	*STY	Control mode	P · S · T
PA02	*REG	Regenerative brake option	P · S · T
PA03	*ABS	Absolute position detection system	P
PA04	*AOP1	Function selection A-1	P · S · T
PA05	*FBP	Number of command input pulses per revolution	P
PA06	CMX	Electronic gear numerator (Command pulse multiplying factor numerator)	P
PA07	CDV	Electronic gear denominator (Command pulse multiplying factor denominator)	P
PA08	ATU	Auto tuning	P · S
PA09	RSP	Auto tuning response	P · S
PA10	INP	Control mode, regenerative brake option selection	P
PA11	TLP	Forward torque limit	P · S · T
PA12	TLN	Reverse torque limit	P · S · T
PA13	*PLSS	Selection of servo motor stop pattern at LSP/LSN signal off	P
PA14	*POL	Rotation direction selection	P
PA15	*ENR	Encoder output pulses	P · S · T
PA16 to PA18		For manufacturer setting	
PA19	*BLK	Parameter block	P · S · T

Gain/filter parameters (PB □ □)			
No.	Symbol	Name	Control mode
PB01	FILT	Adaptive tuning mode (Adaptive filter II)	P · S
PB02	VRFT	Vibration suppression control filter tuning mode (Advanced vibration suppression control)	P
PB03	PST	Position command acceleration/ deceleration time constant (Position smoothing)	P
PB04	FFC	Feed forward gain	P
PB05		For manufacturer setting	
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	P · S
PB07	PG1	Model loop gain	P
PB08	PG2	Position loop gain	P
PB09	VG2	Speed loop gain	P · S
PB10	VIC	Speed integral compensation	P · S
PB11	VDC	Speed differential compensation	P · S
PB12		For manufacturer setting	
PB13	NH1	Machine resonance suppression filter 1	P · S
PB14	NHQ1	Notch form selection 1	P
PB15	NH2	Machine resonance suppression filter 2	P
PB16	NHQ2	Notch form selection 2	P
PB17		For manufacturer setting	
PB18	LPF	Low-pass filter	P
PB19	VRF1	Vibration suppression control vibration frequency setting	P
PB20	VRF2	Vibration suppression control resonance frequency setting	P
PB21		For manufacturer setting	
PB22		For manufacturer setting	
PB23	VFBF	Low-pass filter selection	P
PB24	*MVS	Slight vibration suppression control selection	P · S
PB25	*BOP1	Function selection B-1	P
PB26	*CDP	Gain changing selection	P · S
PB27	CDL	Gain changing condition	P · S
PB28	CDT	Gain changing time constant	P · S
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	P · S
PB30	PG2B	Gain changing position loop gain	P
PB31	VG2B	Gain changing speed loop gain	P · S
PB32	VICB	Gain changing speed integral compensation	P · S
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	P
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	P
PB35 to PB45		For manufacturer setting	

Extension setting parameters (PC□□)			
No.	Symbol	Name	Control mode
PC01	STA	Acceleration time constant	S · T
PC02	STB	Deceleration time constant	S · T
PC03	STC	S-pattern acceleration/ deceleration time constant	S · T
PC04	TQC	Torque command time constant	T
PC05	SC1	Internal speed command 1	S
		Internal speed limit 1	T
PC06	SC2	Internal speed command 2	S
		Internal speed limit 2	T
PC07	SC3	Internal speed command 3	S
		Internal speed limit 3	T
PC08	SC4	Internal speed command 4	S
		Internal speed limit 4	T
PC09	SC5	Internal speed command 5	S
		Internal speed limit 5	T
PC10	SC6	Internal speed command 6	S
		Internal speed limit 6	T
PC11	SC7	Internal speed command 7	S
		Internal speed limit 7	T
PC12	VCM	Analog speed command maximum speed	S
		Analog speed limit maximum speed	T
PC13	TLC	Analog torque command maximum output	T
PC14	MOD1	Analog monitor output 1	P · S · T
PC15	MOD2	Analog monitor output 2	P · S · T
PC16	MBR	Electromagnetic brake sequence output	P · S · T
PC17	ZSP	Zero speed	P · S · T
PC18	*BPS	Alarm history clear	P · S · T
PC19	*ENRS	Encoder output pulses selection	P · S · T
PC20	*SNO	Parameter block	P · S · T
PC21	*SOP	communication function selection	P · S · T
PC22	*COP1	Function selection C-1	S
PC23	*COP2	Function selection C-2	P · S · T
PC24	*COP3	Function selection C-3	P · S · T
PC25	/	For manufacturer setting	/
PC26		*COP5 Function selection C-4	P · S
PC27 to PC29		For manufacturer setting	/
PC30	STA2	Acceleration time constant 2	S · T
PC31	STB2	Deceleration time constant 2	S · T
PC32	CMX2	Command pulse multiplying factor numerator 2	P
PC33	CMX3	Command pulse multiplying factor numerator 3	P
PC34	CMX4	Command pulse multiplying factor numerator 4	P
PC35	TL2	For manufacturer setting	P · S · T
PC36	*DMD	Status display selection	P · S · T
PC37	VCO	Analog speed command offset	S
		Analog speed limit offset	T
PC38	TPO	Analog torque command offset	T
		Analog torque limit offset	S

