

Lexium 26D and BCH2 Servo Drive System

User Guide

(Original Document)

04/2017



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All pertinent state, regional, and local safety regulations must be observed when installing and using this product. For reasons of safety and to help ensure compliance with documented system data, only the manufacturer should perform repairs to components.

When devices are used for applications with technical safety requirements, the relevant instructions must be followed.

Failure to use Schneider Electric software or approved software with our hardware products may result in injury, harm, or improper operating results.

Failure to observe this information can result in injury or equipment damage.

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Important Information

NOTICE

Read these instructions carefully, and look at the equipment to become familiar with the device before trying to install, operate, service, or maintain it. The following special messages may appear throughout this documentation or on the equipment to warn of potential hazards or to call attention to information that clarifies or simplifies a procedure.



The addition of this symbol to a “Danger” or “Warning” safety label indicates that an electrical hazard exists which will result in personal injury if the instructions are not followed.



This is the safety alert symbol. It is used to alert you to potential personal injury hazards. Obey all safety messages that follow this symbol to avoid possible injury or death.

DANGER

DANGER indicates a hazardous situation which, if not avoided, **will result in** death or serious injury.

WARNING

WARNING indicates a hazardous situation which, if not avoided, **could result in** death or serious injury.

CAUTION

CAUTION indicates a hazardous situation which, if not avoided, **could result in** minor or moderate injury.

NOTICE

NOTICE is used to address practices not related to physical injury.

PLEASE NOTE

Electrical equipment should be installed, operated, serviced, and maintained only by qualified personnel. No responsibility is assumed by Schneider Electric for any consequences arising out of the use of this material.

A qualified person is one who has skills and knowledge related to the construction and operation of electrical equipment and its installation, and has received safety training to recognize and avoid the hazards involved.

QUALIFICATION OF PERSONNEL

Only appropriately trained persons who are familiar with and understand the contents of this manual and all other pertinent product documentation are authorized to work on and with this product. These persons must have sufficient technical training, knowledge and experience and be able to foresee and detect potential hazards that may be caused by using the product, by modifying the settings and by the mechanical, electrical and electronic equipment of the entire system in which the product is used.

All persons working on and with the product must be fully familiar with all applicable standards, directives, and accident prevention regulations when performing such work.

INTENDED USE

The products described or affected by this document are, along with software, accessories and options, servo drive systems for servo motors and intended for industrial use according to the instructions, directions, examples and safety information contained in the present document and other supporting documentation.

The products may only be used in compliance with all applicable safety regulations and directives, the specified requirements and the technical data.

Prior to using the products, you must perform a risk assessment in view of the planned application. Based on the results, the appropriate safety-related measures must be implemented.

Since the products are used as components in an entire system, you must ensure the safety of persons by means of the design of this entire system.

Operate the products only with the specified cables and accessories. Use only genuine accessories and spare parts.

Any use other than the use explicitly permitted is prohibited and can result in hazards.



At a Glance

Document Scope

This document describes the functions of the Servo Drive LXM26D and the BCH2 motor.

Validity Note

This document has been updated with the firmware release of the Lexium 26D V1.50.

The technical characteristics of the devices described in this document also appear online. To access this information online:

Step	Action
1	Go to the Schneider Electric home page www.schneider-electric.com .
2	In the Search box type the reference of a product or the name of a product range. • Do not include blank spaces in the reference or product range. • To get information on grouping similar modules, use asterisks (*).
3	If you entered a reference, go to the Product Datasheets search results and click on the reference that interests you. If you entered the name of a product range, go to the Product Ranges search results and click on the product range that interests you.
4	If more than one reference appears in the Products search results, click on the reference that interests you.
5	Depending on the size of your screen, you may need to scroll down to see the data sheet.
6	To save or print a data sheet as a .pdf file, click Download XXX product datasheet .

The characteristics that are presented in this manual should be the same as those characteristics that appear online. In line with our policy of constant improvement, we may revise content over time to improve clarity and accuracy. If you see a difference between the manual and online information, use the online information as your reference.

For product compliance and environmental information (RoHS, REACH, PEP, EOLI, etc.), go to www.schneider-electric.com/green-premium.

Related Documents

Title of documentation	Reference number
Lexium 26D and BCH2 Servo Drive System - User Guide (This document)	EIO0000002299 (ENG)
Lexium 26D DTM Commissioning software - User Guide	EIO0000002311 (ENG)
HBC Holding Brake Controller -Product Manual	0198441113316 (ENG)

You can download these technical publications and other technical information from our website at <http://www.schneider-electric.com/en/download>.

Product Related Information

The use and application of the information contained herein require expertise in the design and programming of automated control systems.

Only you, the user, machine builder or integrator, can be aware of all the conditions and factors present during installation and setup, operation, repair and maintenance of the machine or process.

You must also consider any applicable standards and/or regulations with respect to grounding of all equipment. Verify compliance with any safety information, different electrical requirements, and normative standards that apply to your machine or process in the use of this equipment.

Many components of the equipment, including the printed circuit board, operate with mains voltage, or present transformed high currents, and/or high voltages.

The motor itself generates voltage when the motor shaft is rotated.

DANGER

ELECTRIC SHOCK, EXPLOSION, OR ARC FLASH

- Disconnect all power from all equipment including connected devices prior to removing any covers or doors, or installing or removing any accessories, hardware, cables, or wires.
- Place a "Do Not Turn On" or equivalent hazard label on all power switches and lock them in the non-energized position.
- Wait 15 minutes to allow the residual energy of the DC bus capacitors to discharge.
- Do not assume that the DC bus is voltage-free when the DC bus LED is off.
- Block the motor shaft to prevent rotation prior to performing any type of work on the drive system.
- Do not create a short-circuit across the DC bus terminals or the DC bus capacitors.
- Replace and secure all covers, accessories, hardware, cables, and wires and confirm that a proper ground connection exists before applying power to the unit.
- Use only the specified voltage when operating this equipment and any associated products.

Failure to follow these instructions will result in death or serious injury.

This equipment has been designed to operate outside of any hazardous location. Only install this equipment in zones known to be free of a hazardous atmosphere.

DANGER

POTENTIAL FOR EXPLOSION

Install and use this equipment in non-hazardous locations only.

Failure to follow these instructions will result in death or serious injury.

If the power stage is disabled unintentionally, for example as a result of power outage, errors or functions, the motor is no longer decelerated in a controlled way. Overload, errors or incorrect use may cause the holding brake to no longer operate properly and may result in premature wear.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Verify that movements without braking effect cannot cause injuries or equipment damage.
- Verify the function of the holding brake at regular intervals.
- Do not use the holding brake as a service brake.
- Do not use the holding brake for safety-related purposes.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Drive systems may perform unanticipated movements because of incorrect wiring, incorrect settings, incorrect data or other errors.

WARNING

UNINTENDED MOVEMENT OR MACHINE OPERATION

- Carefully install the wiring in accordance with the EMC requirements.
- Do not operate the product with undetermined settings and data.
- Perform comprehensive commissioning tests that include verification of configuration settings and data that determine position and movement.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

WARNING

LOSS OF CONTROL

- The designer of any control scheme must consider the potential failure modes of control paths and, for certain critical control functions, provide a means to achieve a safe state during and after a path failure. Examples of critical control functions are emergency stop and overtravel stop, power outage and restart.
- Separate or redundant control paths must be provided for critical control functions.
- System control paths may include communication links. Consideration must be given to the implications of unanticipated transmission delays or failures of the link.
- Observe all accident prevention regulations and local safety guidelines.¹
- Each implementation of this equipment must be individually and thoroughly tested for proper operation before being placed into service.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

¹ For additional information, refer to NEMA ICS 1.1 (latest edition), "Safety Guidelines for the Application, Installation, and Maintenance of Solid State Control" and to NEMA ICS 7.1 (latest edition), "Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable-Speed Drive Systems" or their equivalent governing your particular location.

Terminology Derived from Standards

The technical terms, terminology, symbols and the corresponding descriptions in this manual, or that appear in or on the products themselves, are generally derived from the terms or definitions of international standards.

In the area of functional safety systems, drives and general automation, this may include, but is not limited to, terms such as *safety*, *safety function*, *safe state*, *fault*, *fault reset*, *malfunction*, *failure*, *error*, *error message*, *dangerous*, etc.

Among others, these standards include:

Standard	Description
EN 61131-2:2007	Programmable controllers, part 2: Equipment requirements and tests.
ISO 13849-1:2008	Safety of machinery: Safety related parts of control systems. General principles for design.
EN 61496-1:2013	Safety of machinery: Electro-sensitive protective equipment. Part 1: General requirements and tests.
ISO 12100:2010	Safety of machinery - General principles for design - Risk assessment and risk reduction
EN 60204-1:2006	Safety of machinery - Electrical equipment of machines - Part 1: General requirements
EN 1088:2008 ISO 14119:2013	Safety of machinery - Interlocking devices associated with guards - Principles for design and selection
ISO 13850:2006	Safety of machinery - Emergency stop - Principles for design
EN/IEC 62061:2005	Safety of machinery - Functional safety of safety-related electrical, electronic, and electronic programmable control systems
IEC 61508-1:2010	Functional safety of electrical/electronic/programmable electronic safety-related systems: General requirements.
IEC 61508-2:2010	Functional safety of electrical/electronic/programmable electronic safety-related systems: Requirements for electrical/electronic/programmable electronic safety-related systems.
IEC 61508-3:2010	Functional safety of electrical/electronic/programmable electronic safety-related systems: Software requirements.
IEC 61784-3:2008	Digital data communication for measurement and control: Functional safety field buses.
2006/42/EC	Machinery Directive
2014/30/EU	Electromagnetic Compatibility Directive
2014/35/EU	Low Voltage Directive

In addition, terms used in the present document may tangentially be used as they are derived from other standards such as:

Standard	Description
IEC 60034 series	Rotating electrical machines
IEC 61800 series	Adjustable speed electrical power drive systems
IEC 61158 series	Digital data communications for measurement and control – Fieldbus for use in industrial control systems

Finally, the term *zone of operation* may be used in conjunction with the description of specific hazards, and is defined as it is for a *hazard zone* or *danger zone* in the *Machinery Directive (2006/42/EC)* and *ISO 12100:2010*.

NOTE: The aforementioned standards may or may not apply to the specific products cited in the present documentation. For more information concerning the individual standards applicable to the products described herein, see the characteristics tables for those product references.

Part I

Servo Drive System Planning

What Is in This Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
1	General Overview	15
2	Document Navigator	19

Chapter 1

General Overview

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Servo Drive Device Overview	16
Drive / Motor References	17

Servo Drive Device Overview

Presentation

The servo drive system includes:

- the drive ([see page 27](#)) and the motor ([see page 45](#)).



- the accessories and spare parts ([see page 83](#)).



Item	Description
1	Commissioning tools (see page 84)
2	Connectors and adapters (see page 84)
3	External mains filters (see page 84)
4	Not used
5	Application nameplate (see page 85)
6	Not used
7	Motor cables (see page 86)
8	Encoder cables (see page 87)
9	Signal cables (see page 88)
10	Not used
11	External braking resistors (see page 89)
12	Circuit breakers (see page 90)
13	Motor protection switches and power contractors (see page 91)

Drive / Motor References

Introduction

The present user guide provides information about the following Drives and Motors reference tables.

The Lexium 26D range is defined by AC-servo drives Lexium 26D for combination with AC-servo motors BCH2.

- The combinations of servo motors with servo drives are based on the power class: both servo motor and servo drive must have the same power class.
- The bundle of a servo drive with its related servo motor is designed to cover a nominal power from 0.05 kW up to 4.5 kW (0.067 up to 6.03 hp) with 200...240 V mains supply voltage.

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table (*see page 18*).

Lexium 26D Drive References List

Drive references	Nominal power	Supply mains
LXM26DUA5M3X	50 W	single phase or 3-phase, 230 Vac
LXM26DU01M3X	100 W	single phase or 3-phase, 230 Vac
LXM26DU02M3X	200 W	single phase or 3-phase, 230 Vac
LXM26DU04M3X	400 W	single phase or 3-phase, 230 Vac
LXM26DU07M3X	750 W	single phase or 3-phase, 230 Vac
LXM26DU10M3X	1000 W	single phase or 3-phase, 230 Vac
LXM26DU15M3X	1500 W	3-phase, 230 Vac
LXM26DU20M3X	2000 W	3-phase, 230 Vac
LXM26DU30M3X	3000 W	3-phase, 230 Vac
LXM26DU45M3X	4500 W	3-phase, 230 Vac

For further information, refer to the servo drive general overview (*see page 28*).

BCH2 Motor References List

Motor references	Nominal power
BCH2MBA53•C•5C	50 W
BCH2MB013•C•5C	100 W
BCH2LD023•C•5C	200 W
BCH2MM031•C•6C	300 W
BCH2LD043•C•5C	400 W
BCH2LF043•C•5C	400 W
BCH2MM052•C•6C	500 W
BCH2MM061•C•6C	600 W
BCH2HF073•C•5C	750 W
BCH2LF073•C•5C	750 W
BCH2MM081•C•6C	850 W
BCH2MM091•C•6C	900 W
BCH2MM102•C•6C	1000 W
BCH2HM102•C•6C	1000 W
BCH2LH103•C•6C	1000 W
BCH2MM152•C•6C	1500 W
BCH2MM202•C•6C	2000 W
BCH2MR202•C•6C	2000 W
BCH2HR202•C•6C	2000 W
BCH2LH203•C•6C	2000 W
BCH2MR301•C•6C	3000 W

Motor references	Nominal power
BCH2MR302•C•6C	3000 W
BCH2MR352•C•6C	3500 W
BCH2MR451•C•6C	4500 W

For further information, refer to Servo Motor Type Code (*see page 49*).

Drive / Motor Combinations

The permissible Drive / Motor Combinations are detailed in the following table:

Drive	Motor	Nominal power	Nominal speed of rotation	Nominal torque	Peak torque	Rotor inertia without holding brake	Moment of inertia
		W	rpm	Nm	Nm	kg.cm ²	-
Devices 220 Vac that can be connected via a single phase or three phases							
LXM26DUA5M3X	BCH2MBA53•••5C	50	3000	0.16	0.48	0.054	Medium
LXM26DU01M3X	BCH2MB013•••5C	100	3000	0.32	0.96	0.075	Medium
LXM26DU02M3X	BCH2LD023•••5C	200	3000	0.64	1.92	0.16	Low
LXM26DU04M3X	BCH2MM031•••6C	300	1000	2.86	8.59	6.63	Medium
	BCH2LD043•••5C	400	3000	1.27	3.81	0.27	Low
	BCH2LF043•••5C	400	3000	1.27	3.81	0.67	Low
LXM26DU07M3X	BCH2MM052•••6C	500	2000	2.39	7.16	6.63	Medium
	BCH2MM061•••6C	600	1000	5.73	17.19	6.63	Medium
	BCH2LF073•••5C	750	3000	2.39	7.16	1.19	Low
	BCH2HF073•••5C	750	3000	2.39	7.16	1.54	High
LXM26DU10M3X	BCH2MM081•••6C	850	1500	5.39	13.8	13.5	Medium
	BCH2MM091•••6C	900	1000	8.59	25.77	9.7	Medium
	BCH2LH103•••6C	1000	3000	3.18	9.54	2.4	Low
	BCH2MM102•••6C	1000	2000	4.77	14.3	6.63	Medium
	BCH2HM102•••6C	1000	2000	4.77	14.3	8.41	High
LXM26DU15M3X	BCH2MM152•••6C	1500	2000	7.16	21.48	9.7	Medium
Devices 220 Vac that can be connected via three phases							
LXM26DU20M3X	BCH2LH203•••6C	2000	3000	6.37	19.11	4.28	Low
	BCH2MM202•••6C	2000	2000	9.55	28.65	13.5	Medium
	BCH2MR202•••6C	2000	2000	9.55	28.65	26.5	Medium
	BCH2HR202•••6C	2000	2000	9.55	28.65	34.68	High
LXM26DU30M3X	BCH2MR301•••6C	3000	1500	19.1	57.29	53.56	Medium
	BCH2MR302•••6C	3000	2000	14.32	42.97	53.56	Medium
LXM26DU45M3X	BCH2MR352•••6C	3500	2000	16.7	50.3	53.56	Medium
	BCH2MR451•••6C	4500	1500	28.65	71.62	73.32	Medium

Chapter 2

Document Navigator

Document Navigator

Document Content

This user guide contains following data:

- Technical data (*see page 21*)
 - Conditions for UL 508C and CSA (*see page 23*)
 - Drive (*see page 27*)
 - Motor (*see page 45*)
 - Accessories and spare parts (*see page 83*)
- Engineering (*see page 93*)
- Installation (*see page 113*)
 - Before mounting (*see page 115*)
 - Drive installation (*see page 119*)
 - Motor installation (*see page 149*)
 - Verifying installation (*see page 159*)
- Commissioning (*see page 161*)
 - Overview (*see page 163*)
 - Integrated HMI (*see page 167*)
 - Commissioning procedure (*see page 175*)
 - Tuning the control loop (*see page 183*)
- Parameters (*see page 203*)
- Operation (*see page 265*)
 - Operation (*see page 267*)
 - Operating modes (*see page 285*)
- Diagnostics and troubleshooting (*see page 339*)
- Service, maintenance and disposal (*see page 349*)

Part II

Servo Drive System Technical Data

What Is in This Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
3	Certifications	23
4	Drive	27
5	Motor	45
6	Accessories and Spare Parts	83

Chapter 3

Certifications

Download links

Item	Link
UL certification status	<u>UL InfoBY01</u>
CSA certificate	<u>CSA 70022260</u>
EU Declaration of conformity	<u>NHA3487100</u>
TÜV certificate	<u>TUEV 0120554010014</u>
KC certificate Size 1	<u>KC 1333-B797-B43E-FC6C</u>
KC certificate Size 2	<u>KC 8812-6AC0-ECBC-1757</u>
KC certificate Size 3	<u>KC AE96-6B40-C214-7A18</u>
KC certificate Size 4	<u>KC A1BB-480B-E156-0EF1</u>

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Conditions for UL 508C	24
Conditions for CSA	25

Conditions for UL 508C

Introduction

The UL certification status can be downloaded on the [Schneider Electric](#) website.

If the product is used to comply with UL 508C, the following conditions must also be met.

Wiring

Use at least 75 °C (167 °F) copper conductors.

Fuses

Use fuses as per UL 248 or circuit breaker as per UL 489.

LXM26D	UA5, U01, U02, U04, U07, U10, U15	U20, U30, U45
Maximum fuse rating of fuse to be connected upstream	25 A	32 A
Class if fuses are used	J	J
Class if circuit breakers are used	D	D

Overvoltage Category

Use only in overvoltage category III or where the maximum available Rated Impulse Withstand Voltage Peak is equal or less than 4000 Volts, or equivalent as defined in UL 840 and its equivalent defined in IEC 60664-1.

Conditions for CSA

The CSA certificate can be downloaded on the [Schneider Electric](#) website.

If the product is used to comply with CSA, the following conditions must also be met.

Integral solid-state short circuit protection in these drives does not provide branch circuit protection.

DANGER

ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

Provide branch circuit protection in accordance with the manual instructions, National Electrical Code and any additional local codes of the type and size specified in the present document.

Failure to follow these instructions will result in death or serious injury.

For reference groups 1, 2, 3 and 4 (see following table), this product is suitable for use on a circuit capable of delivering not more than 200 kA RMS symmetrical amperes and 230 Vac maximum, when protected by Listed Class J, CC or RK5 fuses as indicated in this instruction manual and the Fuse Type table. Instead of fuses, protection may be provided by circuit breakers of type C60 by Schneider Electric with the maximum current ratings specified in the following table.

For reference group 1 only, this product is suitable for motor group installation on a circuit capable of delivering not more than 5 kA RMS symmetrical amperes and 230 Vac maximum, when protected by Listed Class J or CC fuses as indicated in the instruction manual and the following table. Instead of fuses, protection may be provided by circuit breakers of type C60 by Schneider Electric with the maximum current ratings specified in the following table.

The opening of the branch-circuit protective device may be an indication that an electrical interruption has been detected.

DANGER

ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

- Examine all current carrying parts and other components of the drive controller for damage and replace if necessary before replacing fuses or engaging circuit breakers.
- Completely replace overload relays if burnout of the current element occurs.

Failure to follow these instructions will result in death or serious injury.

Capacitive voltages above 40 V may remain for up to 15 minutes after power is removed from the drive.

DANGER

ELECTRIC SHOCK, EXPLOSION, OR ARC FLASH

- Disconnect all power from all equipment including connected devices prior to removing any covers or doors, or installing or removing any accessories, hardware, cables, or wires.
- Place a "Do Not Turn On" or equivalent hazard label on all power switches and lock them in the non-energized position.
- Wait 15 minutes to allow the residual energy of the DC bus capacitors to discharge.
- Do not assume that the DC bus is voltage-free when the DC bus LED is off.
- Block the motor shaft to prevent rotation prior to performing any type of work on the drive system.
- Do not create a short-circuit across the DC bus terminals or the DC bus capacitors.
- Replace and secure all covers, accessories, hardware, cables, and wires and confirm that a proper ground connection exists before applying power to the unit.
- Use only the specified voltage when operating this equipment and any associated products.

Failure to follow these instructions will result in death or serious injury.

These drives are provided with load and speed adjustable motor overload and short circuit protection. Adjust the parameter P1-78 'User-Defined maximal current' in the drive which protects the motor by limiting the maximum current according to the required degree of protection of the motors as indicated on the name plate.

Other Characteristics

Maximum surrounding Air Temperature: 40 ... 55 °C (104 ... 131 °F) with current derating of 1% per °C (per 1.8 °F).

Tightening torque for the connectors labelled ~ **220 V**, **Resistor** and **Motor** for drive reference group 3 and 4(see following table): 0.7 ... 0.8 Nm (6.2 ... 7 lb.in)

Fuse Types

Reference Group	Reference	Class	Maximum Current
1	LXM26DUA5M3X	CC or J	25 A
	LXM26DU01M3X	CC or J	25 A
	LXM26DU02M3X	CC or J	25 A
	LXM26DU04M3X	CC or J	25 A
	LXM26DU07M3X	CC or J	25 A
2	LXM26DU10M3X	RK5 or CC or J	25 A
	LXM26DU15M3X	RK5 or CC or J	25 A
3	LXM26DU20M3X	RK5 or J	45 A
4	LXM26DU30M3X	RK5 or J	50 A
	LXM26DU45M3X	RK5 or J	50 A

Chapter 4

Drive

What Is in This Chapter?

This chapter contains the following sections:

Section	Topic	Page
4.1	General Overview	28
4.2	Drive Technical Data	32

Section 4.1

General Overview

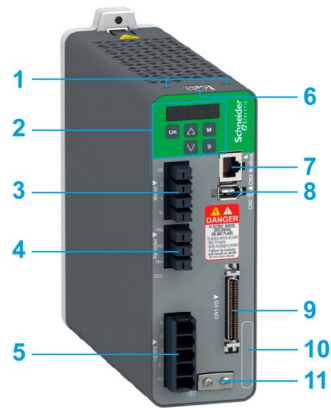
What Is in This Section?

This section contains the following topics:

Topic	Page
Servo Drive Description	29
Servo Drive Nameplate	30
Servo Drive Type Code	31

Servo Drive Description

Presentation



Item	Description	Connector
1	Slot for application name plate (VW3M2501)	-
2	HMI: 7-segment display, 5 buttons, and 2 status LED	-
3	Removable terminal (provided) for motor connection	Motor (see page 146)
4	Removable terminal (provided) for braking resistor connection	Resistor (see page 144)
5	Removable terminal (provided) for connecting the power supply	~ 220 V (see page 141)
6	QR code for access to technical data	-
7	RJ45 connector for Modbus serial link	CN3 (see page 139)
8	Connector for the encoder of the motor	CN2 (see page 137)
9	Input/output connector	CN1 (see page 125)
10	Device Reference	-
11	Screw terminal for protective ground (protective earth)	-

Parameters Access

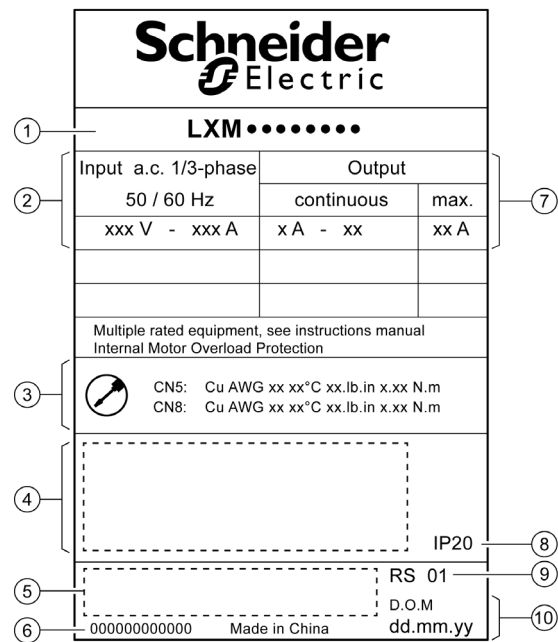
Servo drive parameters ([see page 205](#)) may be accessed using:

- The integrated HMI
- The Device Type Manager (DTM)

Servo Drive Nameplate

Presentation

The nameplate contains the following data:



Item	Description
1	Drive reference (<i>see page 31</i>)
2	Logic supply
3	Cable specifications
4	Certifications
5	Barcode
6	Serial number
7	Output power
8	Degree of protection
9	Hardware version
10	Date of manufacture

Servo Drive Type Code

Servo Drive Type Code

Item	1	2	3	4	5
Type code (example)	LXM	26	D	U07	M3X

Item	Meaning
1	Product designation LXM = Lexium
2	Product type 26 = AC servo drive for one axis
3	Interfaces D = Modbus RTU, PTI, I/O interface, commissioning via Modbus RTU
4	Continuous power UA5 = 0.05 kW U02 = 0.1 kW U02 = 0.2 kW U04 = 0.4 kW U07 = 0.75 kW U10 = 1 kW U15 = 1.5 kW U20 = 2 kW U30 = 3 kW U45 = 4.5 kW
5	Power stage supply [Vac] M3X = single phase or 3-phase, 200/230 Vac

Section 4.2

Drive Technical Data

What Is in This Section?

This section contains the following topics:

Topic	Page
Environmental Conditions	33
Dimensions	35
Electrical Data	37
Single-Phase Connection	38
Three-Phase Connection	39
Inputs / Outputs Characteristics	41

Environmental Conditions

Ambient Conditions During Operation

The maximum permissible ambient temperature during operation depends on the mounting distances between the devices and on the required power. Observe the instructions in the chapter Installation (*see page 120*).

Description	Unit	Value
Ambient temperature without current derating (no icing, non-condensing)	°C (°F)	0...40 (32...104)
Ambient temperature with current derating of 1% per 1 °C (1.8 °F)	°C (°F)	40...55 (104...131)

The following relative humidity is permissible during operation:

Description	Unit	Value
Relative humidity (non-condensing)	%	<95

Description	Unit	Value
Installation altitude above mean sea level without current derating	m (ft)	<2000 (<6561)

Ambient Conditions During Transportation and Storage

The environment during transportation and storage must be dry and free from dust.

Description	Unit	Value
Temperature	°C (°F)	-25...65 (-4...149)

The following relative humidity is permissible during transportation and storage:

Description	Unit	Value
Relative humidity (non-condensing)	%	<95

Installation Site and Connection

For operation, the device must be mounted in a closed control cabinet with a degree of protection of at least IP 54. The device may only be operated with a permanently installed connection.

 DANGER
ELECTRIC SHOCK, EXPLOSION, OR ARC FLASH Install the drive in a control cabinet or housing with a minimum IP 54 rating. Failure to follow these instructions will result in death or serious injury.

Pollution Degree and Degree of Protection

Description	Value
Pollution degree	2
Degree of protection	IP20

Degree of Protection When the Safety Function Is Used

You must ensure that conductive substances cannot get into the product (pollution degree 2). Conductive substances may cause the safety function to become inoperative.

WARNING

INOPERABLE SAFETY FUNCTION

Ensure that conductive substances (water, contaminated or impregnated oils, metal shavings, etc.) cannot get into the drive.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Vibration and Shock During Operation

Description	Value
Class as per IEC 60721-3-3	3M4 3 mm from 9...200 Hz
Maximum shock	98.1 m/s ² (10 g) Type I

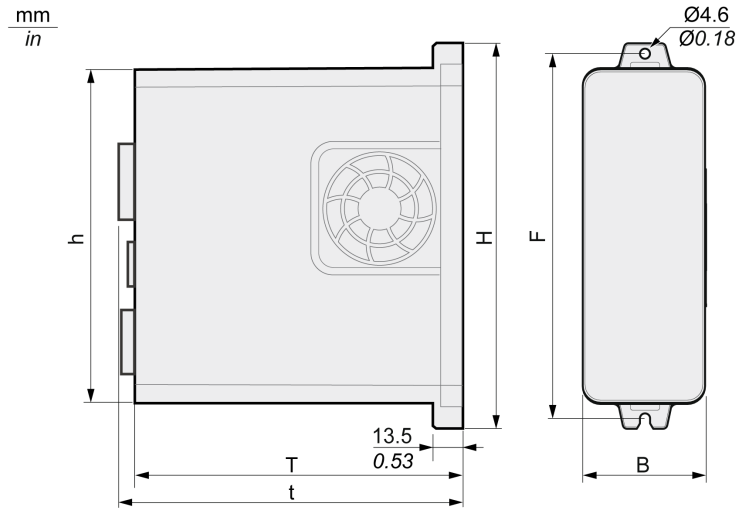
Vibration and Shock During Transportation and Storage

Description	Value
Class as per IEC 60721-3-2	2M2 3.5 mm (2...9 Hz) 9.81 m/s ² (1 g) from 9...200 Hz 14.715 m/s ² (1.5 g) from 200...500 Hz 34.335 m/s ² (3.5 g) from 2...9 Hz
Maximum shock	294.3 m/s ² (30 g) Type II

Dimensions

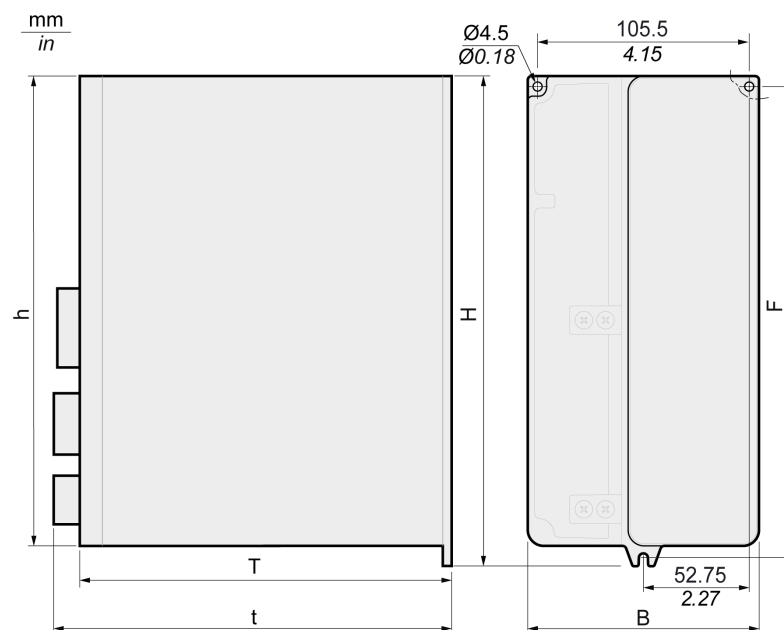
Lexium 26D Dimensions

LXM26DUA5, LXM26DU01, LXM26DU02, LXM26DU04, LXM26DU07, LXM26DU10, LXM26DU15, LXM26DU20



LXM26D	Unit	UA5, U01, U02, U04, U07	U10, U15	U20
B	mm (in)	55 (2.17)	55 (2.17)	62 (2.44)
H	mm (in)	173.2 (6.82)	173.5 (6.83)	194.5 (7.66)
h	mm (in)	150 (5.91)	150 (5.91)	170 (6.69)
F	mm (in)	164 (6.46)	164 (6.46)	185 (7.28)
T	mm (in)	146 (5.75)	170 (6.69)	184 (7.24)
d	mm (in)	152.7 (6.01)	176.3 (6.94)	197 (7.76)

LXM26DU30, LXM26DU45



LXM26D	Unit	U30, U45
B	mm (in)	116 (4.57)
H	mm (in)	245 (9.65)
h	mm (in)	234 (9.21)
F	mm (in)	235 (9.25)
T	mm (in)	186 (7.32)
d	mm (in)	199 (7.83)

Electrical Data

Introduction

The products are intended for industrial use and may only be operated with a permanently installed connection.

Mains Voltage: Range and Tolerance

Description	Unit	Value
220 Vac single-phase/three-phase	Vac	200 -15 % ... 230 +10 %
Frequency	Hz	50 -5 % ... 60 +5 %
Transient overvoltages	–	Overvoltage category III ⁽¹⁾
Rated voltage to ground	Vac	230
(1) Depends on installation altitude, see Environmental Conditions (<i>see page 33</i>)		

Type of Grounding

Description	Value
TT grounding system, TN grounding system	Approved
IT mains	Not approved
Mains with grounded line conductor	Not approved

Leakage Current

Description	Unit	Value
Leakage current (as per IEC 60990, figure 3)	mA	<30 ⁽¹⁾
(1) Measured on mains with grounded neutral point and without external mains filter. Take into account that a 30 mA RCD can already trigger at 15 mA. In addition, there is a high-frequency leakage current which is not considered in the measurement. The response to this depends on the type of residual current device.		

Monitoring of the Continuous Output Power

The continuous output power is monitored by the device. If the continuous output power is exceeded, the device reduces the output current.

PWM Frequency Power Stage

PWM frequency power stage The PWM frequency of the power stage is set to a fixed value.

LXM26D	UA5, U01, U02, U04, U07, U10, U15	U20, U30, U45
PWM frequency power stage	16 kHz	8 kHz

Type of Cooling

LXM26D	UA5, U01, U02	U04, U07, U10, U15, U20, U30, U45
Type of cooling	Convection	Fan

Permissible Drive / Motor Combinations

The BCH2 motors can be connected to the Lexium 26D drive range.

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table (*see page 18*).

Single-Phase Connection

Electrical Data for Drive Connected Via a Single-Phase

LXM26D•M3X	Unit	UA5	U01	U02	U04	U07	U10	U15
Nominal voltage	V	230 (single-phase)						
Inrush current limitation	A	8						
Maximum fuse to be connected upstream ⁽¹⁾	A	25						
Short-circuit current rating (SCCR)	kA	5						
Continuous output current	A _{rms}	0.64	0.9	1.5	2.6	4.5	7	7
Peak output current	A _{rms}	2	2.7	4.5	7.8	13.5	21	21
Nominal power ⁽²⁾	W	50	100	200	400	750	1000	1500
Input current ⁽²⁾⁽³⁾	A _{rms}	0.8	1.2	2.4	3.8	6	8.5	10
THD (total harmonic distortion) ⁽²⁾⁽⁴⁾	%	262.8	239.2	226.8	211.6	181.8	176.3	166.6
Power dissipation ⁽⁵⁾	W	8	10	14	22	38	36	41
Maximum inrush current ⁽⁶⁾	A	175					235	
Time for maximum inrush current	ms	0.5					0.6	
(1) As per IEC 60269; Circuit breakers with C characteristic; See Conditions for UL 508C (<i>see page 23</i>) for UL and CSA; Lower ratings are permissible; The fuse must be rated in such a way that the fuse does not trip at the specified input current.								
(2) At a mains impedance corresponding to the short-circuit current rating (SCCR)								
(3) At nominal power and nominal voltage								
(4) With reference to the input current								
(5) Condition: internal braking resistor not active; value at nominal current, nominal voltage, and nominal power; value approximately proportional with output current								
(6) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time								

DC bus data for drives connected via a single-phase

LXM26D•M3X	Unit	UA5	U01	U02	U04	U07	U10	U15
Nominal voltage (single-phase)	Vac	230						
Nominal voltage DC bus	Vdc	322						
Undervoltage limit	Vdc	160						
Overvoltage limit	Vdc	420						
Maximum continuous power via DC bus	W	50	100	200	400	750	1000	1500
Maximum continuous power via DC bus	A	0.2	0.3	0.6	1.2	2.3	3.1	4.6

Three-Phase Connection

Electrical Data for Drive Connected Via Three-Phase

LXM26D•M3X	Unit	UA5	U01	U02	U04	U07	U10
Nominal voltage	V	230 (3-phase)					
Inrush current limitation	A	8					
Maximum fuse to be connected upstream ⁽¹⁾	A	25					
Short-circuit current rating (SCCR)	kA	5					
Continuous output current	A _{rms}	0.64	0.9	1.5	2.6	4.5	7
Peak output current	A _{rms}	2	2.7	4.5	7.8	13.5	21
Nominal power ⁽²⁾	W	50	100	200	400	750	1000
Input current ⁽²⁾⁽³⁾	A _{rms}	0.42	0.74	1.25	2.2	3.9	5
THD (total harmonic distortion) ⁽²⁾⁽⁴⁾	%	227.8	212.7	200.7	183.7	160.8	155.5
Power dissipation ⁽⁵⁾	W	8	10	14	22	38	36
Maximum inrush current ⁽⁶⁾	A	175					235
Time for maximum inrush current	ms	0.5					0.6
(1) As per IEC 60269; Circuit breakers with C characteristic; See Conditions for UL 508C (<i>see page 23</i>) for UL and CSA; Lower ratings are permissible; The fuse must be rated in such a way that the fuse does not trip at the specified input current.							
(2) At a mains impedance corresponding to the short-circuit current rating (SCCR)							
(3) At nominal power and nominal voltage							
(4) With reference to the input current							
(5) Condition: internal braking resistor not active; value at nominal current, nominal voltage, and nominal power; value approximately proportional with output current							
(6) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time							

LXM26D•M3X	Unit	U15	U20	U30	U45
Nominal voltage	V	230 (3-phase)			
Inrush current limitation	A	8	19.2	17	
Maximum fuse to be connected upstream ⁽¹⁾	A	25	32		
Short-circuit current rating (SCCR)	kA	5		22	
Continuous output current	A _{rms}	7	12	19.8	22.8
Peak output current	A _{rms}	21	36	60	61
Nominal power ⁽²⁾	W	1500	2000	3000	4500
Input current ⁽²⁾⁽³⁾	A _{rms}	5.9	8.7	12.9	18
THD (total harmonic distortion) ⁽²⁾⁽⁴⁾	%	144.8	137.1	155.8	147.1
Power dissipation ⁽⁵⁾	W	41		97	
Maximum inrush current ⁽⁶⁾	A	235	295	300	
Time for maximum inrush current	ms	0.6	1.0		
(1) As per IEC 60269; Circuit breakers with C characteristic; See Conditions for UL 508C (<i>see page 23</i>) for UL and CSA; Lower ratings are permissible; The fuse must be rated in such a way that the fuse does not trip at the specified input current. (2) At a mains impedance corresponding to the short-circuit current rating (SCCR) (3) At nominal power and nominal voltage (4) With reference to the input current (5) Condition: internal braking resistor not active; value at nominal current, nominal voltage, and nominal power; value approximately proportional with output current (6) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time					

DC bus data for drives connected via three-phase

LXM26D•M3X	Unit	UA5	U01	U02	U04	U07	U10
Nominal voltage (three phases)	Vac	230					
Nominal voltage DC bus	Vdc	322					
Undervoltage limit	Vdc	160					
Overvoltage limit	Vdc	420					
Maximum continuous power via DC bus	W	50	100	200	400	750	1000
Maximum continuous power via DC bus	A	0.2	0.3	0.6	1.2	2.3	3.1

LXM26D•M3X	Unit	U15	U20	U30	U45
Nominal voltage (three phases)	Vac	230			
Nominal voltage DC bus	Vdc	322			
Undervoltage limit	Vdc	160			
Overvoltage limit	Vdc	420			
Maximum continuous power via DC bus	W	1500	2000	3000	4500
Maximum continuous power via DC bus	A	4.6	6.2	9.2	13.8

Inputs / Outputs Characteristics

Logic Type

The outputs are short-circuit protected. The inputs and outputs are galvanically isolated.

The digital inputs and outputs of this product can be wired for positive or negative logic.

Logic type	Active state
Positive logic	Output supplies current (source output) Current flows to the input (sink input)
Negative logic	Output draws current (sink output) Current flows from the input (source input)

Digital Input Signals 24 V

When wired as positive logic, the levels of the opto-isolated inputs DI1...DI5 and DI8 comply with IEC 61131-2, type 1. The electrical characteristics are also valid when wired as negative logic.

Description	Unit	Value
"0" signal voltage	Vdc	≤5
"1" signal voltage	Vdc	≥11
Input current (typical)	mA	6
Debounce time ⁽¹⁾	mA	0...20
(1) Adjustable via parameter P2-09 in increments of 1 ms.		

Digital Output Signals 24 V

The levels of the digital 24 V output signals DO• comply with IEC 61131-2.

Description	Unit	Value
Switching voltage	Vdc	24
Maximum switching current	mA	100
Voltage drop at 100 mA load	Vdc	< 3

Analog Input Signals

Description	Unit	Value
Voltage range	Vdc	-10...10
Input resistance, typical	kΩ	10
Resolution	Bit	12
Sampling period	μs	32.25

Analog Output Signals

Description	Unit	Value
Voltage range	Vdc	-8...8
Output current	mA	10
Minimum load resistance (voltage source)l	kΩ	1
Resolution	Bit	12
Sampling period	ms	1
Time constant	μs	10

Touch Probe Input Signals 24 V

When wired as positive logic, the levels of the opto-isolated inputs DI6 and DI7 comply with IEC 61131-2, type 1. The electrical characteristics are also valid when wired as negative logic.

Description	Unit	Value
"0" signal voltage	Vdc	≤5
"1" signal voltage	Vdc	≥11
Input current (typical)	mA	7
Debounce time ⁽¹⁾	µs	0...100
Jitter Capture	µs	1
(1) Adjustable via parameter P2-24 in increments of 1 µs.		

24 Vdc Power Supply (Pin 17):

24 Vdc power supply (pin 17):

Description	Unit	Value
Output voltage	Vdc	24
Maximum output current	mA	200

ESIM Output Signals

The ESIM output signals comply with the RS422 interface specification.

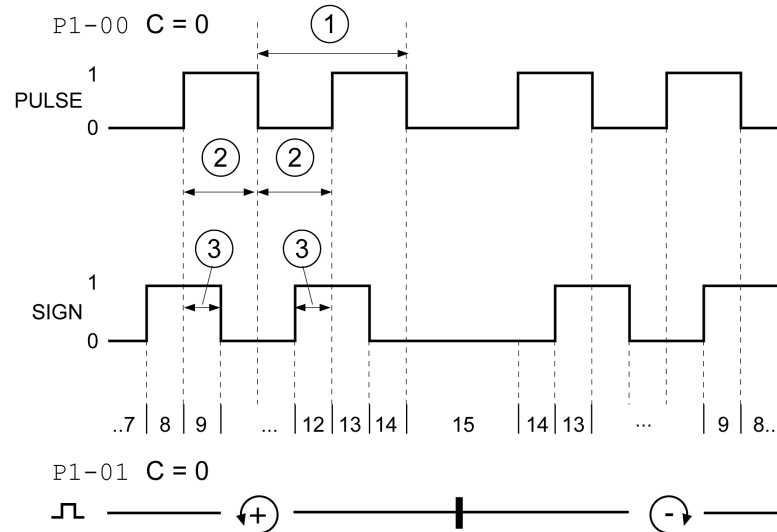
Description	Unit	Value
Logic level	–	As per RS422 ⁽¹⁾
Output frequency per signal	kHz	800
Maximum output frequency (quadruple evaluation)	kHz	3200
(1) Due to the input current of the optocoupler in the input circuit, a parallel connection of a driver output to several devices is not permitted.		

Function A/B Signals

External A/B signals can be supplied via the PTI input as reference values in operating mode Pulse Train (Pt).

Signal	Function
Signal SIGN before signal PULSE	Movement in positive direction
Signal PULSE before signal SIGN	Movement in negative direction

Time chart with A/B signal, counting forwards and backwards



The signal shape shown relates to the factory setting (P1-00 C=0). The direction of movement shown relates to the factory setting (P1-01 C=0).

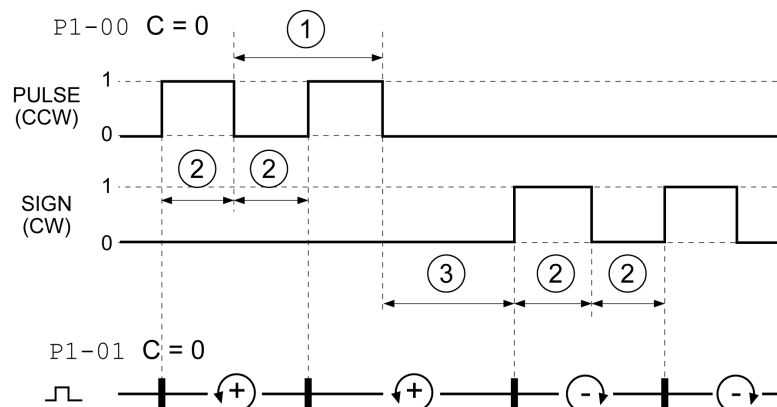
Intervals (minimum)	HPULSE / HSIGN with RS422	PULSE / SIGN with RS422	PULSE / SIGN with Open Collector
1	4 MHz	500 kHz	200 kHz
2	0.125 μ s	0.1 μ s	2.5 μ s
3	0.0625 μ s	0.5 μ s	1.25 μ s

Function CW/CCW

External CW/CCW signals can be supplied via the PTI input as reference values.

Signal	Function
Signal PULSE (CCW)	Movement in positive direction
Signal SIGN (CW)	Movement in negative direction

Time chart with "CW/CCW"



The signal shape shown relates to the factory setting (P1-00 C=0). The direction of movement shown relates to the factory setting (P1-01 C=0).

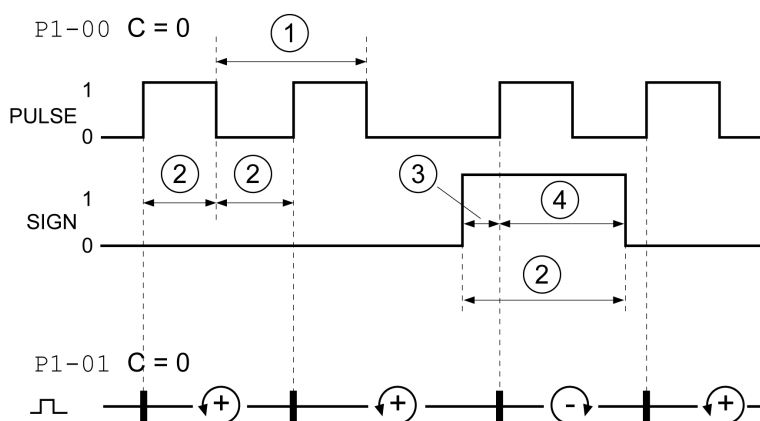
Intervals (minimum)	HPULSE / HSIGN with RS422	PULSE / SIGN with RS422	PULSE / SIGN with Open Collector
1	4 MHz	500 kHz	200 kHz
2	0.125 µs	0.1 µs	2.5 µs
3	0.0625 µs	0.5 µs	1.25 µs

Function P/D

External P/D signals can be supplied via the PTI input as reference values.

Signal	Function
Signal PULSE	Motor movement
Signal SIGN	Direction of movement

Time chart with pulse/direction signal



The signal shape shown relates to the factory setting (P1-00 C=0). The direction of movement shown relates to the factory setting (P1-01 C=0).

Intervals (minimum)	HPULSE / HSIGN with RS422	PULSE / SIGN with RS422	PULSE / SIGN with Open Collector
1	4 MHz	500 kHz	200 kHz
2	0.125 µs	0.1 µs	2.5 µs
3	0.0625 µs	0.5 µs	1.25 µs
4	0.0625 µs	0.5 µs	1.25 µs

Chapter 5

Motor

What Is in This Chapter?