Extension setting parameters (PC□□)			
No.	Symbol	Name	Control mode
PC39	MO1	Analog monitor 1 offset	P · S · T
PC40	MO2	Analog monitor 2 offset	P · S · T
PC41 to PC50	/	For manufacturer setting	/

I/O setting parameters (PD□□)			
No.	Symbol	Name	Control mode
PD01	*DIA1	Input signal automatic ON selection 1	P · S · T
PD02	/	For manufacturer setting	/
PD03		*DI1 Input signal device selection 1 (CN1-pin 15)	P · S · T
PD04	*DI2	Input signal device selection 2 (CN1-pin 16)	P · S · T
PD05	*DI3	Input signal device selection 3 (CN1-pin 17)	P · S · T
PD06	*DI4	Input signal device selection 4 (CN1-pin 18)	P · S · T
PD07	*DI5	Input signal device selection 5 (CN1-pin 19)	P · S · T
PD08	*DI6	Input signal device selection 6 (CN1-pin 41)	P · S · T
PD09	/	For manufacturer setting	/
PD10		*DI8 Input signal device selection 8 (CN1-pin 43)	P · S · T
PD11	*DI9	Input signal device selection 9 (CN1-pin 44)	P · S · T
PD12	*DI10	Input signal device selection 10 (CN1-pin 45)	P · S · T
PD13	*DO1	Output signal device selection 1 (CN1-pin 22)	P · S · T
PD14	*DO2	Output signal device selection 2 (CN1-pin 23)	P · S · T
PD15	*DO3	Output signal device selection 3 (CN1-pin 24)	P · S · T
PD16	*DO4	Output signal device selection 4 (CN1-pin 25)	P · S · T
PD17	/	For manufacturer setting	/
PD18		*DO6 Output signal device selection 6 (CN1-pin 49)	P · S · T
PD19	*DIF	Response level setting	P · S · T
PD20	*DOP1	Function selection D-1	P · S · T
PD21	/	For manufacturer setting	/
PD22		*DOP3 Function selection D-2	P
PD23	/	For manufacturer setting	/
PD24		*DOP5 Function selection D-4	P · S · T
PD25 to PD30	/	For manufacturer setting	/

App 2. Signal Layout Recording Paper

Position control mode

CN1

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26
P15R	TLA	LG	LA	LAR	LB	LBR	LZ	OP	LZR	NP	PG	OPC								DICOM	DICOM	DICOM	ALM		
3	28	29	LG	30	31	32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47	48	49	50	