This chapter contains the following sections:

Section	Topic	Page
5.1	General Overview	46
5.2	Motor Technical Data	50
5.3	BCH2MB Motor	55
5.4	BCH2LD Motor	59
5.5	BCH2•F Motor	63
5.6	BCH2LH Motor	67
5.7	BCH2•M Motor	71
5.8	BCH2•R Motor	77

Section 5.1

General Overview

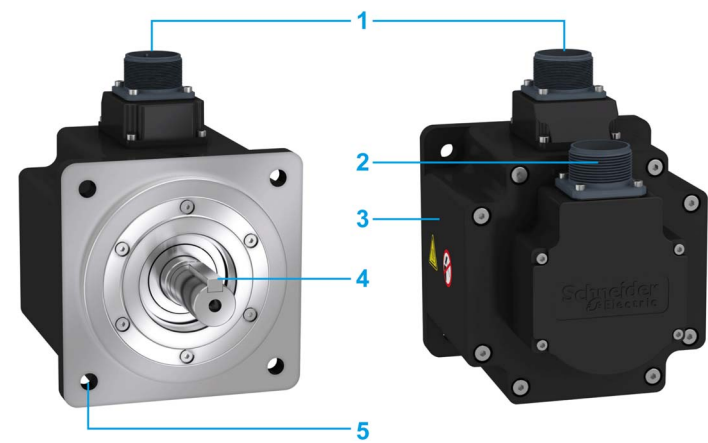
What Is in This Section?

This section contains the following topics:

Topic	Page
Components and Interfaces	46
Servo Motor Nameplate	47
Servo Motor Type Code	49

Components and Interfaces

Presentation



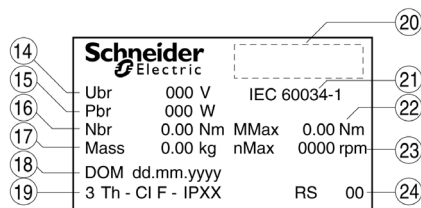
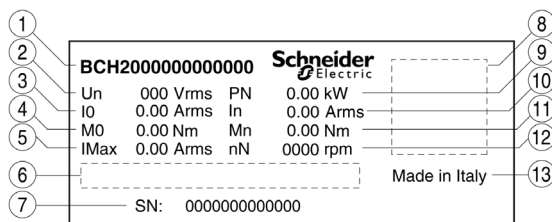
BCH2 servo motors, with a 3-phase stator and rotor with rare earth-based permanent magnets, consist of:

Item	Description
1	Connector of the motor cable (<i>see page 86</i>)
2	Connector of the encoder cable (<i>see page 87</i>)
3	Housing
4	Smooth or keyed shaft end, depending on the motor reference
5	4-point axial mounting flange

Servo Motor Nameplate

BCH2•B

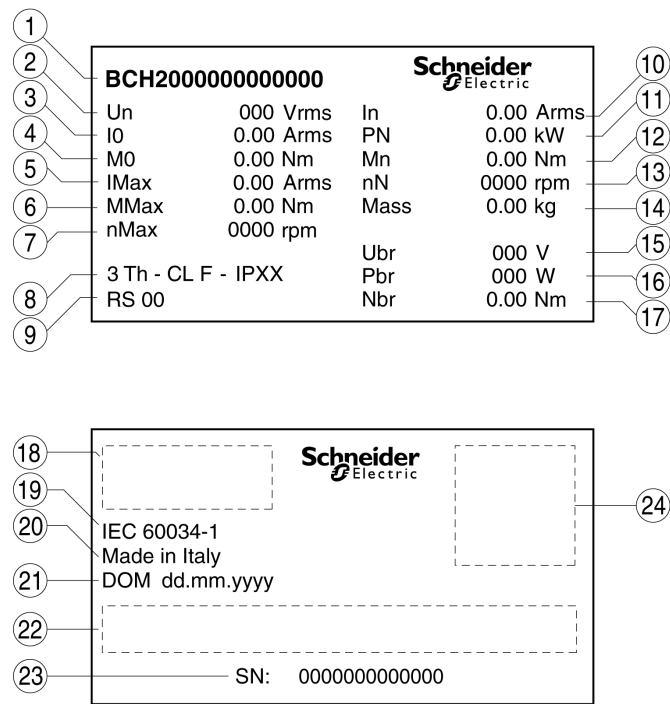
The nameplate contains the following data:



Item	Description	Item	Description
1	Motor reference (<i>see page 49</i>)	13	Country of manufacture
2	Nominal voltage	14	Nominal voltage of the holding brake (optional)
3	Continuous stall current	15	Nominal power of the holding brake (optional)
4	Continuous stall torque	16	Nominal torque of the holding brake (optional)
5	Maximum current	17	Mass
6	Barcode	18	Date of manufacture DOM
7	Serial number	19	Number of motor phases, temperature class, degree of protection
8	QR code	20	Certifications
9	Nominal power	21	Applied standard
10	Nominal current	22	Peak torque
11	Nominal torque	23	Maximum permissible speed of rotation
12	Nominal speed of rotation	24	Hardware version

BCH2•D, BCH2•F, BCH2•H, BCH2•M, and BCH2•R

The nameplate contains the following data:



Item	Description	Item	Description
1	Motor reference (<i>see page 49</i>)	13	Nominal speed of rotation
2	Nominal voltage	14	Mass
3	Continuous stall current	15	Nominal voltage of the holding brake (optional)
4	Continuous stall torque	16	Nominal power of the holding brake (optional)
5	Maximum current	17	Nominal torque of the holding brake (optional)
6	Peak torque	18	Certifications
7	Maximum permissible speed of rotation	19	Applied standard
8	Number of motor phases, temperature class, degree of protection	20	Country of manufacture
9	Hardware version	21	Date of manufacture DOM
10	Nominal current	22	Barcode
11	Nominal power	23	Serial number
12	Nominal torque	24	QR code

Servo Motor Type Code

Servo Motor Type Code

Item	1	2	3	4	5	6	7	8	9	10
Type code (example)	BCH2	M	B	01	3	3	C	A	5	C

Item	Meaning		
1	Product family BCH2 = Brushless servo motors - second generation		
2	Moment of inertia L = Low M = Medium H = High		
3	Size (housing) B = 40 mm flange D = 60 mm flange F = 80 mm flange H = 100 mm flange M = 130 mm flange R = 180 mm flange		
4	<table> <tr> <td>Nominal power A5 = 50 W 01 = 100 W 02 = 200 W 03 = 300 W 04 = 400 W 05 = 500 W 06 = 600 W 07 = 750 W 08 = 850 W 09 = 900 W</td><td>10 = 1.0 kW 13 = 1.3 kW 15 = 1.5 kW 20 = 2.0 kW 30 = 3.0 kW 35 = 3.5 kW 45 = 4.5 kW</td></tr> </table>	Nominal power A5 = 50 W 01 = 100 W 02 = 200 W 03 = 300 W 04 = 400 W 05 = 500 W 06 = 600 W 07 = 750 W 08 = 850 W 09 = 900 W	10 = 1.0 kW 13 = 1.3 kW 15 = 1.5 kW 20 = 2.0 kW 30 = 3.0 kW 35 = 3.5 kW 45 = 4.5 kW
Nominal power A5 = 50 W 01 = 100 W 02 = 200 W 03 = 300 W 04 = 400 W 05 = 500 W 06 = 600 W 07 = 750 W 08 = 850 W 09 = 900 W	10 = 1.0 kW 13 = 1.3 kW 15 = 1.5 kW 20 = 2.0 kW 30 = 3.0 kW 35 = 3.5 kW 45 = 4.5 kW		
5	Winding 1 = Optimized in terms of torque (1000 rpm/1500 rpm) 2 = Optimized in terms of torque and speed of rotation (2000 rpm) 3 = Optimized in terms of speed of rotation (3000 rpm)		
6	Shaft and degree of protection⁽¹⁾ 3 = Parallel key; degree of protection: shaft and housing IP 65		
7	Encoder system C = High-resolution encoder single turn		
8	Holding brake A = Without holding brake F = With holding brake		
9	Connection version 5 = Flying leads (for BCH2•B, BCH2•D, BCH2•F) 6 = MIL connector (for BCH2•H, BCH2•M, BCH2•R)		
10	Mechanical interface - mounting C = Asian style		
(1) In the case of mounting position IM V3 (drive shaft vertical, shaft end up), the motor has degree of protection IP 50.			

Section 5.2

Motor Technical Data

What Is in This Section?

This section contains the following topics:

Topic	Page
Environmental Conditions	50
Tightening Torque and Property Class of Screws	52
Overload Characteristics Curves	53
Encoder Technical Data	54

Environmental Conditions

Ambient Conditions During Operation

The maximum permissible ambient temperature during operation depends on the mounting distances between the devices and on the required power. Observe the instructions in the chapter Installation (*see page 150*).

Description	Unit	Value
Ambient temperature ⁽¹⁾ for motors without holding brake (no icing, non-condensing).	°C (°F)	-20...40 (-4...104)
Ambient temperature for motors with holding brake (no icing, non-condensing).	°C (°F)	0...40 (32...104)
Ambient temperature with current derating of 1% per °C (per 1.8 °F)	°C (°F)	40...60 (104...140)
Relative humidity (non-condensing)	%	5...85
Class as per IEC 60721-3-3	-	3K3, 3Z12, 3Z2, 3B2, 3C1, 3M6 ⁽²⁾
Installation altitude above mean sea level without current derating	m (ft)	<1000 (<3281)
Installation altitude above mean sea level with current derating of 1% per 100 m at altitudes higher than 1000 m	m (ft)	1000...3000 (3281...9843)
(1) Limit values with flanged motor, see Flange Sizes for Limit Values (<i>see page 50</i>)		
(2) Tested as per IEC 60068-2-6 and IEC 60068-2-27		

Ambient Conditions During Transportation and Storage

The environment during transportation and storage must be dry and free from dust.

Description	Unit	Value
Temperature	°C (°F)	-40...70 (-40...158)
Relative humidity (non-condensing)	%	≤75
Set of class combinations as per IEC 60721-3-2	—	IE 21

Flange Sizes for Limit Values

Limit values referring to this table relate to flanged motors with the following flange sizes:

Motor	Flange material	Flange size in [mm (in)]
BCH2MB	Aluminum	185 x 185 x 8 (7.28 x 7.28 x 0.31)
BCH2LD	Aluminum	250 x 250 x 12 (9.84 x 9.84 x 0.47)
BCH2•F	Aluminum	250 x 250 x 12 (9.84 x 9.84 x 0.47)
BCH2LH	Steel	300 x 300 x 20 (11.8 x 11.8 x 0.79)
BCH2•M	Steel	400 x 400 x 20 (15.7 x 15.7 x 0.79)
BCH2•R	Steel	550 x 550 x 20 (21.7 x 21.7 x 0.79)

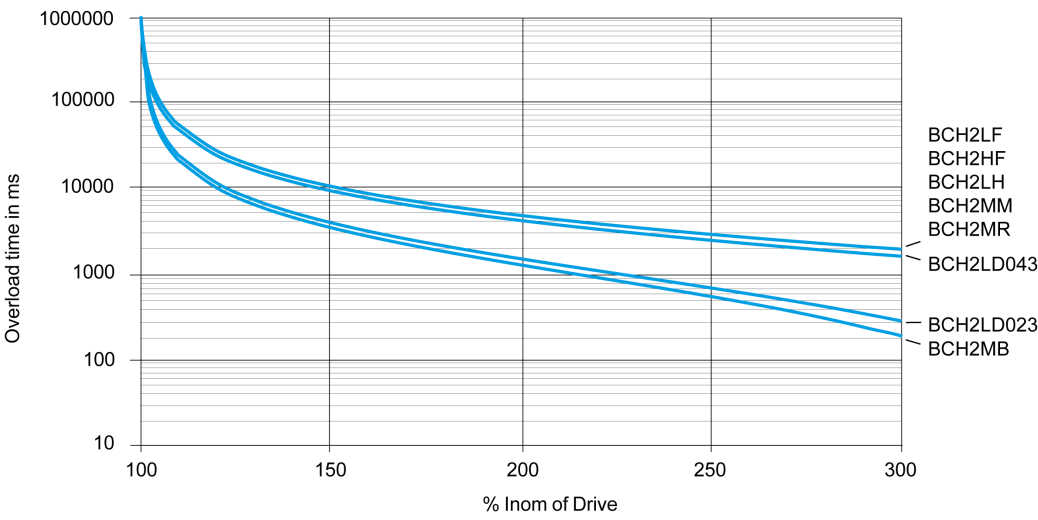
Compatibility with Foreign Substances

The motor has been tested for compatibility with many known substances and with the latest available knowledge at the moment of the design. Nonetheless, you must perform a compatibility test before using a foreign substance.

Tightening Torque and Property Class of Screws

Housing screws	Unit	Tightening torque
M3 x 0.50	Nm (lb.in)	1 (8.85)
M4 x 0.70	Nm (lb.in)	2.9 (25.67)
M5 x 0.80	Nm (lb.in)	5.9 (52.22)
M6 x 1.00	Nm (lb.in)	9.9 (87.62)
M7 x 1.25	Nm (lb.in)	24 (212.40)
M8 x 1.50	Nm (lb.in)	49 (433.65)
Property class of the screws	H	8.8

Overload Characteristics Curves



Encoder Technical Data

The drive can access the electronic nameplate via the electronic interface of the encoder for easy commissioning.

The signals meet the PELV requirements.

Description	Value
Measuring range absolute	1 revolution
Resolution in increments	Depending on evaluation
Accuracy of position	$\pm 0.044^\circ$
Supply voltage	4.1...5.25 Vdc
Maximum supply current	100 mA
Maximum permissible speed of rotation	6000 rpm
Maximum angular acceleration	100,000 rad/s ²

Section 5.3

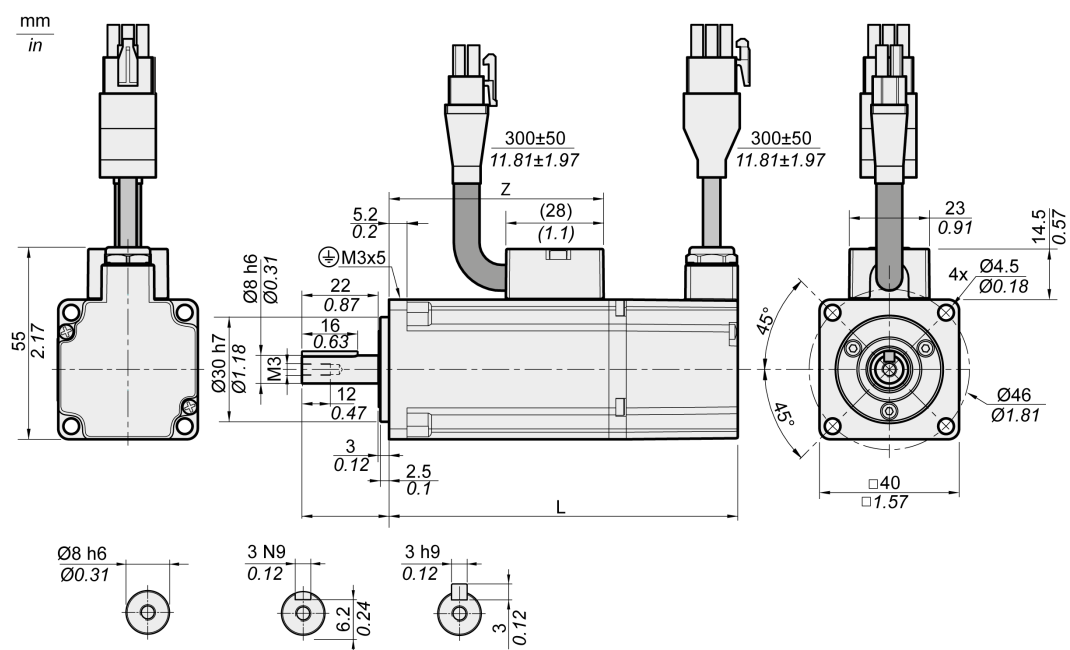
BCH2MB Motor

What Is in This Section?

This section contains the following topics:

Topic	Page
BCH2MB Dimensions	56
BCH2MB Characteristics Table	57
BCH2MB Curves	58

BCH2MB Dimensions

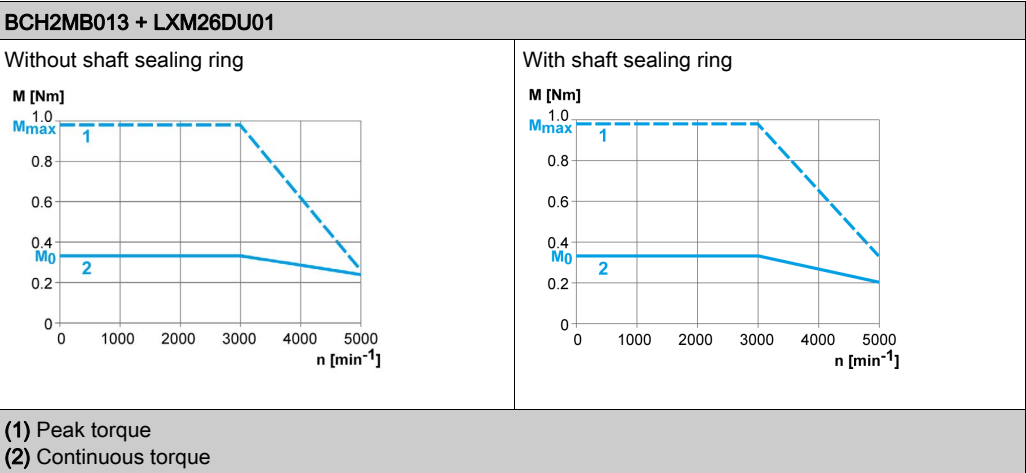
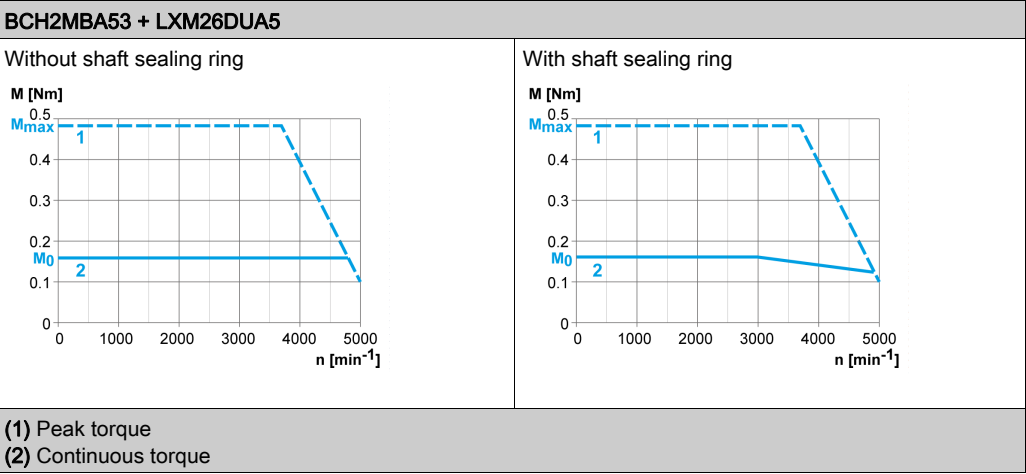


BCH2MB	Unit	A5	01
L (without holding brake)	mm (in)	82 (3.23)	100 (3.94)
L (with holding brake)	mm (in)	112 (4.41)	130 (5.12)
Z	mm (in)	43.5 (1.71)	61.5 (2.42)

BCH2MB Characteristics Table

BCH2MB ⁽¹⁾			A53	013
Technical data - general				
Continuous stall torque ⁽²⁾	M_0	Nm	0.16	0.32
Peak torque	$M_{\max}$	Nm	0.48	0.96
With supply voltage $U_n = 230$ Vac				
Nominal speed of rotation	n_N	rpm	3000	3000
Nominal torque	M_N	Nm	0.16	0.32
Nominal Current	I_N	A_{rms}	0.59	0.89
Nominal power	P_N	kW	0.05	0.10
Technical data - electrical				
Maximum winding voltage	$U_{\max}$	Vac	255	255
Maximum winding voltage	$U_{\max}$	Vdc	360	360
Maximum voltage to ground	–	Vac	255	255
Maximum Current	$I_{\max}$	A_{rms}	1.8	2.7
Continuous stall current	I_0	A_{rms}	0.54	0.81
Voltage constant ⁽³⁾	$k_{E\text{U-V}}$	V_{rms}	18	24
Torque constant ⁽⁴⁾	k_t	Nm/A	0.30	0.40
Winding resistance	$R_{20\text{U-V}}$	Ω	31.0	23.4
Winding inductance	$L_{q\text{U-V}}$	mH	26.4	21.5
Winding inductance	$L_{d\text{U-V}}$	mH	24.7	20.6
Technical data - mechanical				
Maximum permissible speed of rotation	$n_{\max}$	rpm	5000	5000
Rotor inertia without brake	J_M	kgcm ²	0.054	0.075
Rotor inertia with brake	J_M	kgcm ²	0.055	0.076
Mass without brake	m	kg	0.40	0.56
Mass with brake	m	kg	0.60	0.77
Degree of protection of the shaft	–	–	IP 65	IP 65
Degree of protection of the housing	–	–	IP 65	IP 65
Technical data - holding brake				
Holding torque	–	Nm	0.32	0.32
Nominal voltage	–	Vdc	24 +/-10%	24 +/-10%
Nominal power (electrical pull-in power)	–	W	4.4	4.4
(1) Limit values with flanged motor: ○ Flange material: Aluminum ○ Flange size in mm (in): 185 x 185 x 8 (7.28 x 7.28 x 0.31) (2) M_0 = Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 %. (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At $n = 20$ rpm and 20 °C (68 °F).				

BCH2MB Curves



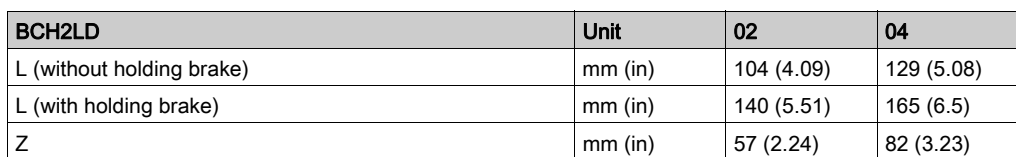
Section 5.4

BCH2LD Motor

What Is in This Section?

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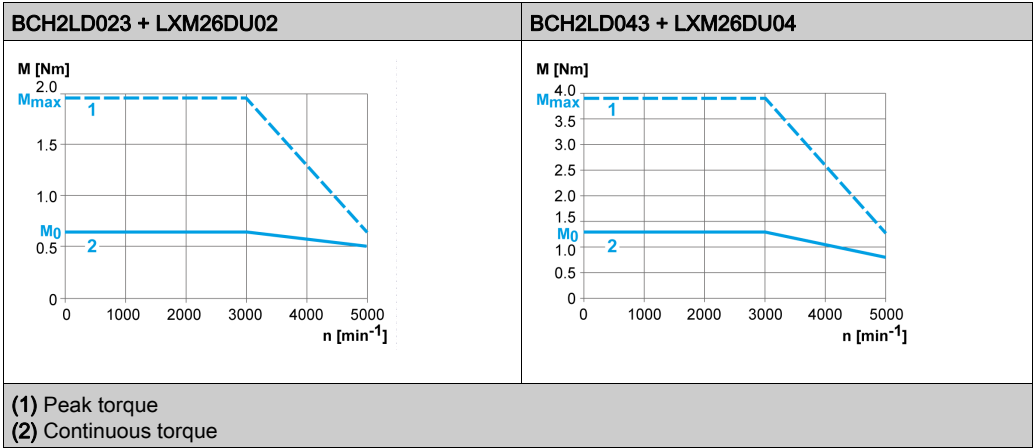
Topic	Page
BCH2LD Dimensions	60
BCH2LD Characteristics Table	61
BCH2LD Curves	62



BCH2LD Characteristics Table

BCH2LD ⁽¹⁾			023	043
Technical data - general				
Continuous stall torque ⁽²⁾	M_0	Nm	0.64	1.27
Peak torque	M_{max}	Nm	1.92	3.81
With supply voltage $U_n = 230$ Vac				
Nominal speed of rotation	n_N	rpm	3000	3000
Nominal torque	M_N	Nm	0.64	1.27
Nominal Current	I_N	A_{rms}	1.30	2.50
Nominal power	P_N	kW	0.20	0.40
Technical data - electrical				
Maximum winding voltage	U_{max}	Vac	255	255
Maximum winding voltage	U_{max}	Vdc	360	360
Maximum voltage to ground	–	Vac	255	255
Maximum Current	I_{max}	A_{rms}	4.5	7.8
Continuous stall current	I_0	A_{rms}	1.11	2.19
Voltage constant ⁽³⁾	k_E u-v	V_{rms}	35	35
Torque constant ⁽⁴⁾	k_t	Nm/A	0.58	0.58
Winding resistance	R_{20} u-v	Ω	12.2	5.2
Winding inductance	L_q u-v	mH	24.8	12.5
Winding inductance	L_d u-v	mH	22.7	12.0
Technical data - mechanical				
Maximum permissible speed of rotation	n_{max}	rpm	5000	5000
Rotor inertia without brake	J_M	kgcm ²	0.16	0.27
Rotor inertia with brake	J_M	kgcm ²	0.17	0.28
Mass without brake	m	kg	1.02	1.45
Mass with brake	m	kg	1.50	2.00
Degree of protection of the shaft	–	–	IP 65	IP 65
Degree of protection of the housing	–	–	IP 65	IP 65
Technical data - holding brake				
Holding torque	–	Nm	1.3	1.3
Nominal voltage	–	Vdc	24 +/- 10%	24 +/- 10%
Nominal power (electrical pull-in power)	–	W	11.2	11.2
(1) Limit values with flanged motor: ○ Flange material: Aluminum ○ Flange size in mm (in): 250 x 250 x 12 (9.84 x 9.84 x 0.47) (2) M_0 =Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At $n = 20$ rpm and 20 °C (68 °F).				

BCH2LD Curves



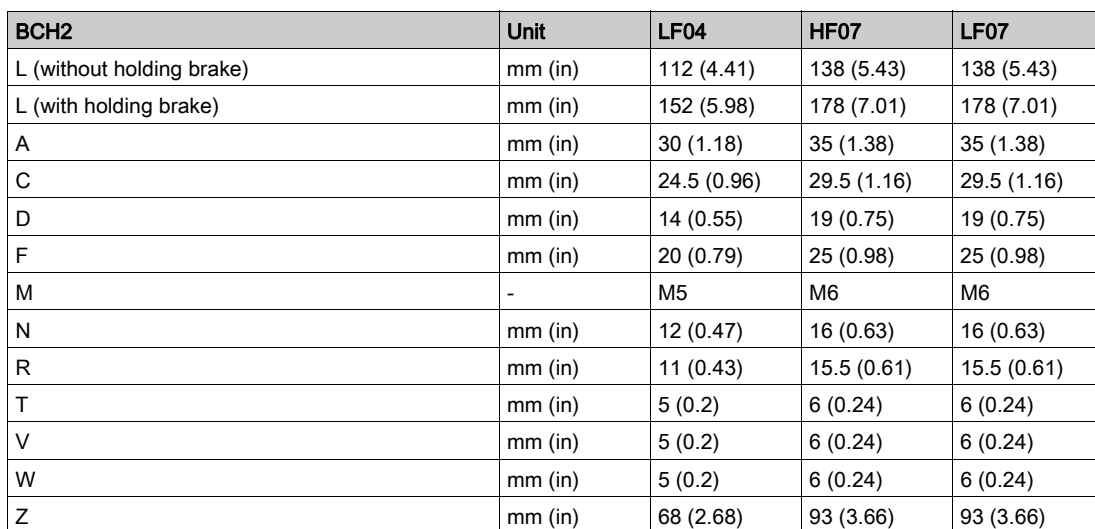
Section 5.5

BCH2•F Motor

What Is in This Section?

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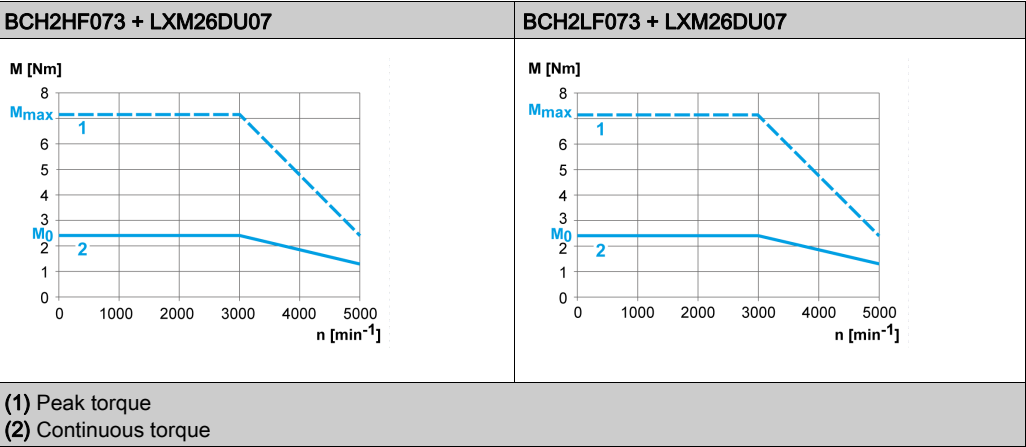
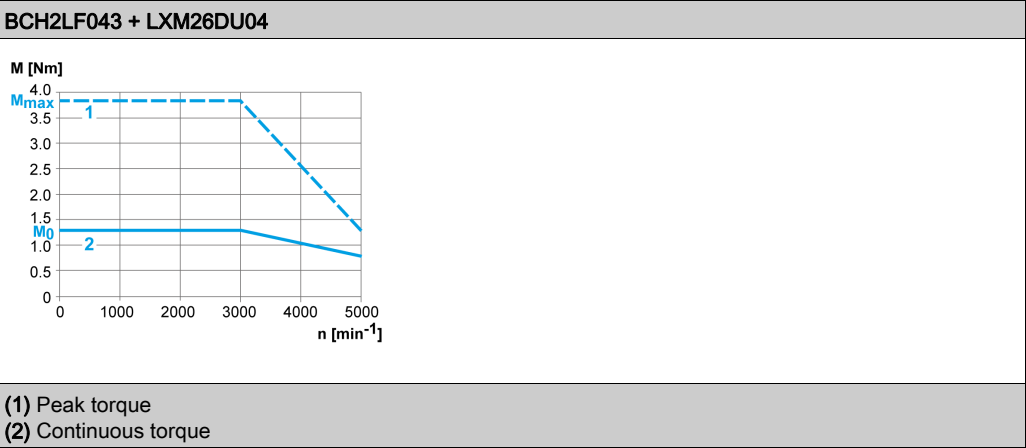
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BCH2•F Dimensions	64
BCH2•F Characteristics Table	65
BCH2•F Curves	66



BCH2•F Characteristics Table

BCH2 ⁽¹⁾			LF04 3	HF073	LF073
Technical data - general					
Continuous stall torque ⁽²⁾	M ₀	Nm	1.27	2.39	2.39
Peak torque	M _{max}	Nm	3.81	7.16	7.16
With supply voltage U _n = 230 Vac					
Nominal speed of rotation	n _N	rpm	3000	3000	3000
Nominal torque	M _N	Nm	1.27	2.39	2.39
Nominal Current	I _N	A _{rms}	2.52	4.29	4.29
Nominal power	P _N	kW	0.40	0.75	0.75
Technical data - electrical					
Maximum winding voltage	U _{max}	Vac	255	255	255
Maximum winding voltage	U _{max}	Vdc	360	360	360
Maximum voltage to ground	–	Vac	255	255	255
Maximum Current	I _{max}	A _{rms}	7.8	13.5	13.5
Continuous stall current	I ₀	A _{rms}	2.29	4.01	4.01
Voltage constant ⁽³⁾	k _E U-v	V _{rms}	33.5	36	36
Torque constant ⁽⁴⁾	k _t	Nm/A	0.55	0.60	0.60
Winding resistance	R ₂₀ U-v	Ω	3.20	1.50	1.50
Winding inductance	L _q U-v	mH	12.0	6.6	6.6
Winding inductance	L _d U-v	mH	11.3	6.1	6.1
Technical data - mechanical					
Maximum permissible speed of rotation	n _{max}	rpm	5000	5000	5000
Rotor inertia without brake	J _M	kgcm ²	0.67	1.54	1.19
Rotor inertia with brake	J _M	kgcm ²	0.72	1.59	1.24
Mass without brake	m	kg	2.00	2.90	2.80
Mass with brake	m	kg	2.80	3.70	3.60
Degree of protection of the shaft	–	–	IP 65	IP 65	IP 65
Degree of protection of the housing	–	–	IP 65	IP 65	IP 65
Technical data - holding brake					
Holding torque	–	Nm	2.5	2.5	2.5
Nominal voltage	–	Vdc	24 +/- 10%	24 +/- 10%	24 +/- 10%
Nominal power (electrical pull-in power)	–	W	10.2	10.2	10.2
(1) Limit values with flanged motor: ○ Flange material: Aluminum ○ Flange size in mm (in): 250 x 250 x 12 (9.84 x 9.84 x 0.47) (2) M₀=Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At n = 20 rpm and 20 °C (68 °F).					

BCH2•F Curves



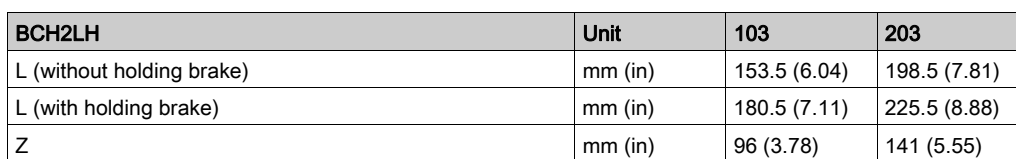
Section 5.6

BCH2LH Motor

What Is in This Section?

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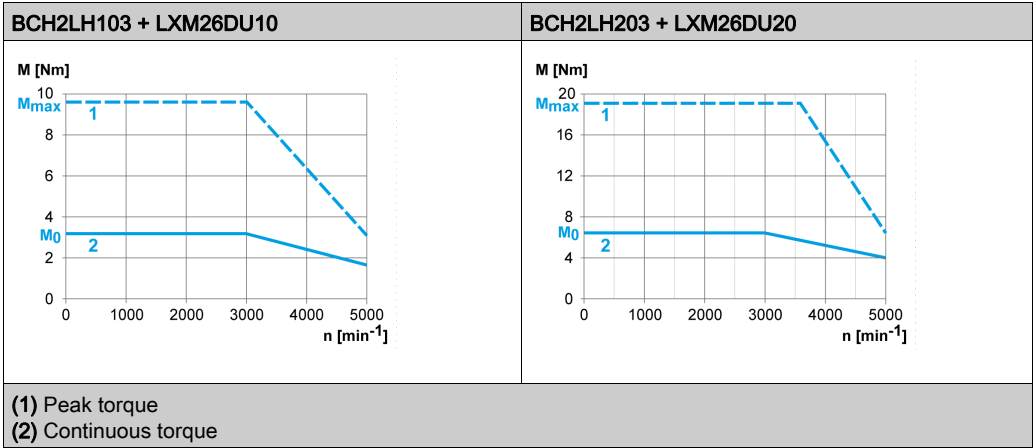
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BCH2LH Dimensions	68
BCH2LH Characteristics Table	69
BCH2LH Curves	70



BCH2LH Characteristics Table

BCH2LH ⁽¹⁾			103	203
Technical data - general				
Continuous stall torque ⁽²⁾	M_0	Nm	3.18	6.37
Peak torque	M_{max}	Nm	9.54	19.11
With supply voltage $U_n = 230$ Vac				
Nominal speed of rotation	n_N	rpm	3000	3000
Nominal torque	M_N	Nm	3.18	6.37
Nominal Current	I_N	A_{rms}	6.64	10.27
Nominal power	P_N	kW	1.00	2.00
Technical data - electrical				
Maximum winding voltage	U_{max}	Vac	255	255
Maximum winding voltage	U_{max}	Vdc	360	360
Maximum voltage to ground	–	Vac	255	255
Maximum Current	I_{max}	A_{rms}	20.0	35.0
Continuous stall current	I_0	A_{rms}	5.83	9.87
Voltage constant ⁽³⁾	k_E u-v	V_{rms}	33	39
Torque constant ⁽⁴⁾	k_t	Nm/A	0.55	0.65
Winding resistance	R_{20u-v}	Ω	0.67	0.36
Winding inductance	L_q u-v	mH	4.3	2.6
Winding inductance	L_d u-v	mH	4.20	2.59
Technical data - mechanical				
Maximum permissible speed of rotation	n_{max}	rpm	5000	5000
Rotor inertia without brake	J_M	kgcm ²	2.40	4.28
Rotor inertia with brake	J_M	kgcm ²	2.45	4.35
Mass without brake	m	kg	4.60	6.70
Mass with brake	m	kg	5.10	7.20
Degree of protection of the shaft	–	–	IP 65	IP 65
Degree of protection of the housing	–	–	IP 65	IP 65
Technical data - holding brake				
Holding torque	–	Nm	6.5	6.5
Nominal voltage	–	Vdc	24 +/-10%	24 +/-10%
Nominal power (electrical pull-in power)	–	W	10.4	10.4
(1) Limit values with flanged motor: ○ Flange material: Steel ○ Flange size in mm (in): 300 x 300 x 20 (11.8 x 11.8 x 0.79) (2) M_0 =Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At $n = 20$ rpm and 20 °C (68 °F).				

BCH2LH Curves



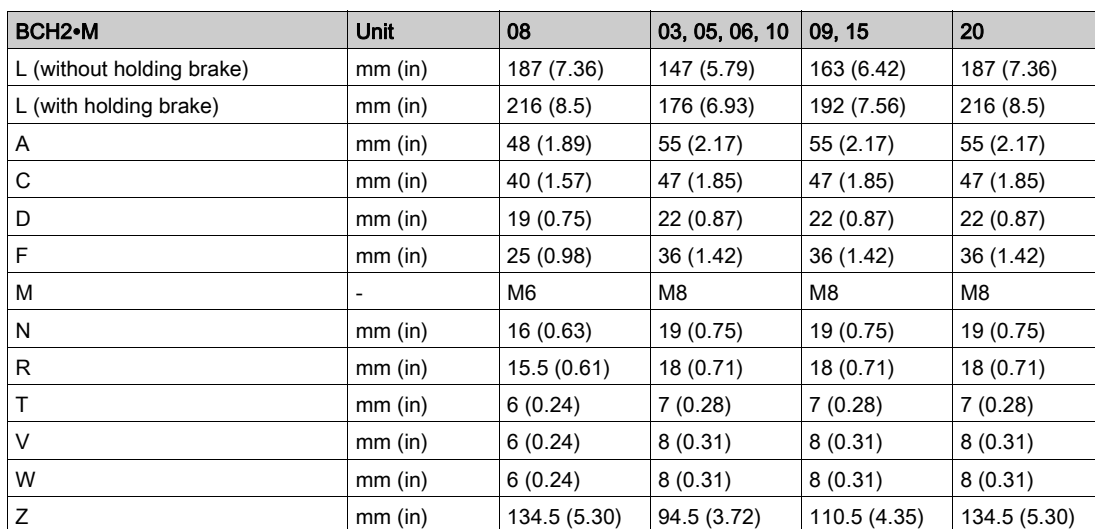
Section 5.7

BCH2•M Motor

What Is in This Section?

This section contains the following topics:

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BCH2•M Dimensions	72
BCH2•M Characteristics Table	73
BCH2•M Curves	75

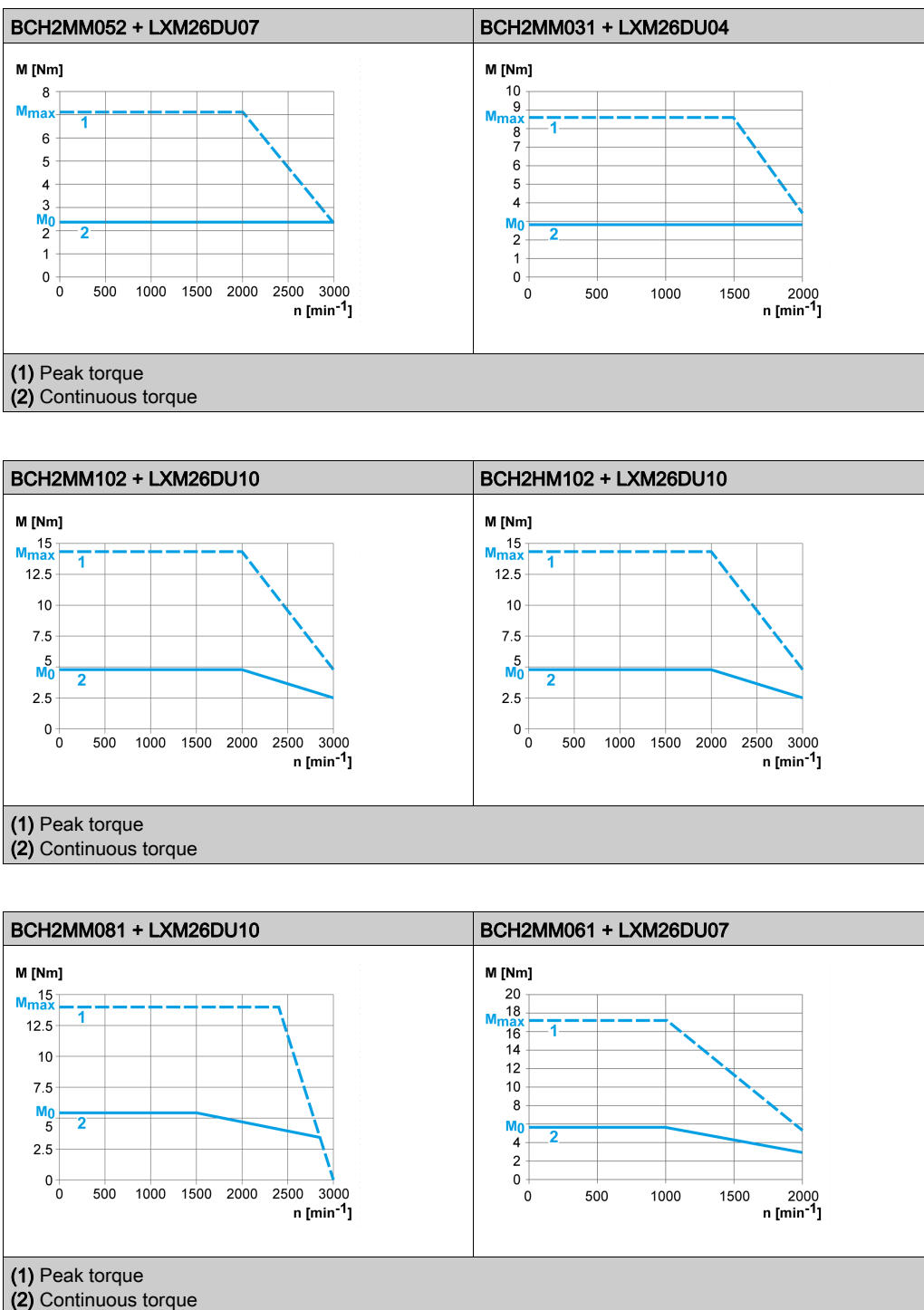


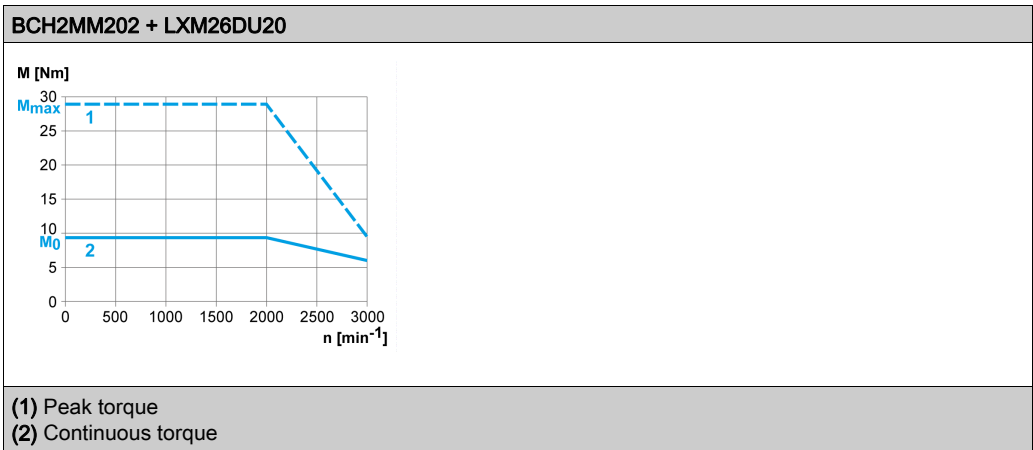
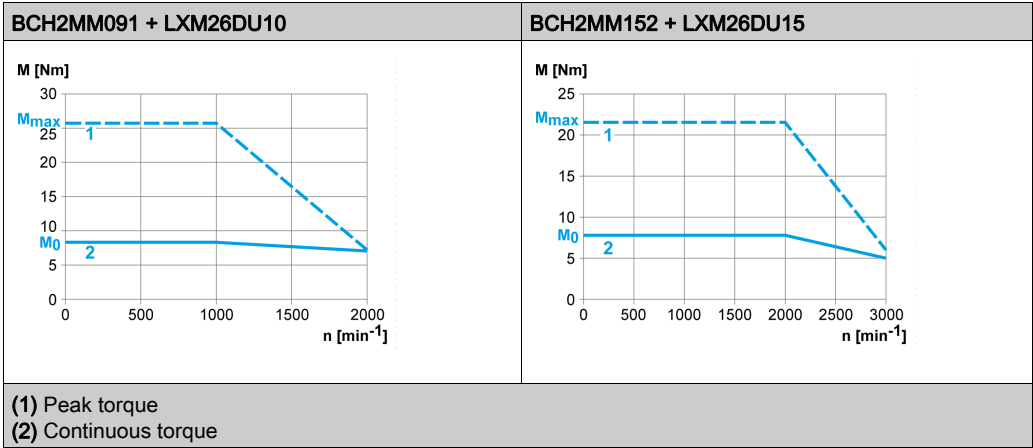
BCH2•M Characteristics Table

BCH2 ⁽¹⁾			MM052	MM031	MM102	HM102	MM081
Technical data - general							
Continuous stall torque ⁽²⁾	M ₀	Nm	2.39	2.86	4.77	4.77	5.39
Peak torque	M _{max}	Nm	7.16	8.59	14.30	14.30	13.80
With supply voltage U _n = 230 Vac							
Nominal speed of rotation	n _N	rpm	2000	1000	2000	2000	1500
Nominal torque	M _N	Nm	2.39	2.86	4.77	4.77	5.39
Nominal Current	I _N	A _{rms}	3.24	2.09	6.29	6.29	6.29
Nominal power	P _N	kW	0.50	0.30	1.00	1.00	0.85
Technical data - electrical							
Maximum winding voltage	U _{max}	Vac	255	255	255	255	255
Maximum winding voltage	U _{max}	Vdc	360	360	360	360	360
Maximum voltage to ground	–	Vac	255	255	255	255	255
Maximum Current	I _{max}	A _{rms}	9.5	6.0	20.0	20.0	15.0
Continuous stall current	I ₀	A _{rms}	2.89	1.88	5.77	5.77	5.62
Voltage constant ⁽³⁾	k _E U-v	V _{rms}	50	92	50	50	58
Torque constant ⁽⁴⁾	k _t	Nm/A	0.83	1.52	0.83	0.83	0.96
Winding resistance	R _{20U-v}	Ω	0.74	2.08	0.74	0.74	0.42
Winding inductance	L _{qU-v}	mH	7.84	26.25	7.84	7.84	4.70
Winding inductance	L _{dU-v}	mH	7.14	23.91	7.14	7.14	4.30
Technical data - mechanical							
Maximum permissible speed of rotation	n _{max}	rpm	3000	2000	3000	3000	3000
Rotor inertia without brake	J _M	kgcm ²	6.63	6.63	6.63	8.41	13.5
Rotor inertia with brake	J _M	kgcm ²	6.91	6.91	6.91	8.54	14.1
Mass without brake	m	kg	7.00	7.00	7.00	7.10	9.60
Mass with brake	m	kg	8.20	8.20	8.20	8.30	10.90
Degree of protection of the shaft	–	–	IP 65	IP 54	IP 65	IP 65	IP 54
Degree of protection of the housing	–	–	IP 65	IP 65	IP 65	IP 65	IP 65
Technical data - holding brake							
Holding torque	–	Nm	9.6	9.6	9.6	9.6	9.6
Nominal voltage	–	Vdc	24 +/-10%	24 +/-10%	24 +/-10%	24 +/-10%	24 +/-10%
Nominal power (electrical pull-in power)	–	W	19.7	19.7	19.7	19.7	19.7
(1) Limit values with flanged motor: ○ Flange material: Steel ○ Flange size in mm (in): 400 x 400 x 20 (15.7 x 15.7 x 0.79) (2) M ₀ =Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At n = 20 rpm and 20 °C (68 °F).							