Speed control mode

CN1

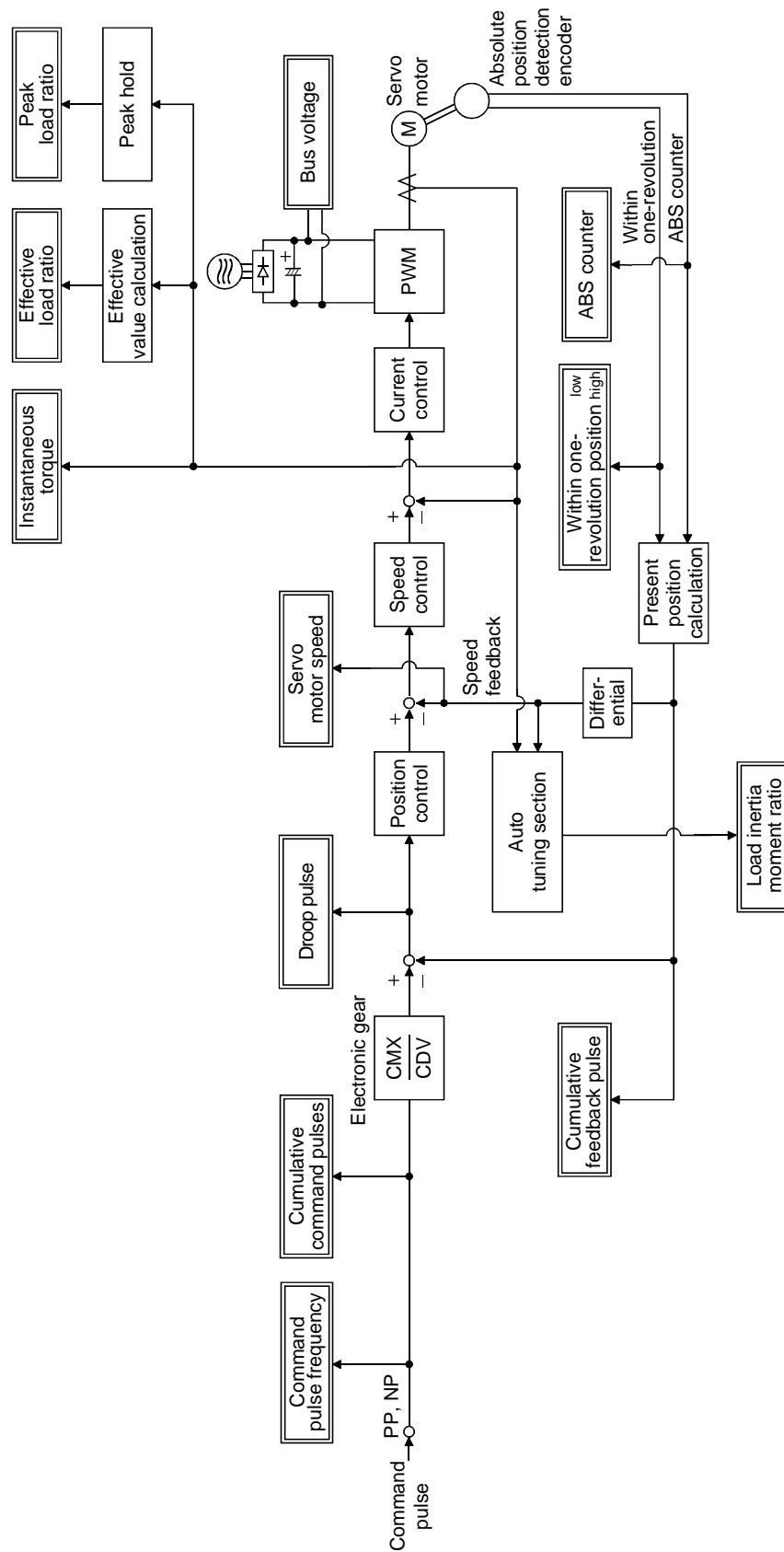
1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26
P15R	VC	TLA	LG	LA	LAR	LB	LBR	OP	LZR											DICOM	DICOM	DICOM	ALM		
3	28	29	LG	30	31	32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47	48	49	50	

Torque control mode

CN1

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26
P15R	VLA	LG	LA	LAR	LB	LBR	LZ	OP	LZR											DICOM	DICOM	DICOM	ALM		
3	28	29	LG	30	31	32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47	48	49	50	

App 3. Status display block diagram



App 4. Combination of servo amplifier and servo motor

The servo amplifier software versions compatible with the servo motors are indicated in the parentheses.
The servo amplifiers whose software versions are not indicated can be used regardless of the versions.

Servo motor	Servo amplifier (Software version)
HF-KP053	MR-J3-10A MR-J3-10A1
HF-KP13	MR-J3-10A MR-J3-10A1
HF-KP23	MR-J3-20A MR-J3-20A1
HF-KP43	MR-J3-40A MR-J3-40A1
HF-KP73	MR-J3-70A
HF-SP52	MR-J3-60A (Version A1 or later)
HF-SP102	MR-J3-100A (Version A1 or later)
HF-SP152	MR-J3-200A (Version A2 or later)
HF-SP202	MR-J3-200A (Version A2 or later)
HF-SP352	MR-J3-350A (Version A2 or later)

[illegible]

REVISIONS

*The manual number is given on the bottom left of the back cover.