BCH2 ⁽¹⁾			MM061	MM091	MM152	MM202
Technical data - general						
Continuous stall torque ⁽²⁾	M_0	Nm	5.73	8.59	7.16	9.55
Peak torque	M_{max}	Nm	17.19	25.77	21.48	28.65
With supply voltage $U_n = 230$ Vac						
Nominal speed of rotation	n_N	rpm	1000	1000	2000	2000
Nominal torque	M_N	Nm	5.73	8.59	7.16	9.55
Nominal Current	I_N	A_{rms}	4.10	6.15	6.74	11.25
Nominal power	P_N	kW	0.60	0.90	1.50	2.00
Technical data - electrical						
Maximum winding voltage	U_{max}	Vac	255	255	255	255
Maximum winding voltage	U_{max}	Vdc	360	360	360	360
Maximum voltage to ground	–	Vac	255	255	255	255
Maximum Current	I_{max}	A_{rms}	13.5	20.0	21.0	33.0
Continuous stall current	I_0	A_{rms}	3.77	5.64	6.18	9.95
Voltage constant ⁽³⁾	$k_{E\text{U-V}}$	V_{rms}	92	92	70	58
Torque constant ⁽⁴⁾	k_t	Nm/A	1.52	1.52	1.16	0.96
Winding resistance	$R_{20\text{U-V}}$	Ω	2.08	1.22	0.64	0.42
Winding inductance	$L_{q\text{U-V}}$	mH	26.25	16.40	7.20	4.70
Winding inductance	$L_{d\text{U-V}}$	mH	23.91	14.90	6.40	4.30
Technical data - mechanical						
Maximum permissible speed of rotation	n_{max}	rpm	2000	2000	3000	3000
Rotor inertia without brake	J_M	kgcm ²	6.63	9.70	9.70	13.50
Rotor inertia with brake	J_M	kgcm ²	6.91	10.00	10.00	14.10
Mass without brake	m	kg	7.00	7.60	7.60	9.70
Mass with brake	m	kg	8.20	8.80	8.80	11.00
Technical data - holding brake						
Holding torque	–	Nm	9.6	9.6	9.6	9.6
Nominal voltage	–	Vdc	24 +/-10%	24 +/-10%	24 +/-10%	24 +/-10%
Nominal power (electrical pull-in power)	–	W	19.7	19.7	19.7	19.7
(1) Limit values with flanged motor: ○ Flange material: Steel ○ Flange size in mm (in): 400 x 400 x 20 (15.7 x 15.7 x 0.79) (2) M_0=Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At n = 20 rpm and 20 °C (68 °F).						

BCH2•M Curves





Section 5.8

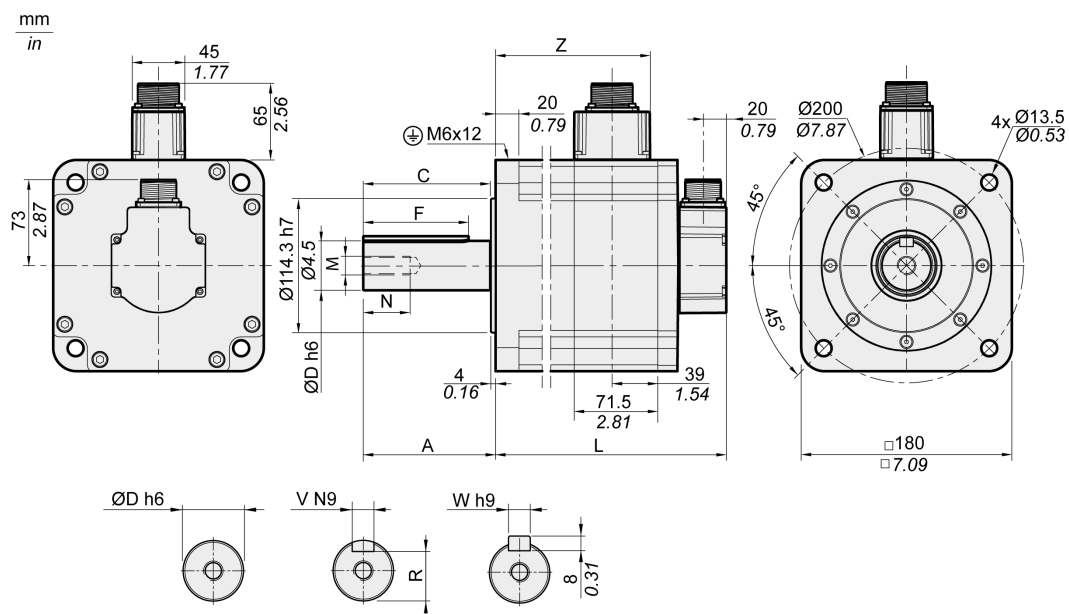
BCH2•R Motor

What Is in This Section?

This section contains the following topics:

Topic	Page
BCH2•R Dimensions	78
BCH2•R Characteristics Table	79
BCH2•R Curves	81

BCH2•R Dimensions



BCH2•R	Unit	20	30, 35	45
L (without holding brake)	mm (in)	168 (6.61)	201 (7.91)	234 (9.21)
L (with holding brake)	mm (in)	203 (7.99)	236 (9.29)	269 (10.59)
A	mm (in)	79 (3.11)	79 (3.11)	79 (3.11)
C	mm (in)	73 (2.87)	73 (2.87)	73 (2.87)
D	mm (in)	35 (1.38)	35 (1.38)	35 (1.38)
F	mm (in)	63 (2.48)	63 (2.48)	63 (2.48)
M	-	M12	M12	M12
N	mm (in)	28 (1.10)	28 (1.10)	28 (1.10)
R	mm (in)	30 (1.18)	30 (1.18)	30 (1.18)
V	mm (in)	10 (0.39)	10 (0.39)	10 (0.39)
W	mm (in)	10 (0.39)	10 (0.39)	10 (0.39)
Z	mm (in)	103 (4.06)	136 (5.35)	169 (6.65)

BCH2•R Characteristics Table

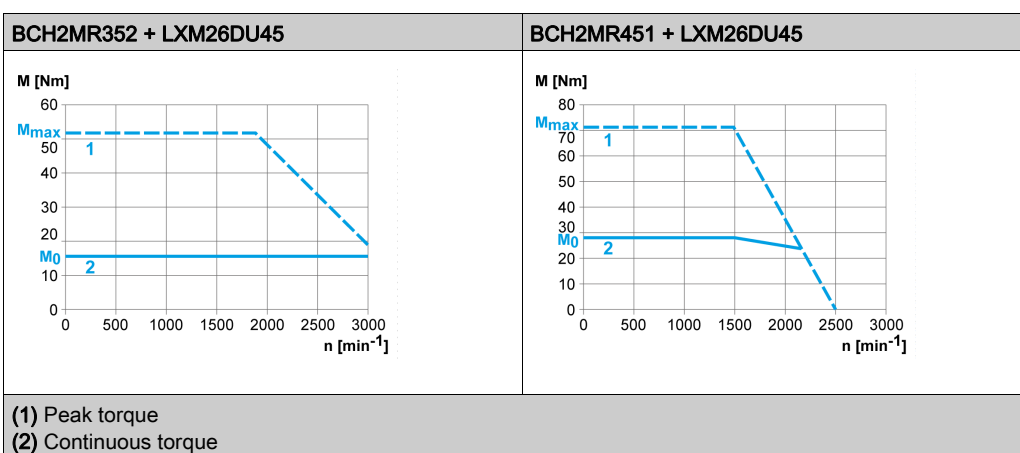
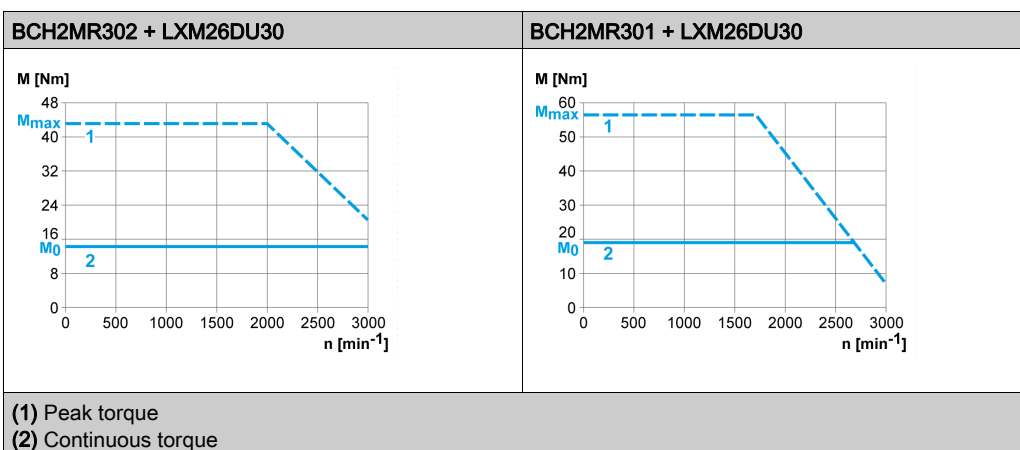
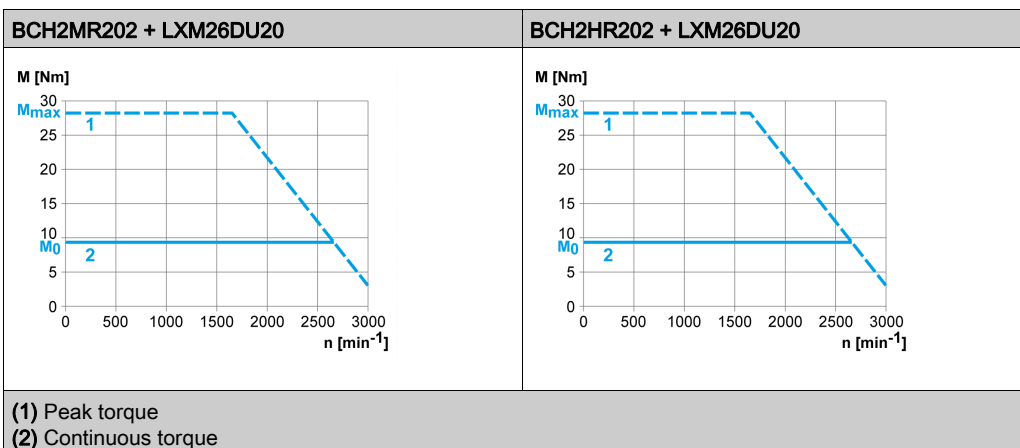
BCH2MR202/301/302, BCH2HR202 technical data

BCH2 ⁽¹⁾			MR202	HR202	MR302	MR301
Technical data - general						
Continuous stall torque ⁽²⁾	M ₀	Nm	9.55	9.55	14.32	19.10
Peak torque	M _{max}	Nm	28.65	28.65	42.97	57.29
With supply voltage U _n = 230 Vac						
Nominal speed of rotation	n _N	rpm	2000	2000	2000	1500
Nominal torque	M _N	Nm	9.55	9.55	14.32	19.10
Nominal Current	I _N	A _{rms}	9.6	9.6	18.8	18.8
Nominal power	P _N	kW	2.00	2.00	3.00	3.00
Technical data - electrical						
Maximum winding voltage	U _{max}	Vac	255	255	255	255
Maximum winding voltage	U _{max}	Vdc	360	360	360	360
Maximum voltage to ground	–	Vac	255	255	255	255
Maximum Current	I _{max}	A _{rms}	35.5	35.5	56.0	61.0
Continuous stall current	I ₀	A _{rms}	8.75	8.75	16.33	16.49
Voltage constant ⁽³⁾	k _E U-V	V _{rms}	66	66	53	70
Torque constant ⁽⁴⁾	k _t	Nm/A	1.09	1.09	0.88	1.16
Winding resistance	R ₂₀ U-V	Ω	0.572	0.572	0.168	0.234
Winding inductance	L _q U-V	mH	6.70	6.70	2.88	3.78
Winding inductance	L _d U-V	mH	6.10	6.10	2.71	3.45
Technical data - mechanical						
Maximum permissible speed of rotation	n _{max}	rpm	3000	3000	3000	3000
Rotor inertia without brake	J _M	kgcm ²	26.50	34.68	53.56	53.56
Rotor inertia with brake	J _M	kgcm ²	27.0	35.13	54.1	54.1
Mass without brake	m	kg	13.00	14.30	18.50	18.50
Mass with brake	m	kg	18.00	19.30	23.00	23.00
Degree of protection of the shaft	–	–	IP 65	IP 65	IP 65	IP 54
Degree of protection of the housing	–	–	IP 65	IP 65	IP 65	IP 65
Technical data - holding brake						
Holding torque	–	Nm	48	48	48	48
Nominal voltage	–	Vdc	24 +/-10%	24 +/-10%	24 +/-10%	24 +/-10%
Nominal power (electrical pull-in power)	–	W	49.6	49.6	49.6	49.6
(1) Limit values with flanged motor: ○ Flange material: Steel ○ Flange size in mm (in): 550 x 550 x 20 (21.7 x 21.7 x 0.79) (2) M ₀ =Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At n = 20 rpm and 20 °C (68 °F).						

BCH2MR352/451/551/751 technical data

BCH2 ⁽¹⁾			MR352	MR451	MR551	MR751
Technical data - general						
Continuous stall torque ⁽²⁾	M ₀	Nm	16.70	28.65	35.01	47.75
Peak torque	M _{max}	Nm	50.30	71.62	87.53	119.37
With supply voltage U _n = 230 Vac						
Nominal speed of rotation	n _N	rpm	2000	1500	1500	1500
Nominal torque	M _N	Nm	16.70	28.65	35.01	47.75
Nominal Current	I _N	A _{rms}	19.3	22.8	28.8	41.5
Nominal power	P _N	kW	3.50	4.50	5.50	7.50
Technical data - electrical						
Maximum winding voltage	U _{max}	Vac	255	255	255	255
Maximum winding voltage	U _{max}	Vdc	360	360	360	360
Maximum voltage to ground	–	Vac	255	255	255	255
Maximum Current	I _{max}	A _{rms}	61.0	61.0	74.2	106.9
Continuous stall current	I ₀	A _{rms}	16.83	19.68	25.05	36.08
Voltage constant ⁽³⁾	k _E U-v	V _{rms}	60	88	84.5	80
Torque constant ⁽⁴⁾	k _t	Nm/A	0.99	1.46	1.40	1.32
Winding resistance	R _{20U-v}	Ω	0.168	0.199	0.104	0.062
Winding inductance	L _q U-v	mH	2.80	4.00	2.25	1.30
Winding inductance	L _d U-v	mH	2.57	3.80	2.07	1.22
Technical data - mechanical						
Maximum permissible speed of rotation	n _{max}	rpm	3000	3000	2700	2700
Rotor inertia without brake	J _M	kgcm ²	53.56	73.32	103.34	142.7
Rotor inertia with brake	J _M	kgcm ²	54.1	73.0	120.2	158.7
Mass without brake	m	kg	18.50	23.64	32	41.7
Mass with brake	m	kg	23.00	28.00	36.5	46.2
Technical data - holding brake						
Holding torque	–	Nm	48	48	50	50
Nominal voltage	–	Vdc	24 +/-10%	24 +/-10%	24 +/-10%	24 +/-10%
Nominal power (electrical pull-in power)	–	W	49.6	49.6	49.6	49.6
(1) Limit values with flanged motor: ○ Flange material: Steel ○ Flange size in mm (in): 550 x 550 x 20 (21.7 x 21.7 x 0.79) (2) M₀=Continuous stall torque at 20 rpm and 100 % duty cycle; at speeds of rotation of <20 rpm the continuous stall torque is reduced to 87 % (3) RMS value at 1000 rpm and 20 °C (68 °F). (4) At n = 20 rpm and 20 °C (68 °F).						

BCH2•R Curves



Chapter 6

Accessories and Spare Parts

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Commissioning Tools	84
Connectors and Adapters	84
External Mains Filters	84
Application Nameplate	85
Motor Cables	86
Encoder Cables	87
Signal Cables	88
External Braking Resistors and Holding Brake Controller	89
Circuit Breakers	90
Motor Protection Switches and Power Contactors	91

Commissioning Tools

Description	Reference
Commissioning software LXM26 DTM Library, can be downloaded at: www.schneider-electric.com	-
PC connection kit, serial connection between drive and PC, USB-A to RJ45	TCSMCNAM3M002P
Multi-Loader, device for copying the parameter settings to a PC or to another drive	VW3A8121
Connection cable for Multi-Loader	VW3A8126
Modbus cable, 1 m (3.28 ft), 2 x RJ45	VW3A8306R10

Connectors and Adapters

Description	Reference
Connector kit for logic supply and power stage supply (~ 220 V), braking resistor (Resistor), and motor (Motor); suitable for LXM26DUA5, LXM26DU01, LXM26DU02, LXM26DU04, LXM26DU07, LXM26DU10, and LXM26DU15	VW3M4C21
Connector kit for logic supply and power stage supply (~ 220 V), braking resistor (Resistor), and motor (Motor); suitable for LXM26DU20	VW3M4C23
Connector kit for logic supply and power stage supply (~ 220 V), braking resistor (Resistor), and motor (Motor); suitable for LXM26DU30 and LXM26DU45	VW3M4C24
Cable shield connection plate, clamps, and screws; suitable for LXM26DUA5, LXM26DU01, LXM26DU02, LXM26DU04, LXM26DU07, LXM26DU10, and LXM26DU15	VW3M2C31
Cable shield connection plate, clamps, and screws; suitable for LXM26DU20	VW3M2C33
Cable shield connection plate, clamps, and screws; suitable for LXM26DU30 and LXM26DU45	VW3M2C34
Interface connector for CN1, 50-pin, 3 pieces	VW3M1C12
Interface adapter for CN1, connector with 0.5 m (1.64 ft) cable and connection module with screw terminals for DIN rail mounting	VW3M1C13
Connector kit for motor; motor end plastic connector without holding brake	VW3M5D1A
Connector kit for motor; motor end plastic connector with holding brake	VW3M5D1F
Connector kit for motor; motor end MIL connector with holding brake, size 100 ... 130	VW3M5D2A
Connector kit for motor; motor end MIL connector with holding brake, size 180	VW3M5D2B
Connector kit for encoder; motor end flying leads; device end IEEE1394 connector	VW3M8D1A
Connector kit for encoder; motor end MIL connector; device end IEEE1394 connector	VW3M8D2A

External Mains Filters

Description	Reference
Mains filter single-phase; 9 A; 115/230 Vac	VW3A4420
Mains filter single-phase; 16 A; 115/230 Vac	VW3A4421
Mains filter single-phase; 23 A; 115/230 Vac	VW3A4426
Mains filter three-phase; 15 A; 208/400/480 Vac	VW3A4422
Mains filter three-phase; 25 A; 208/400/480 Vac	VW3A4423
Mains filter three-phase; 47 A; 208/400/480 Vac	VW3A4424

Application Nameplate

Description	Reference
Application nameplate to be clipped onto the top of the drive, size 38.5 mm (1.52 in) x 13 mm (0.51 in), 50 pieces	VW3M2501

Motor Cables

Description	Reference
Motor cable without holding brake 1.5 m (4.92 ft), 4 x 0.82 mm ² (AWG 18) shielded; motor end plastic connector, other cable end flying leads	VW3M5D1AR15
Motor cable without holding brake 3 m (9.84 ft), 4 x 0.82 mm ² (AWG 18) shielded; motor end plastic connector, other cable end flying leads	VW3M5D1AR30
Motor cable without holding brake 5 m (16.4 ft), 4 x 0.82 mm ² (AWG 18) shielded; motor end plastic connector, other cable end flying leads	VW3M5D1AR50
Motor cable with holding brake 3 m (9.84 ft), 6 x 0.82 mm ² (AWG 18) shielded; motor end plastic connector, other cable end flying leads	VW3M5D1FR30
Motor cable with holding brake 5 m (16.4 ft), 6 x 0.82 mm ² (AWG 18) shielded; motor end plastic connector, other cable end flying leads	VW3M5D1FR50
Motor cable without holding brake 3 m (9.84 ft), 4 x 1.3 mm ² (AWG 16) shielded; motor end MIL connector, other cable end flying leads	VW3M5D2AR30
Motor cable without holding brake 5 m (16.4 ft), 4 x 1.3 mm ² (AWG 16) shielded; motor end MIL connector, other cable end flying leads	VW3M5D2AR50
Motor cable with holding brake 3 m (9.84 ft), 6 x 1.3 mm ² (AWG 16) shielded; motor end MIL connector, other cable end flying leads	VW3M5D2FR30
Motor cable with holding brake 5 m (16.4 ft), 6 x 1.3 mm ² (AWG 16) shielded; motor end MIL connector, other cable end flying leads	VW3M5D2FR50
Motor cable without holding brake 3 m (9.84 ft), 4 x 3.3 mm ² (AWG 12) shielded; motor end MIL connector, other cable end flying leads	VW3M5D4AR30
Motor cable without holding brake 5 m (16.4 ft), 4 x 3.3 mm ² (AWG 12) shielded; motor end MIL connector, other cable end flying leads	VW3M5D4AR50
Motor cable with holding brake 3 m (9.84 ft), 6 x 3.3 mm ² (AWG 12) shielded; motor end MIL connector, other cable end flying leads	VW3M5D4FR30
Motor cable with holding brake 5 m (16.4 ft), 6 x 3.3 mm ² (AWG 12) shielded; motor end MIL connector, other cable end flying leads	VW3M5D4FR50
Motor cable without holding brake 3 m (9.84 ft), 4 x 6 mm ² (AWG 10) shielded; motor end MIL connector, other cable end flying leads	VW3M5D6AR30
Motor cable without holding brake 5 m (16.4 ft), 4 x 6 mm ² (AWG 10) shielded; motor end MIL connector, other cable end flying leads	VW3M5D6AR50
Motor cable with holding brake 3 m (9.84 ft), 6 x 6 mm ² (AWG 10) shielded; motor end MIL connector, other cable end flying leads	VW3M5D6FR30
Motor cable with holding brake 5 m (16.4 ft), 6 x 6 mm ² (AWG 10) shielded; motor end MIL connector, other cable end flying leads	VW3M5D6FR50

Encoder Cables

Description	Reference
Encoder cable 1.5 m (4.92 ft), 10 x 0.13 mm ² (AWG 26) shielded; motor end and device end plastic connector	VW3M8D1AR15
Encoder cable 3 m (9.84 ft), 10 x 0.13 mm ² (AWG 26) shielded; motor end and device end plastic connector	VW3M8D1AR30
Encoder cable 5 m (16.4 ft), 10 x 0.13 mm ² (AWG 26) shielded; motor end and device end plastic connector	VW3M8D1AR50
Encoder cable 3 m (9.84 ft), 10 x 0.13 mm ² (AWG 26) shielded; motor end MIL connector, other cable end plastic connector	VW3M8D2AR30
Encoder cable 5 m (16.4 ft), 10 x 0.13 mm ² (AWG 26) shielded; motor end MIL connector, other cable end plastic connector	VW3M8D2AR50

Signal Cables

Description	Reference
Signal cable 1 m (3.28 ft) for signal interface CN1, device end 50-pin connector, other cable end flying leads	VW3M1C10R10
Signal cable 2 m (6.56 ft) for signal interface CN1, device end 50-pin connector, other cable end flying leads	VW3M1C10R20
Signal cable 3 m (9.84 ft) for signal interface CN1, device end 50-pin connector, other cable end flying leads	VW3M1C10R30

External Braking Resistors and Holding Brake Controller

Description	Reference
Holding brake controller HBC with automatic voltage reduction; 24 V - 1.6 A	VW3M3103
Braking resistor IP 65; 10 Ω; maximum continuous power 400 W; 0.75 m (2.46 ft) connection cable, 2.1 mm ² (AWG 14)	VW3A7601R07
Braking resistor IP 65; 10 Ω; maximum continuous power 400 W; 2 m (6.56 ft) connection cable, 2.1 mm ² (AWG 14)	VW3A7601R20
Braking resistor IP 65; 10 Ω; maximum continuous power 400 W; 3 m (9.84 ft) connection cable, 2.1 mm ² (AWG 14)	VW3A7601R30
Braking resistor IP 65; 27 Ω; maximum continuous power 100 W; 0.75 m (2.46 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7602R07
Braking resistor IP 65; 27 Ω; maximum continuous power 100 W; 2 m (6.56 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7602R20
Braking resistor IP 65; 27 Ω; maximum continuous power 100 W; 3 m (9.84 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7602R30
Braking resistor IP 65; 27 Ω; maximum continuous power 200 W; 0.75 m (2.46 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7603R07
Braking resistor IP 65; 27 Ω; maximum continuous power 200 W; 2 m (6.56 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7603R20
Braking resistor IP 65; 27 Ω; maximum continuous power 200 W; 3 m (9.84 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7603R30
Braking resistor IP 65; 27 Ω; maximum continuous power 400 W; 0.75 m (2.46 ft) connection cable, 2.1 mm ² (AWG 14)	VW3A7604R07
Braking resistor IP 65; 27 Ω; maximum continuous power 400 W; 2 m (6.56 ft) connection cable, 2.1 mm ² (AWG 14)	VW3A7604R20
Braking resistor IP 65; 27 Ω; maximum continuous power 400 W; 3 m (9.84 ft) connection cable, 2.1 mm ² (AWG 14)	VW3A7604R30
Braking resistor IP 65; 72 Ω; maximum continuous power 200 W; 0.75 m (2.46 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7606R07
Braking resistor IP 65; 72 Ω; maximum continuous power 200 W; 2 m (6.56 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7606R20
Braking resistor IP 65; 72 Ω; maximum continuous power 200 W; 3 m (9.84 ft) connection cable, 2.1 mm ² (AWG 14), UL	VW3A7606R30
Braking resistor IP 65; 72 Ω; maximum continuous power 400 W; 0.75 m (2.46 ft) connection cable	VW3A7607R07
Braking resistor IP 65; 72 Ω; maximum continuous power 400 W; 2 m (6.56 ft) connection cable	VW3A7607R20
Braking resistor IP 65; 72 Ω; maximum continuous power 400 W; 3 m (9.84 ft) connection cable	VW3A7607R30
Braking resistor IP20; 15 Ω; maximum continuous power 1000 W; M6 terminals, UL	VW3A7704
Braking resistor IP20; 10 Ω; maximum continuous power 1000 W; M6 terminals, UL	VW3A7705

Circuit Breakers

Description	Reference
Circuit breaker - thermal magnetic - 4 ... 6.3 A - screw terminals	GV2P10
Circuit breaker - thermal magnetic - 6 ... 10 A - screw terminals	GV2P14
Circuit breaker - thermal magnetic - 9 ... 14 A - screw terminals	GV2P16
Circuit breaker - thermal magnetic - 13 ... 18 A - screw terminals	GV2P20
Circuit breaker - thermal magnetic - 17 ... 23 A - screw terminals	GV2P21
Circuit breaker - thermal magnetic - 20 ... 25 A - screw terminals	GV2P22
Circuit breaker - thermal magnetic - 24 ... 32 A - screw terminals	GV2P32

Motor Protection Switches and Power Contactors

Drive	Nominal power	Order no. motor protection switch	Rated continuous current motor protection switch	Order no. power contactor
LXM26DUA5	50 W	GV2L10	6.3 A	LC1K0610••
LXM26DU01	100 W	GV2L10	6.3 A	LC1K0610••
LXM26DU02	200 W	GV2L14	10 A	LC1D09••
LXM26DU04	400 W	GV2L14	10 A	LC1D09••
LXM26DU07	750 W	GV2L16	14 A	LC1D12••
LXM26DU15	1500 W	GV2L22	25 A	LC1D18••
LXM26DU20	2000 W	GV2L32	30 A	LC1D32••
LXM26DU30	3000 W	GV2L32	30 A	LC1D32••

Control voltage power contactor		24 V	48 V	110 V	220 V	230 V	240 V
LC1K••••	50/60 Hz	B7	E7	F7	M7	P7	U7

Control voltage power contactor		24 V	48 V	110 V	220/230 V	230	230/240 V
LC1D••••	50 Hz	B5	E5	F5	M5	P5	U5
	60 Hz	B6	E&	F6	M6	-	U6
	50/60 Hz	B7	E7	F7	M7	P7	U7

Part III

Engineering

Chapter 7

Engineering

This chapter contains information on the application of the Servo Drive system for the engineering phase.

What Is in This Chapter?

This chapter contains the following sections:

Section	Topic	Page
7.1	Electromagnetic Compatibility (EMC)	96
7.2	Cables	100
7.3	Residual Current Device	102
7.4	Rating the Braking Resistor	103
7.5	Monitoring Functions	107
7.6	Configurable Inputs and Outputs	108
7.7	Wiring	109

Section 7.1

Electromagnetic Compatibility (EMC)

What Is in This Section?

This section contains the following topics:

Topic	Page
Electromagnetic Compatibility (EMC)	97
External Mains Filters	99

Electromagnetic Compatibility (EMC)

Signal interference can cause unexpected responses of the drive and of other equipment in the vicinity of the drive.

⚠ WARNING
SIGNAL AND EQUIPMENT INTERFERENCE • Only operate the drive with the specified external mains filter. • Install the wiring in accordance with the EMC requirements described in the present document. • Verify compliance with the EMC requirements described in the present document. • Verify compliance with all EMC regulations and requirements applicable in the country in which the product is to be operated and with all EMC regulations and requirements applicable at the installation site. Failure to follow these instructions can result in death, serious injury, or equipment damage.

Limit Values

This product meets the EMC requirements according to the standard IEC 61800-3 if the measures described in this manual, and in particular the installation of the mains filters, are implemented during installation.

⚠ WARNING
ELECTROMAGNETIC DISTURBANCES OF SIGNALS AND DEVICES Use proper EMC shielding techniques to help prevent unintended device operation in accordance with the standard IEC 61800-3. Failure to follow these instructions can result in death, serious injury, or equipment damage.

These types of devices are not intended to be used on a low-voltage public network which supplies domestic premises. Radio frequency interference is expected if used in such a network.

⚠ WARNING
RADIO INTERFERENCE Do not use these products in domestic electrical networks. Failure to follow these instructions can result in death, serious injury, or equipment damage.

As a system provider, you may have to include this information in the documentation to your customer.

Equipotential Bonding Conductor

Potential differences can result in excessive currents on the cable shields. Use equipotential bonding conductors to reduce currents on the cable shields.

⚠ WARNING
UNINTENDED EQUIPMENT OPERATION • Ground cable shields for all fast I/O, analog I/O, and communication signals at a single point. ¹⁾ • Route communications and I/O cables separately from power cables. Failure to follow these instructions can result in death, serious injury, or equipment damage.

¹⁾ Multipoint grounding is permissible if connections are made to an equipotential ground plane dimensioned to help avoid cable shield damage in the event of power system short-circuit currents.

The equipotential bonding conductor must be rated for the maximum current. The following conductor cross sections can be used:

- 16 mm² (AWG 4) for equipotential bonding conductors up to a length of 200 m (656 ft)
- 20 mm² (AWG 4) for equipotential bonding conductors with a length of more than 200 m (656 ft)

EMC Requirements for the Control Cabinet

EMC measures	Objective
Use mounting plates with good electrical conductivity, connect large surface areas of metal parts, remove paint from contact areas.	Good conductivity due to large surface contact.
Ground the control cabinet, the control cabinet door, and the mounting plate with ground straps or ground wires. The conductor cross section must be at least 10 mm ² (AWG 6).	Reduces emissions.
Install switching devices such as power contactors, relays, or solenoid valves with interference suppression units or arc suppressors (for example, diodes, varistors, RC circuits).	Reduces mutual interference
Do not install power components and control components adjacent to one another.	Reduces mutual interference

Additional Measures for EMC Improvement

Depending on the application, the following measures can improve the EMC-dependent values:

EMC measures	Objective
Use mains reactors.	Reduces mains harmonics, prolongs product service life.
Mount in a closed control cabinet with shielded attenuation of radiated interference	Improves the EMC limit values.

External Mains Filters

Filter/Drive Combinations

You can obtain EMC conformance by following the wiring standards and practices in the present document and installing, for each drive, the following filter/drive combination:

For further information, refer to Electromagnetic compatibility (EMC) (*see page 96*).

LXM26D	Mains filter for single-phase connection	Mains filter for three-phase connection
UA5 = 0.05 kW U01 = 0.1 kW U02 = 0.2 kW U04 = 0.4 kW U07 = 0.75 kW U10 = 1 kW	VW3A4420	VW3A4422
U15 = 1.5 kW	VW3A4421	VW3A4422
U20 = 2 kW	-	VW3A4423
U30 = 3 kW U45 = 4.5 kW	-	VW3A4424

If you use mains filters of other manufacturers, these mains filters must have the same technical data as specified mains filters.

Emission

The specified limit values are complied with if the external mains filters available as accessories are used.

The following limit values for emission are complied with if the installation is EMC-compliant and if the cables offered as accessories are used.

Lexium 26D	Category
Conducted interference	C3
Radiated emission	C3

Section 7.2

Cables

Cables

Suitability of the Cables

Cables must not be twisted, stretched, crushed, or bent. Use only cables that comply with the cable specification. Consider the following in determining suitability of the cables:

- Suitable for drag chain applications
- Temperature range
- Chemical resistance
- Outdoor installation
- Underground installation

Equipotential Bonding Conductors

Potential differences can result in excessive currents on the cable shields. Use equipotential bonding conductors to reduce currents on the cable shields

 WARNING	
UNINTENDED EQUIPMENT OPERATION	
• Ground cable shields for all fast I/O, analog I/O, and communication signals at a single point. ¹⁾ • Route communications and I/O cables separately from power cables.	
Failure to follow these instructions can result in death, serious injury, or equipment damage.	

¹⁾ Multipoint grounding is permissible if connections are made to an equipotential ground plane dimensioned to help avoid cable shield damage in the event of power system short-circuit currents.

The equipotential bonding conductor must be rated for the maximum current. The following conductor cross sections can be used:

- 16 mm² (AWG 4) for equipotential bonding conductors up to a length of 200 m (656 ft)
- 20 mm² (AWG 4) for equipotential bonding conductors with a length of more than 200 m (656 ft)

Conductor Cross Sections According to Method of Installation

The following sections describe the conductor cross sections for two methods of installation:

- Method of installation B2:
Cables in conduits or cable trunking systems
- Method of installation E:
Cables on open cable trays

Cross section in mm ² (AWG) ⁽¹⁾	Current-carrying capacity with method of installation B2 in A ⁽²⁾	Current carrying capacity with method of installation E in A ⁽²⁾
0.75 (18)	8.5	10.4
1 (16)	10.1	12.4
1.5 (14)	13.1	16.1
2.5 (12)	17.4	22
4 (10)	23	30
6 (8)	30	37
10 (6)	40	52

⁽¹⁾ See chapter "Accessories and spare parts" ([see page 83](#)) for available cables.

⁽²⁾ Values as per IEC 60204-1 for continuous operation, copper conductors, and ambient air temperature 40 °C (104 °F); see IEC 60204-1 for additional information.

Cross section in mm ² (AWG) ⁽¹⁾	Current-carrying capacity with method of installation B2 in A ⁽²⁾	Current carrying capacity with method of installation E in A ⁽²⁾
16 (4)	54	70
25 (2)	70	88
(1) See chapter “Accessories and spare parts” (see page 83) for available cables. (2) Values as per IEC 60204-1 for continuous operation, copper conductors, and ambient air temperature 40 °C (104 °F); see IEC 60204-1 for additional information.		

Note the derating factors for grouping of cables and correction factors for other ambient conditions (IEC 60204-1).

The conductors must have a sufficiently large cross section so that the upstream fuse can trip.

In the case of longer cables, it may be necessary to use a greater conductor cross section to reduce the energy losses.

For conformance to UL requirements, use 75 °C (167 °F) copper conductors.

Section 7.3

Residual Current Device

Residual Current Device

Direct current can be introduced in the protective ground conductor of this drive. If a residual current device (RCD / GFCI) or a residual current monitor (RCM) is used for protection against direct or indirect contact, the following specific types must be used:

WARNING

DIRECT CURRENT CAN BE INTRODUCED INTO THE PROTECTIVE GROUND CONDUCTOR

- Use a Type A Residual Current Device (RCD / GFCI) or a Residual Current Monitor (RCM) for single-phase drives connected to a phase and to the neutral conductor.
- Use a Type B Residual Current Device (RCD / GFCI) or a Residual Current Monitor (RCM) that has approval for use with frequency inverters and is sensitive to all types of current for three-phase drives and for single-phase drives not connected to a phase and the neutral conductor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Conditions for Use of Residual Current Device

- The drive has an increased leakage current at the moment power is applied. Use residual current devices with a response delay.
- High-frequency currents must be filtered.

Section 7.4

Rating the Braking Resistor

What Is in This Section?

This section contains the following topics:

Topic	Page
Rating the Braking Resistor	104
Internal Braking Resistor	105
External Braking Resistors	106

Rating the Braking Resistor

Braking resistors are required for dynamic applications. During deceleration, the kinetic energy is transformed into electrical energy in the motor. The electrical energy increases the DC bus voltage. The braking resistor is activated when the defined threshold value is exceeded. The braking resistor transforms electrical energy into heat. If highly dynamic deceleration is required, the braking resistor must be well adapted to the system. External driving forces acting on the motor can cause high currents to be regenerated and supplied back to the drive.

DANGER

FIRE DUE TO EXTERNAL DRIVING FORCES ACTING ON MOTOR

Verify that no external forces can act on the motor that will exceed the capacity of the braking resistor.

Failure to follow these instructions will result in death or serious injury.

An insufficiently rated braking resistor can cause overvoltage on the DC bus. Overvoltage on the DC bus causes the power stage to be disabled. The motor is no longer actively decelerated.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Verify that the braking resistor has a sufficient rating by performing a test run under maximum load conditions.
- Verify that the parameter settings for the braking resistor are correct.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

An external braking resistor ([see page 89](#)) is required for applications in which the motor must be decelerated quickly and the internal braking resistor cannot absorb the excess braking energy.

Internal Braking Resistor

Introduction

The drive has an internal braking resistor. If the internal braking resistor is insufficient for the dynamics of the application, one or more external braking resistors must be used.

The resistance values for external braking resistors must not be below the specified minimum resistance. If an external braking resistor is activated by using the appropriate parameter, the internal braking resistor is deactivated.

LXM26D	Unit	UA5	U01	U02	U04	U07
Resistance value of internal braking resistor	Ω	100	100	100	100	40
Continuous power internal braking resistor P_{PR}	W	60	60	60	60	60
Peak energy $E_{CR}^{(1)}$	Ws	152	152	152	152	380
External braking resistor minimum	Ω	25	25	25	25	25
External braking resistor maximum ⁽²⁾	Ω	50	50	50	50	50
Maximum continuous power external braking resistor	W	640	640	640	640	640
Switch-on voltage braking resistor	V	390	390	390	390	390
Capacitance of the internal capacitors	μF	820	820	820	820	820
Energy absorption of internal capacitors E_{var} at nominal voltage 230 V +10%	Ws	8.87	8.87	8.87	8.87	8.87
(1) Parameter P1-71 is set to 100 ms.						
(2) The maximum specified braking resistor can derate the peak power of the device. Depending on the application, it is possible to use a greater ohm resistor.						

LXM26D	Unit	U10	U15	U20	U30	U45
Resistance value of internal braking resistor	Ω	40	40	40	22	22
Continuous power internal braking resistor P_{PR}	W	60	60	60	100	100
Peak energy $E_{CR}^{(1)}$	Ws	380	380	380	691	691
External braking resistor minimum	Ω	15	15	8	8	8
External braking resistor maximum ⁽²⁾	Ω	50	50	25	25	25
Maximum continuous power external braking resistor	W	1000	1000	1500	2500	2500
Switch-on voltage braking resistor	V	390	390	390	390	390
Capacitance of the internal capacitors	μF	1640	1640	2110	3280	3280
Energy absorption of internal capacitors E_{var} at nominal voltage 230 V +10%	Ws	17.76	17.76	22.82	35.51	35.51
(1) Parameter P1-71 is set to 100 ms.						
(2) The maximum specified braking resistor can derate the peak power of the device. Depending on the application, it is possible to use a greater ohm resistor.						

External Braking Resistors

Introduction

An external braking resistor is required for applications in which the motor must be decelerated quickly and the internal braking resistor cannot absorb the excess braking energy. The temperature of the braking resistor may exceed 250 °C (482 °F) during operation.

WARNING

HOT SURFACES

- Ensure that it is not possible to make any contact with a hot braking resistor.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of the braking resistor.
- Verify that the heat dissipation is sufficient by performing a test run under maximum load conditions.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

VW3A760•	Unit	1R.. (1)	2R..	3R..	4R.. (1)	5R..	6R..	7R.. (1)
Resistance	Ω	10	27			72		
Continuous power	W	400	100	200	400	100	200	400
Maximum time in braking at 115 V / 230 V	s	0.72	0.552	1.08	2.64	1.44	3.72	9.6
Peak power at 115 V / 230 V	kW	18.5	6.8			2.6		
Maximum peak energy at 115 V / 230 V	Ws	13300	3800	7400	18100	3700	9600	24700
Degree of protection	-	IP 65						
(1) Resistors with a continuous power of 400 W are not UL/CSA-approved.								

VW3A77•	Unit	04	05
Resistance	Ω	15	10
Continuous power	W	1000	
Maximum time in braking at 115 V / 230 V	s	3.5	1.98
Peak power at 115 V / 230 V	kW	12.3	18.5
Maximum peak energy at 115 V / 230 V	Ws	43100	36500
Degree of protection	-	IP20	

Section 7.5

Monitoring Functions

Monitoring Functions

Overview

The monitoring functions of the drive can be used to monitor movements and to monitor internal signals. These monitoring functions are not safety-related functions.

The following monitoring functions are available:

Monitoring function	Task
Data connection	Monitors data connection for interruption
Limit switch signals	Monitors for permissible movement range
Position deviation	Monitors for difference between actual position and reference position
Motor overload	Monitors for excessively high current in the motor phases
Overvoltage and undervoltage	Monitors for overvoltage and undervoltage of the power stage supply and the DC bus
Overtemperature	Monitors the drive for overtemperature
Encoder overtemperature	Monitors the encoder for overtemperature
Overvoltage and undervoltage	Monitors the logic supply and power stage supply for permissible voltage range
Overvoltage at digital inputs	Monitors the digital inputs for overvoltage
Wire break HPULSE inputs	Monitors the HPULSE inputs for wire break
Power supply encoder	Monitors the encoder supply for short circuit and permissible voltage range
Current limitation (Foldback)	Power limitation in the case of overloads for the motor, the output current, the output power, and the braking resistor.

Section 7.6

Configurable Inputs and Outputs

Configurable Inputs and Outputs

Presentation

This drive has digital inputs and outputs that can be configured. The inputs and outputs have a defined default assignment depending on the operating mode. This assignment can be adapted to the requirements of the customer's installation.

For further details, refer to chapter Operation (*see page 267*).

Section 7.7

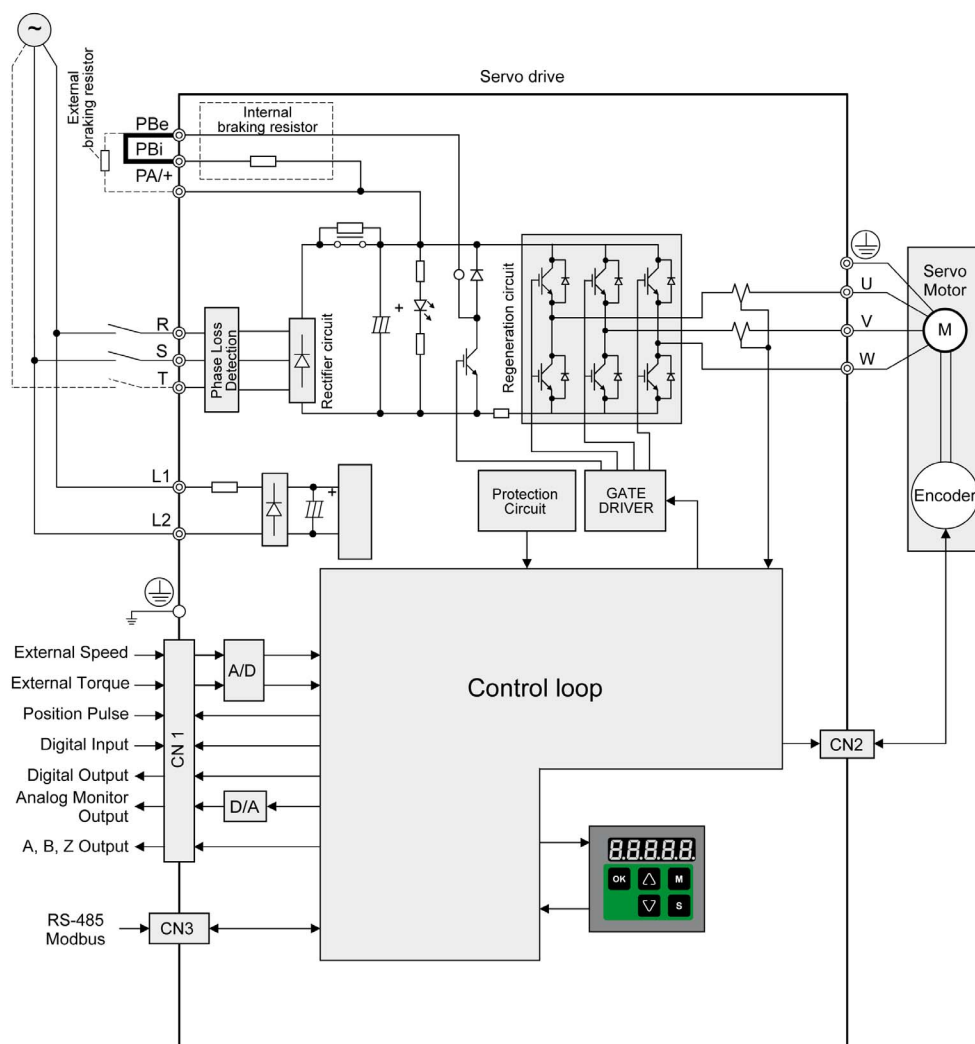
Wiring

What Is in This Section?