Print Data	*Manual Number	Revision
Oct., 2003	SH(NA)030038-A	First edition
May, 2004	SH(NA)030038-B	<p>Safety Instructions: 4. (1) HF-SP Series servomotor is added to the environment conditions.</p> <p>Compliance with EC directives in EU: 2.(1) Servo amplifiers MR-J3-60A/100A/200A/350A are added. HF-SP Series servomotor is added.</p> <p>Compliance with UL/C-UL standard: (1) Servo amplifiers MR-J3-60A/100A/200A/350A are added. HF-SP Series servomotor is added. (4) Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 1.3: Servo amplifiers MR-J3-60A/100A/200A/350A are added. Note 2. The torque limit is changed to the effective load ratio.</p> <p>Section 1.4: The amplifier diagnosis function is added.</p> <p>Section 1.5 (2): Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 1.6: Servo amplifiers MR-J3-60A/100A/200A/350A are added. HF-SP Series servomotor is added.</p> <p>Section 1.7 (2): Added.</p> <p>Section 1.8 (2): Added.</p> <p>Section 2.1 (2): Part of the paragraph is changed.</p> <p>Section 3.2.2: Analog torque limit $\pm 10V$ is changed to 8V.</p> <p>Section 3.3.1: Paragraph is added. Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 3.3.3 (2) (4) : Added.</p> <p>Section 3.4 (1): Error in the CN2 connector signal allotment is corrected.</p> <p>Section 3.5 (1) (b): Description of speed reached is examined. Alarm code AL. 47 is added.</p> <p>Section 3.5 (5): Caution is added.</p> <p>Section 3.6.2 (1) (a): Note is added.</p> <p>Section 3.8.2 (3) (a) 2): 0.7μs is changed to 0.35μs.</p> <p>Section 3.10.2 (1): HF-KP Series is added.</p> <p>Section 3.10.2 (2): HF-SP Series is added.</p> <p>Section 3.11.4: "POINT" is added.</p> <p>Section 5.1.4: Parameter No. PA02 MR-RB30 and MR-RB50 is added.</p> <p>Section 5.1.8 (3): The per-revolution pulse count of the servomotor viewed from QD75 is examined.</p> <p>Section 5.2.2: PB01 Paragraph is added. PB02 Paragraph is added. PB23 Paragraph is examined.</p> <p>Section 5.3.1: PC22 Control mode is examined. PC13 Setting is changed to "1000.0." PC23 Part of the paragraph is examined. PC24 The in-position range unit selection setting is changed to the fourth digit.</p> <p>Section 5.4.1: PD08 Initial value is changed to 00202006h.</p>

Print Data	*Manual Number	Revision
May, 2004	SH(NA)030038-B	<p>Section 5.4.2: List of details is added. PD24 AL. 47 is added.</p> <p>Section 6.4: Amplifier diagnosis is added.</p> <p>Section 6.7 (3) (a) (b): SP2 (CN1-16) is added.</p> <p>Section 8.2 (3): Paragraph is added. Part of the paragraph in "POINT" is examined.</p> <p>Section 9.1: AL. 47 is added. AL. E8 is added.</p> <p>Section 9.2: Description of AL. 52 is changed.</p> <p>Section 9.3: Paragraph is added. AL. E8 is added.</p> <p>Section 10: Outline drawing is examined.</p> <p>Section 10.1 (4): Added.</p> <p>Section 11.1: c. HF-SP152 to 352 is added.</p> <p>Section 11.2 (1): Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 11.3: HF-SP Series is added.</p> <p>Section 11.5: Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.1.1: The cable and connector set drawing is added and changed.</p> <p>Section 12.1.2 (1) (a): The CN2 connector signal allotment drawing is changed.</p> <p>Section 12.1.2 (4) (5): Added.</p> <p>Section 12.2 (1) (b): Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.2 (1) (c): MR-RB30 and MR-RB50 are added.</p> <p>Section 12.2 (5): MR-RB30 and MR-ORB50 are added.</p> <p>Section 12.4 (2): The free space of the hard disk is changed to 30MB.</p> <p>Section 12.4 (2) (c): Added.</p> <p>Section 12.6 (1): Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.6 (2): Cable is added.</p> <p>Section 12.7: Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.8: Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.9: Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.12 (2) (d): FR-BLF is added.</p> <p>Section 12.13 (1): Servo amplifiers MR-J3-60A/100A/200A/350A are added.</p> <p>Section 12.14: HF-3030-UN is added.</p> <p>Section 14.8.3: Added.</p> <p>App 4.: Added.</p>

MODEL	
MODEL CODE	



MITSUBISHI ELECTRIC CORPORATION

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