This section contains the following topics:

Topic	Page
General Wiring	110
I/O Wiring Example With Modicon M221 Logic Controller	111

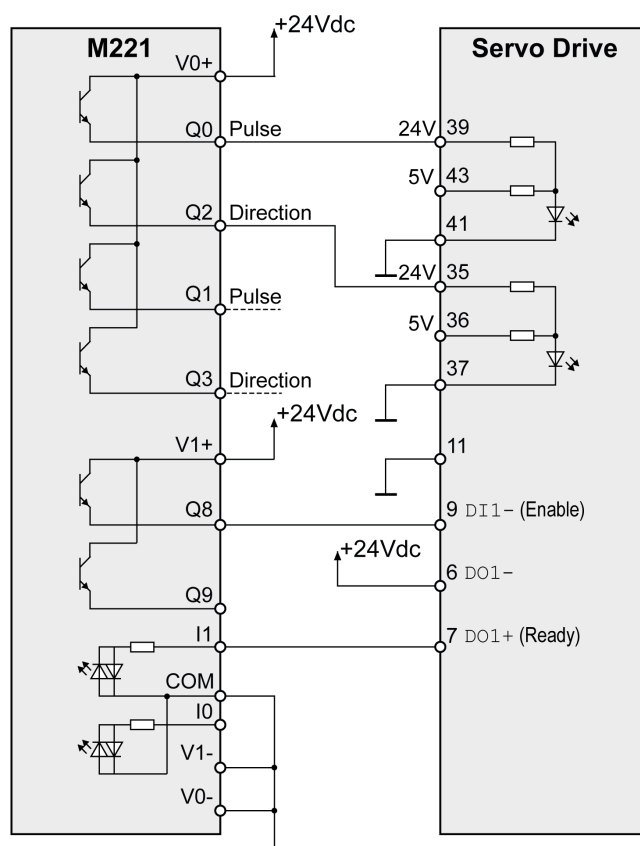
General Wiring



I/O Wiring Example With Modicon M221 Logic Controller

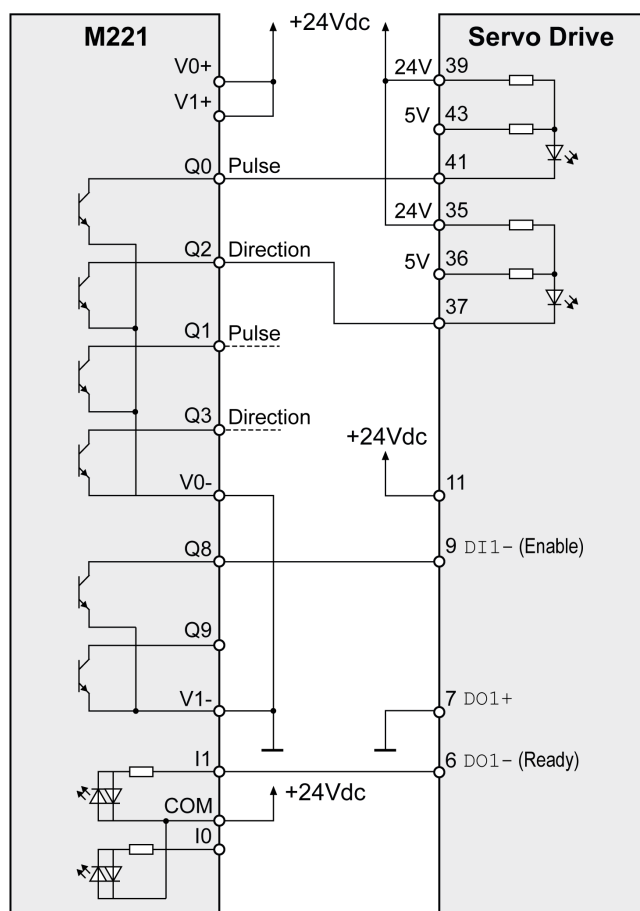
Positive Logic

Wiring example with Modicon M221 Logic Controller (positive logic).



Negative Logic

Wiring example with Modicon M221 Logic Controller (negative logic).



Part IV

Installation

Introduction

An engineering phase is mandatory prior to mechanical and electrical installation. For basic information, refer to Engineering (*see page 95*).

DANGER

INSUFFICIENT GROUNDING

- Use a protective ground conductor with at least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals.
- Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of the entire drive system.
- Ground the drive system before applying voltage.
- Do not use conduits as protective ground conductors; use a protective ground conductor inside the conduit.
- Do not use cable shields as protective ground conductors.
- Keep foreign objects from getting into the product.
- Verify the correct seating of seals and cable entries in order to avoid contamination such as deposits and humidity.

Failure to follow these instructions will result in death or serious injury.

In the case of a ground error, the maximum permissible current in the motor phases may be exceeded.

DANGER

FIRE CAUSED BY INCORRECT INSTALLATION

Use upstream, external ground error detection equipment (Residual Current Device / Ground Fault Circuit Interrupter).

Failure to follow these instructions will result in death or serious injury.

WARNING

LOSS OF CONTROL

- The designer of any control scheme must consider the potential failure modes of control paths and, for certain critical control functions, provide a means to achieve a safe state during and after a path failure. Examples of critical control functions are emergency stop and overtravel stop, power outage and restart.
- Separate or redundant control paths must be provided for critical control functions.
- System control paths may include communication links. Consideration must be given to the implications of unanticipated transmission delays or failures of the link.
- Observe all accident prevention regulations and local safety guidelines.¹
- Each implementation of this equipment must be individually and thoroughly tested for proper operation before being placed into service.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

¹ For additional information, refer to NEMA ICS 1.1 (latest edition), “Safety Guidelines for the Application, Installation, and Maintenance of Solid State Control” and to NEMA ICS 7.1 (latest edition), “Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable-Speed Drive Systems” or their equivalent governing your particular location.

Conductive foreign objects, dust or liquids may cause safety functions to become inoperative.

WARNING

LOSS OF SAFETY FUNCTION CAUSED BY FOREIGN OBJECTS

Protect the system against contamination by conductive substances.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The metal surfaces of the product may exceed 70 °C (158 °F) during operation.

WARNING

HOT SURFACES

- Avoid unprotected contact with hot surfaces.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of hot surfaces.
- Verify that the heat dissipation is sufficient by performing a test run under maximum load conditions.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

CAUTION

INOPERABLE EQUIPMENT DUE TO INCORRECT MAINS VOLTAGE CONNECTION

- Verify that you use the correct mains voltage; install a transformer, if necessary.
- Do not connect mains voltage to the output terminals (U, V, W).

Failure to follow these instructions can result in injury or equipment damage.

What Is in This Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
8	Before Mounting	115
9	Drive Installation	119
10	Motor Installation	149
11	Verifying Installation	159

Chapter 8

Before Mounting

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Inspecting the Product	116
Scope of Supply	117

Inspecting the Product

Inspecting the Product

- Verify the product version by means of the type code on the nameplate. Refer to chapter Nameplate (*see page 30*) and chapter Type Code (*see page 31*).
- Prior to mounting, inspect the product for visible damage.

Damaged products may cause electric shock or unintended equipment operation.



ELECTRIC SHOCK OR UNINTENDED EQUIPMENT OPERATION

- Do not use damaged products.
- Keep foreign objects (such as chips, screws or wire clippings) from getting into the product.

Failure to follow these instructions will result in death or serious injury.

Contact your local Schneider Electric representative if you detect any damage whatsoever to the products.

Scope of Supply

Drive

- Drive Lexium 26D
- Connector kit with 3 connectors for:
 - Power stage supply and logic supply
 - Braking resistor
 - Including jumper between **PBi** and **PBe**
 - Motor
- Plastic tool for opening the spring terminals (available for devices from 50 W to 1.5 kW)
- Adhesive hazard label (Chinese)
- Instruction sheet for the product

Motor

- BCH2 servo motor
- BCH2•R: 2 eyebolts
- Information sheet for the product

Chapter 9

Drive Installation

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Mechanical Installation Drive	120
Electrical Installation Drive	122
Connection Grounding Screw	124
Connection I/O Interface (CN1)	125
Connecting the Motor Encoder (CN2)	137
Connection PC (CN3)	139
Connection Logic Supply and Power Stage Supply (~220V)	141
Connection Braking Resistor (Resistor)	144
Connecting the Motor Phases (Motor)	146
Holding Brake Connection	148

Mechanical Installation Drive

DANGER

ELECTRIC SHOCK OR UNINTENDED EQUIPMENT OPERATION

- Keep foreign objects from getting into the product.
- Verify the correct seating of seals and cable entries in order to avoid contamination such as deposits and humidity.

Failure to follow these instructions will result in death or serious injury.

Conductive foreign objects, dust or liquids may cause safety functions to become inoperative.

WARNING

LOSS OF SAFETY FUNCTION CAUSED BY FOREIGN OBJECTS

Protect the system against contamination by conductive substances.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The metal surfaces of the product may exceed 70 °C (158 °F) during operation.

WARNING

HOT SURFACES

- Avoid unprotected contact with hot surfaces.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of hot surfaces.
- Verify that the heat dissipation is sufficient by performing a test run under maximum load conditions.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Attaching a Hazard Label with Safety Instructions

Included in the packaging of the drive are adhesive hazard labels in Chinese language. The English version is affixed to the drive by the factory. If the country to which your final machine or process is to be delivered is other than English speaking:

- Select the hazard label suitable for the target country.
Respect the safety regulations in the target country.
- Attach the hazard label to the front of the device so that it is clearly visible.

Control Cabinet

The control cabinet (enclosure) must have a sufficient size so that all devices and components can be permanently installed and wired in compliance with the EMC requirements.

The ventilation of the control cabinet must be sufficient to comply with the specified ambient conditions for the devices and components operated in the control cabinet.

Install and operate this equipment in a control cabinet rated for its intended environment and secured by a keyed or tooling locking mechanism.

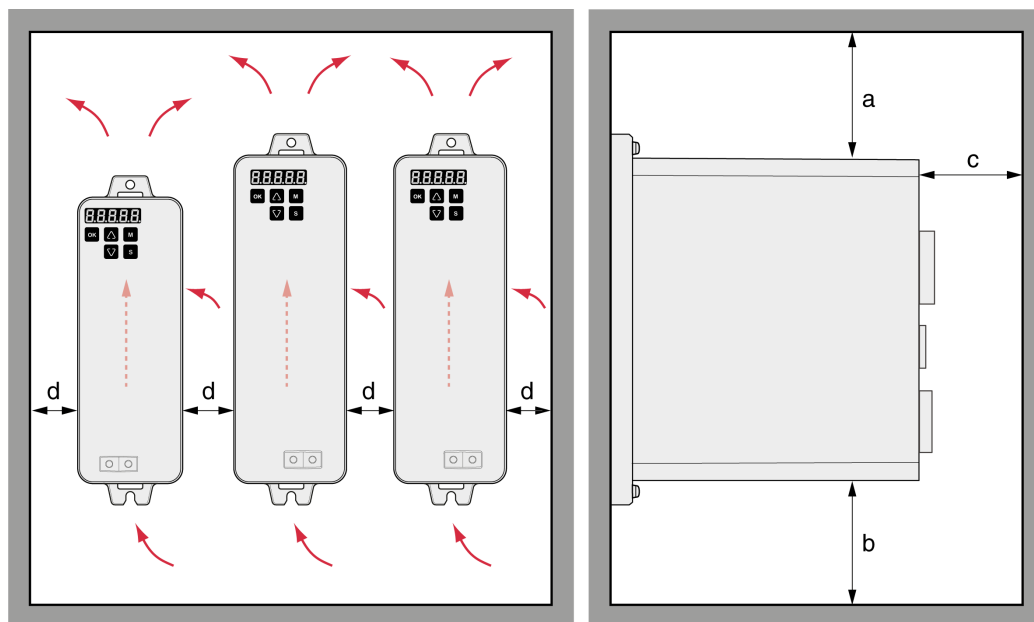
Mounting Distances, Ventilation

When selecting the position of the device in the control cabinet, note the following:

- Mount the device in a vertical position ($\pm 10^\circ$). This is required for cooling the device.
- Adhere to the minimum installation distances for required cooling. Avoid heat accumulations.
- Do not mount the device close to heat sources.
- Do not mount the device on or near flammable materials.
- The heated airflow from other devices and components must not heat up the air used for cooling the device.

The connection cables of the devices are routed to the top and to the bottom. The minimum distances must be adhered to for air circulation and cable installation.

Mounting distances and air circulation



Distance	Unit	Value
Free space a above the device	mm (in)	≥50 (≥1.97)
Free space b below the device	mm (in)	≥50 (≥1.97)
Free space c in front of the device ⁽¹⁾	mm (in)	≥60 (≥2.36)
Free space d between devices	mm (in)	≥15 (≥0.59)
(1) The free space is strictly for observing proper ventilation and may not be sufficient for your wiring requirements.		

Mounting the Drive

See chapter Dimensions ([see page 35](#)) for the dimensions of the mounting holes.

Painted surfaces may create electrical resistance or isolation. Before mounting the device to a painted mounting plate, remove all paint across a large area of the mounting points.

- Respect the ambient conditions in chapter Environmental Conditions ([see page 33](#)).
- Mount the device in a vertical position ($\pm 10^\circ$).

Electrical Installation Drive

Introduction

⚡ ⚠ DANGER

INSUFFICIENT GROUNDING

- Use a protective ground conductor with at least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals.
- Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of the entire drive system.
- Ground the drive system before applying voltage.
- Do not use conduits as protective ground conductors; use a protective ground conductor inside the conduit.
- Do not use cable shields as protective ground conductors.
- Keep foreign objects from getting into the product.
- Verify the correct seating of seals and cable entries in order to avoid contamination such as deposits and humidity.

Failure to follow these instructions will result in death or serious injury.

Direct current can be introduced in the protective ground conductor of this drive. If a residual current device (RCD / GFCI) or a residual current monitor (RCM) is used for protection against direct or indirect contact, the following specific types must be used:

⚠ WARNING

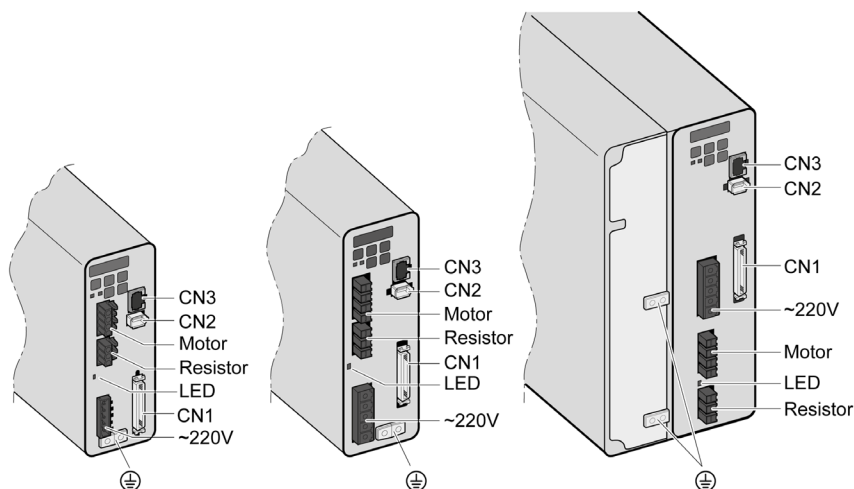
DIRECT CURRENT CAN BE INTRODUCED INTO THE PROTECTIVE GROUND CONDUCTOR

- Use a Type A Residual Current Device (RCD / GFCI) or a Residual Current Monitor (RCM) for single-phase drives connected to a phase and to the neutral conductor.
- Use a Type B Residual Current Device (RCD / GFCI) or a Residual Current Monitor (RCM) that has approval for use with frequency inverters and is sensitive to all types of current for three-phase drives and for single-phase drives not connected to a phase and the neutral conductor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The entire installation procedure must be performed without voltage present.

Overview of interfaces



Item	Description	Refer to
CN1	Signal interface For connecting master controller or I/O signals.	Connection I/O Interface (CN1) (see page 125)
CN2	Connection for motor encoder	Connecting the Motor Encoder (CN2) (see page 137)
CN3	Modbus (commissioning interface) For connecting PC via converter TCSCNAM3M002P	Connection PC (CN3) (see page 139)
~220V	Power stage supply (R,S,T) and logic supply (L1, L2)	Connection Logic Supply and Power Stage Supply (~220V) (see page 141)
LED	DC bus LED The LED is illuminated when mains voltage or internal charge are present. The DC bus LED is not an indicator of the absence of DC bus voltage.	-
Resistor	Connection for external braking resistor	Connection braking resistor (Resistor) (see page 144)
Motor	Motor phases connection (U, V, W, PE)	Connecting the motor phases (Motor) (see page 146)

Connection Grounding Screw

This product has a touch current greater than 3.5 mA. If the protective ground connection is interrupted, a hazardous touch current may flow if the housing is touched.

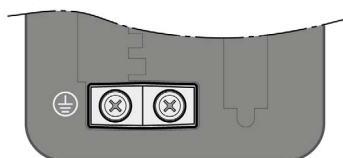
DANGER

INSUFFICIENT GROUNDING

- Use a protective ground conductor with at least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals.
- Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of the entire drive system.
- Ground the drive system before applying voltage.
- Do not use conduits as protective ground conductors; use a protective ground conductor inside the conduit.
- Do not use cable shields as protective ground conductors.
- Keep foreign objects from getting into the product.
- Verify the correct seating of seals and cable entries in order to avoid contamination such as deposits and humidity.

Failure to follow these instructions will result in death or serious injury.

The central grounding screw of the product is located at the bottom of the front side.



- Use ring-type cable lugs or fork-type cable lugs.
- Connect the ground connection of the device to the equipotential ground plane of your system.

Tightening torque of grounding screw	Nm (lb.in)	1.5 (13.28)
Screw type	-	M4 x 8 socket button head screw

Connection I/O Interface (CN1)

The I/O Interface (CN1) is a D-Sub 50-pin female connector. The following table describes the contacts of the connector:

Pin	Signal	Meaning	Pin	Signal	Meaning
1	DO4+	Digital output 4	2	DO3-	Digital output 3
3	DO3+	Digital output 3	4	DO2-	Digital output 2
5	DO2+	Digital output 2	6	DO1-	Digital output 1
7	DO1+	Digital output 1	8	DI4-	Digital input 4
9	DI1-	Digital input 1	10	DI2-	Digital input 2
11	COM	Reference potential to DI1 ... DI8	12	GND	Reference potential analog input
13	GND	Reference potential for analog input	14	-	Reserved
15	MON2	Analog output 2	16	MON1	Analog output 1
17	VDD	24 Vdc power supply (for external I/O)	18	T_REF	Analog input for reference torque
19	GND	Analog input signal ground	20	VCC	Output power supply 12 Vdc (for analog reference values)
21	OA	ESIM channel A	22	/OA	ESIM channel A, inverted
23	/OB	ESIM channel B, inverted	24	/OZ	ESIM index pulse, inverted
25	OB	ESIM channel B	26	DO4-	Digital output 4
27	DO5-	Digital output 5	28	DO5+	Digital output 5
29	/HPULSE	High-speed pulses, inverted	30	DI8-	Digital input 8
31	DI7-	Digital input 7	32	DI6-	Digital input 6
33	DI5-	Digital input 5	34	DI3-	Digital input 3
35	PULL HI_S (SIGN)	Pulse applied Power (SIGN)	36	/SIGN	Direction signal, inverted
37	SIGN	Direction signal	38	HPULSE	High-speed pulses
39	PULL HI_P (PULSE)	Pulse applied Power (PULSE)	40	/HSIGN	Direction signal for high-speed pulses, inverted
41	PULSE	Pulse input	42	V_REF	Analog input for reference velocity
43	/PULSE	Pulse input	44	GND	Analog input signal ground
45	COM-	Reference potential to VDD and DO6(OCZ)	46	HSIGN	Direction signal for high-speed pulses
47	COM-	Reference potential to VDD and DO6(OCZ)	48	DO6(OCZ)	ESIM index pulse Open collector output
49	COM-	Reference potential to VDD and DO6(OCZ)	50	OZ	ESIM index pulse Line driver output

WARNING

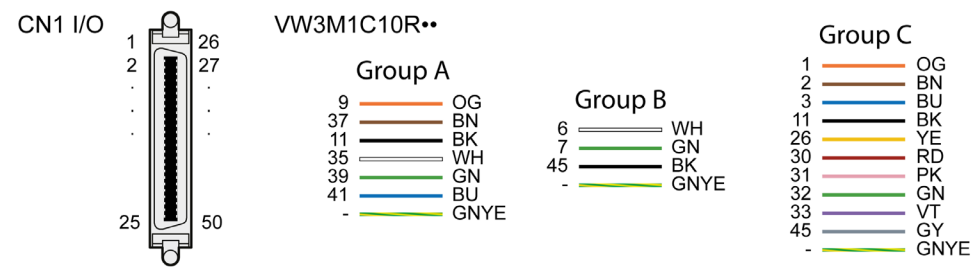
UNINTENDED EQUIPMENT OPERATION

Do not connect any wiring to reserved, unused connections, or to connections designated as No Connection (N.C.).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Prefabricated Cable VW3M1C10R••

Color assignments of the prefabricated cable connected to the I/O interface (CN1):



VW3M1C10R•• Pinout

Group A			Group B			Group C		
Pin	Signal	Color	Pin	Signal	Color	Pin	Signal	Color
9	DI1-	OG	6	DO1-	WH	1	DO4+	OG
37		BN	7	DO1+	GN	2	DO3-	BN
11	COM	BK	45	COM-	BK	3	DO3+	BU
35		WH	-			11	COM	BK
39		GN				26	DO4-	YE
41		BU				30	DI8-	RD
-						31	DI7-	PK
						32	DI6-	GN
						33	DI5-	VT
						45	COM-	BY

NOTE: For the CN1 mating connector, use a clip-on (latching) type, such as Schneider Electric reference VW3M1C12 CN1 Connector Kit.

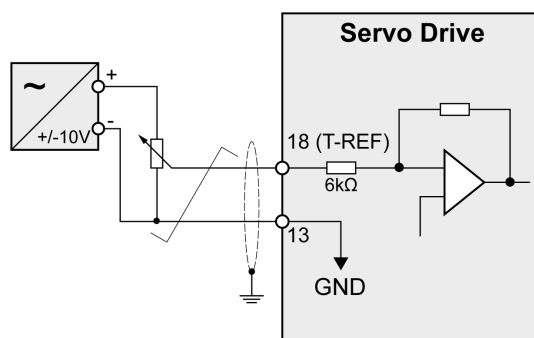
Inputs and Outputs Signals

The following inputs and outputs signals are available:

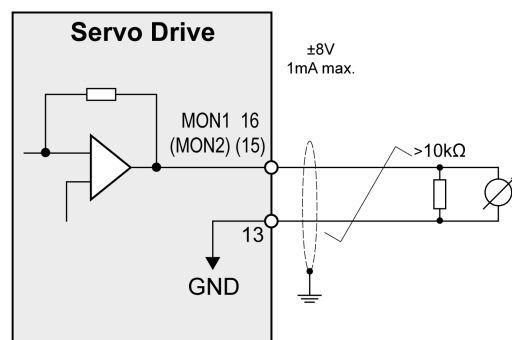
- Analog inputs and outputs ([see page 127](#))
- Pulse input (open collector, negative logic ([see page 128](#)))
- Pulse input (open collector, positive logic ([see page 129](#)))
- Pulse input (line driver) ([see page 130](#))
- High-speed pulse input (line driver) ([see page 130](#))
- Digital outputs (negative logic) ([see page 131](#))
- Digital outputs (positive logic) ([see page 132](#))
- Digital inputs (negative logic) ([see page 133](#))
- Digital inputs (positive logic) ([see page 135](#))
- Encoder output signal) ([see page 136](#))

Analog Inputs and Outputs

Example of reference value via analog input:



Example of analog output:



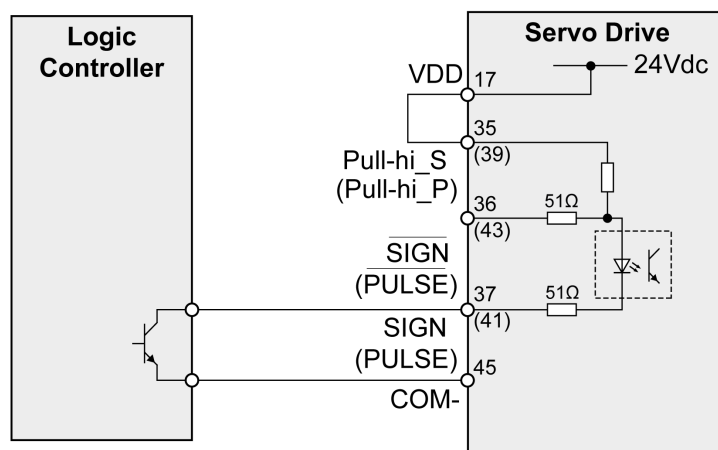
Pulse Input (Open Collector, Negative Logic)

⚠ WARNING**UNINTENDED EQUIPMENT OPERATION**

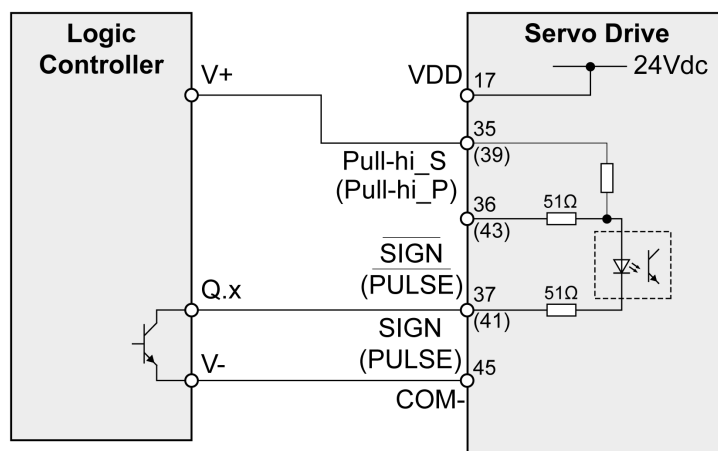
Do not connect an external, 24 Vdc power supply to the VDD connection of the I/O interface (CN1) connector.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Example of pulse input (open collector) with internal power supply (negative logic).



Example of pulse input (open collector) with external power supply (negative logic).



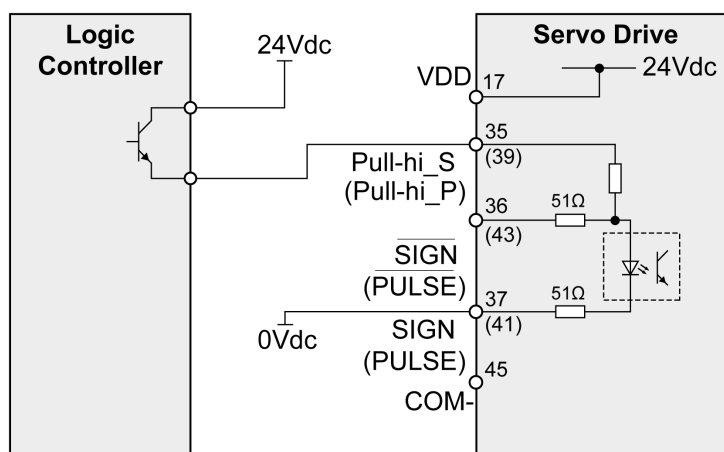
Pulse Input (Open Collector, Positive Logic)

⚠ WARNING**UNINTENDED EQUIPMENT OPERATION**

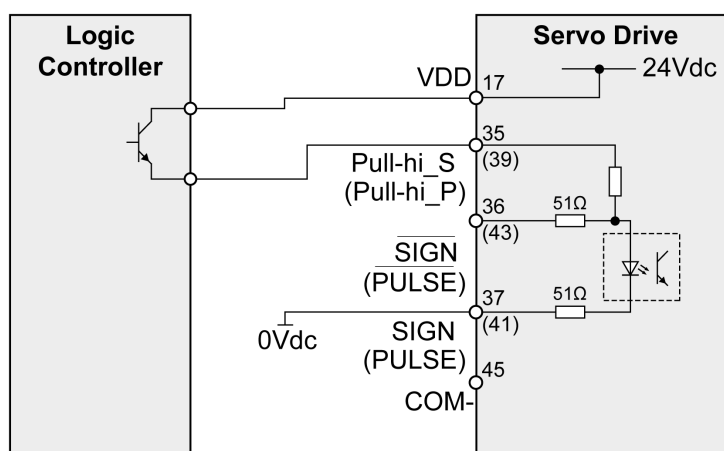
Do not connect an external, 24 Vdc power supply to the VDD connection of the I/O interface (CN1) connector.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Example of pulse input (open collector) with internal power supply (positive logic).

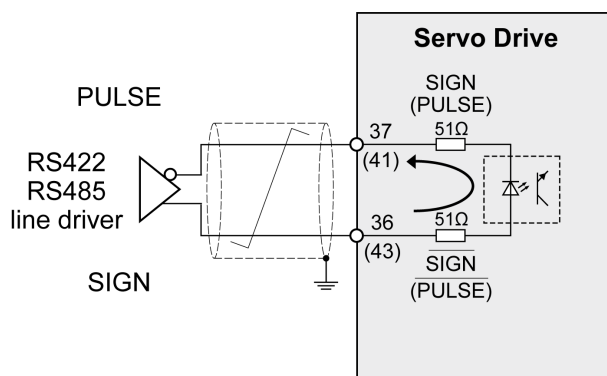


Example of pulse input (open collector) with external power supply (positive logic).



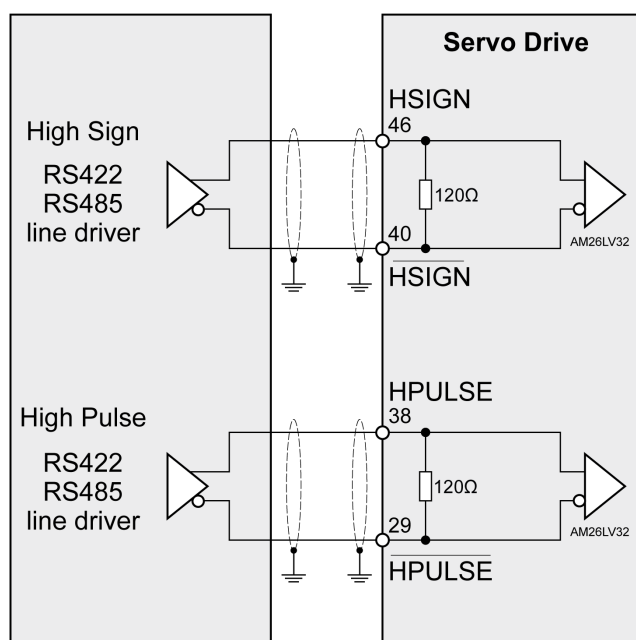
Pulse Input (Line Driver)

Example of pulse input (line driver).



High-Speed Pulses

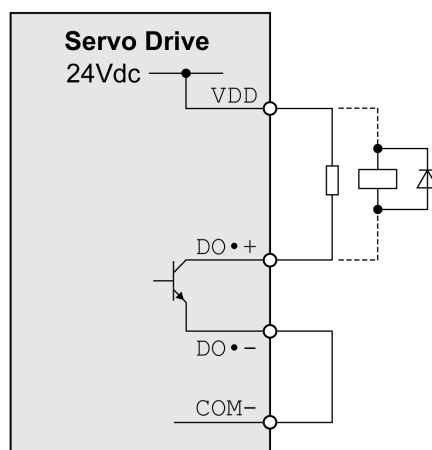
Example of high-speed pulse input (line driver).



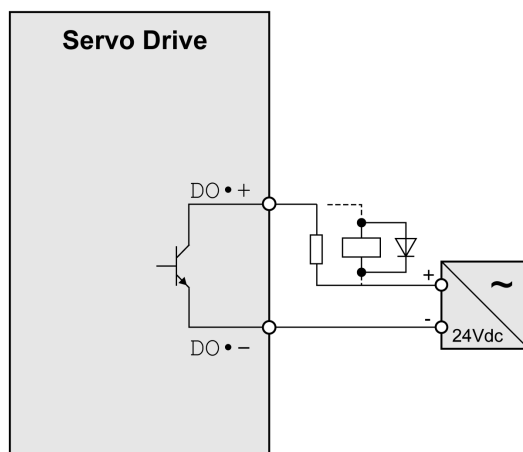
Connect the cable shield to the equipotential ground of your controller/drive electrical system.

Wiring of the Digital Outputs (Negative Logic)

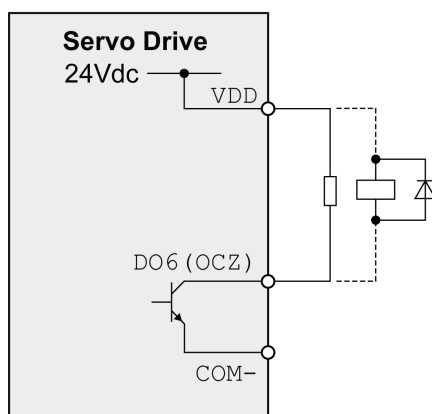
Example of digital outputs DO1 ... DO5 with internal power supply (negative logic):



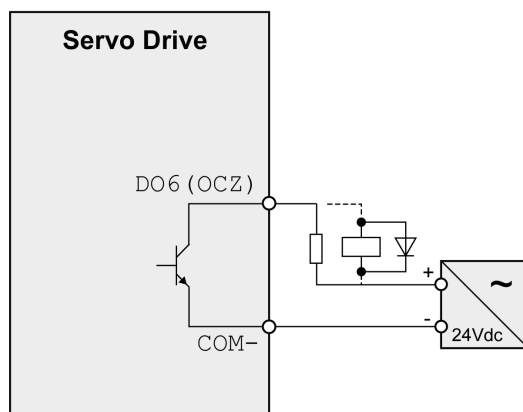
Example of digital outputs DO1 ... DO5 with external power supply (negative logic):



Example of digital output DO6 (OCZ) with internal power supply (negative logic):



Example of digital output DO6 (OCZ) with external power supply (negative logic):



Inductive loads using DC voltages may damage the signal outputs. A protection circuit is required to protect the signal outputs against inductive loads.

⚠ CAUTION

OUTPUT CIRCUIT DAMAGE DUE TO INDUCTIVE LOADS

Use an appropriate external protective circuit or device to reduce the inductive direct current load damage.

Failure to follow these instructions can result in injury or equipment damage.

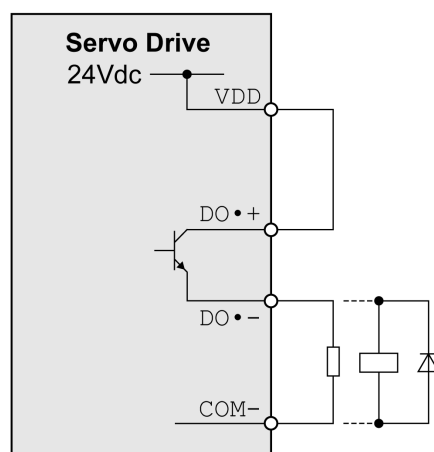
A diode can be used to protect the signal outputs against inductive loads.

Use a diode with the following ratings:

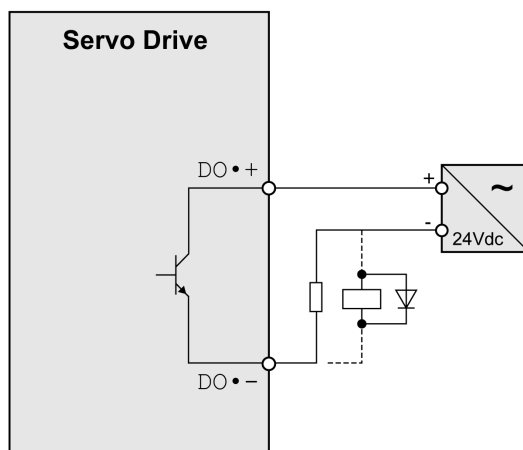
- Reverse withstand voltage: voltage of signal output times 10
- Forward current: greater than the load current

Wiring of the Digital Outputs (Positive Logic)

Example of digital outputs DO1 ... DO5 with internal power supply (positive logic):



Example of digital outputs DO1 ... DO5 with external power supply (positive logic):



Inductive loads using DC voltages may damage the signal outputs. A protection circuit is required to protect the signal outputs against inductive loads.

⚠ CAUTION

OUTPUT CIRCUIT DAMAGE DUE TO INDUCTIVE LOADS

Use an appropriate external protective circuit or device to reduce the inductive direct current load damage.

Failure to follow these instructions can result in injury or equipment damage.

A diode can be used to protect the signal outputs against inductive loads. Use a diode with the following ratings:

Reverse withstand voltage: voltage of signal output times 10

Forward current: greater than the load current

Wiring of the Digital Inputs (Negative Logic)

⚠ WARNING

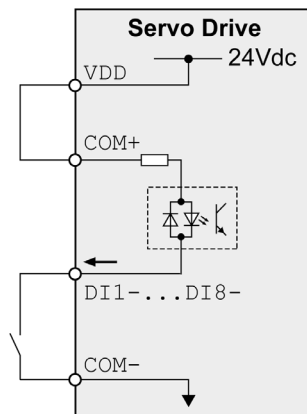
UNINTENDED EQUIPMENT OPERATION

Do not connect an external, 24 Vdc power supply to the VDD connection of the I/O interface (CN1) connector.

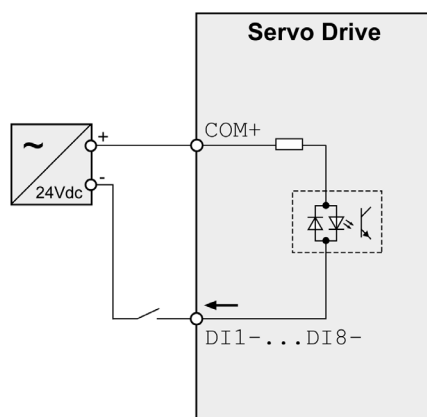
Failure to follow these instructions can result in death, serious injury, or equipment damage.

Use a relay or an open collector output (NPN transistor) for the input signal.

Example of digital input (negative logic) with internal power supply:



Example of digital input (negative logic) with external power supply:



Wiring of the Digital Inputs (Positive Logic)

⚠ WARNING

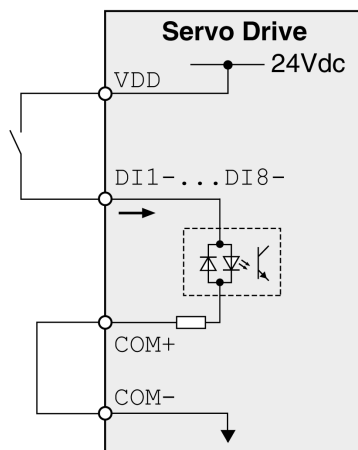
UNINTENDED EQUIPMENT OPERATION

Do not connect an external, 24 Vdc power supply to the VDD connection of the I/O interface (CN1) connector.

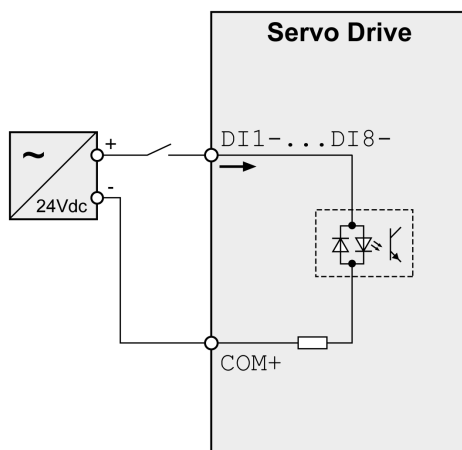
Failure to follow these instructions can result in death, serious injury, or equipment damage.

Use a relay or an open collector output (PNP transistor) for the input signal.

Example of digital input with internal power supply (positive logic):

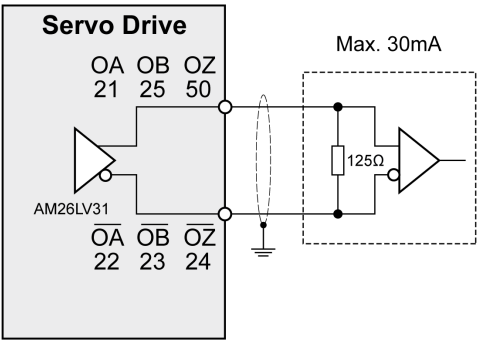


Example of digital input with external power supply (positive logic):

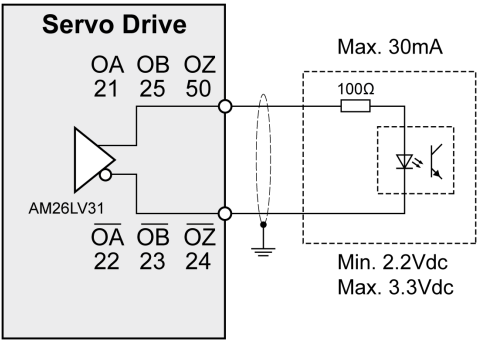


Encoder Output Signal

Example of encoder output signal Line Driver.



Example of encoder output signal, high-speed optocoupler.



Connecting the Motor Encoder (CN2)

Function and Encoder Type

The motor encoder is an integrated, high-resolution singleturn absolute encoder. It provides the device with information on the motor position (analog and digital).

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table (*see page 18*).

Cable Specifications

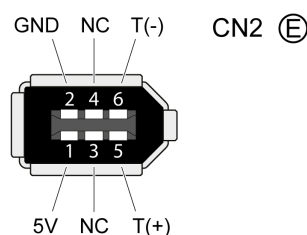
For further information, refer to chapter Cables (*see page 100*).

Shield:	Required, both ends grounded
Twisted Pair:	Required
PELV:	Required
Cable composition:	10 x 0.13 mm ² (10 x AWG 24)
Maximum cable length:	20 m (65.6 ft)
Special characteristics:	Fieldbus cables are not suitable for connecting encoders.

- Use pre-assembled cables to reduce the risk of wiring errors.

Wiring Diagram

Connection assignment motor encoder (CN2)



The motor encoder interface (CN2) is a 6-pin connector. The following table describes the contacts of the connector:

Pin	Signal	Color ⁽¹⁾	Meaning	Motor military connector	Motor plastic connector	I/O
5	T+	Blue (BU)	Serial communication	A	1	I/O
6	T-	Blue/Black (BU/BK)		B	4	
1	+5 V	Red, red/white (RD, RD/WH)	5 V encoder supply	S	7	I
2	GND	Black, black/white (BK, BK/WH)	Reference potential for encoder supply	R	8	O
3, 4	N.C.	Reserved	-	-	-	-

(1) Color information relates to the cables available as accessories.

⚠ WARNING

UNINTENDED EQUIPMENT OPERATION

Do not connect any wiring to reserved, unused connections, or to connections designated as No Connection (N.C.).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Connecting the Motor Encoder

- Verify that wiring, cables, and connected interface meet the PELV requirements.
- Note the information on EMC, see chapter Electromagnetic Compatibility (EMC) (*see page 96*). Use equipotential bonding conductors for equipotential bonding.
- Connect the connector to CN2 Encoder.
- Verify that the connector locks snap in properly at the housing.

Route the cables from the motor and the encoder to the device (starting from the motor). Due to the pre-assembled connectors, this direction is often faster and easier.

Connection PC (CN3)

Function

The commissioning interface (CN3) is an RS-485 connection, supported on an RJ45 connector. If the PC used to connect to the commissioning interface has an RS-485 port, typically supported on a DB9 connector, you can connect it to this connector (RJ45 / DB9 cable). Otherwise, you can use the USB port of the PC with a USB to RS-485 converter.

The commissioning interface may only be used for a point-to-point connection, but not for a point-to-multipoint connection (RS-485 network).

If the commissioning interface at the product is directly connected to an Ethernet interface at the PC, the PC interface may be damaged and rendered inoperable.

NOTICE

INOPERABLE EQUIPMENT

Do not directly connect an Ethernet interface to the commissioning interface of this product.

Failure to follow these instructions can result in equipment damage.

Connecting a PC

A PC with the commissioning software LXM26 DTM Library can be connected for commissioning. The PC is connected via a bidirectional USB/RS485 converter, refer to Accessories and Spare Parts.

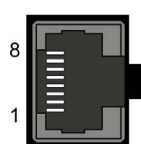
Cable Specifications

For further information, refer to chapter Cables (*see page 100*).

Shield:	Required, both ends grounded
Twisted Pair:	Required
PELV:	Required
Cable composition:	8 x 0.25 mm ² (8 x AWG 22)
Maximum cable length:	100 m (328 ft)
Special characteristics:	-

Wiring Diagram

Wiring diagram PC with commissioning software



CN3 Modbus

The commissioning interface (CN3) is an RJ45 connector. The following table describes the contacts of the connector:

Pin	Signal	Meaning	I/O
1 ... 3	-	Reserved	-
4	MOD_D1 ⁽¹⁾	Bidirectional transmit/receive signal	RS-485 level
5	MOD_D0 ⁽¹⁾	Bidirectional transmit/receive signal, inverted	
6 ... 7	-	Reserved	-
8 and connector housing	SHLD	Functional ground / shield - internally connected to ground potential of the drive	-
(1) No polarization.			

 WARNING

UNINTENDED EQUIPMENT OPERATION

Do not connect any wiring to reserved, unused connections, or to connections designated as No Connection (N.C.).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

NOTE: Verify that the connector locks snap in properly at the housing.

Connection Logic Supply and Power Stage Supply (~220V)

This product has a touch current greater than 3.5 mA. If the protective ground connection is interrupted, a hazardous touch current may flow if the housing is touched.

DANGER

INSUFFICIENT GROUNDING

- Use a protective ground conductor with at least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals.
- Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of the entire drive system.
- Ground the drive system before applying voltage.
- Do not use conduits as protective ground conductors; use a protective ground conductor inside the conduit.
- Do not use cable shields as protective ground conductors.
- Keep foreign objects from getting into the product.
- Verify the correct seating of seals and cable entries in order to avoid contamination such as deposits and humidity.

Failure to follow these instructions will result in death or serious injury.

WARNING

INSUFFICIENT PROTECTION AGAINST OVERCURRENT

- Use the external fuses specified in chapter "Technical Data".
- Do not connect the product to a supply mains whose short-circuit current rating (SCCR) exceeds the value specified in the chapter "Technical Data".

Failure to follow these instructions can result in death, serious injury, or equipment damage.

WARNING

INCORRECT MAINS VOLTAGE

Verify that the product is approved for the mains voltage before applying power and configuring the product.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The equipment, drives and motors, are intended for industrial use and may only be operated with a permanently installed connection.

Prior to connecting the equipment, verify the approved mains types, see chapter Electrical Data Drive (*see page 37*).

Cable Specifications

Respect the required cable properties in chapter Cables (*see page 100*) and in chapter Electromagnetic Compatibility (EMC) (*see page 96*).

Shield:	-
Twisted Pair:	-
PELV:	-
Cable composition:	The conductors must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.
Maximum cable length:	3 m (9.84 ft)
Special characteristics:	-

Properties of the Terminals

The terminals are approved for stranded conductors and solid conductors. Use cable ends (ferrules), if possible.

LXM26D	Unit	UA5, U01, U02, U04, U07, U10, U15	U20, U30, U45
Connection cross section	mm ² (AWG)	0.75 ... 2.5 (20 ... 14)	0.75 ... 6 (20 ... 10)
Stripping length	mm (in)	8 ... 9 (0.31 ... 0.35)	15 (0.59)

Prerequisites for Connecting the Logic Supply

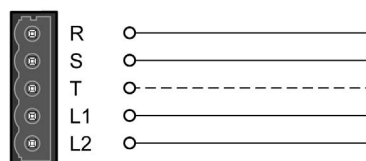
Note the following information:

- Use upstream mains fuses. For further information about fuse types and fuse ratings, refer to chapter Electrical Data Drive ([see page 37](#)).
- Note the EMC requirements. Where required, use surge arresters and mains reactors.
- If the length of the mains cable between the external mains filter and the drive exceeds 200 mm (7.87 in), it must be shielded and grounded at both ends.
- For a UL-compliant design, refer to chapter Conditions for UL 508C ([see page 23](#)).

Connection Logic Supply

Wiring diagram logic supply

~220V



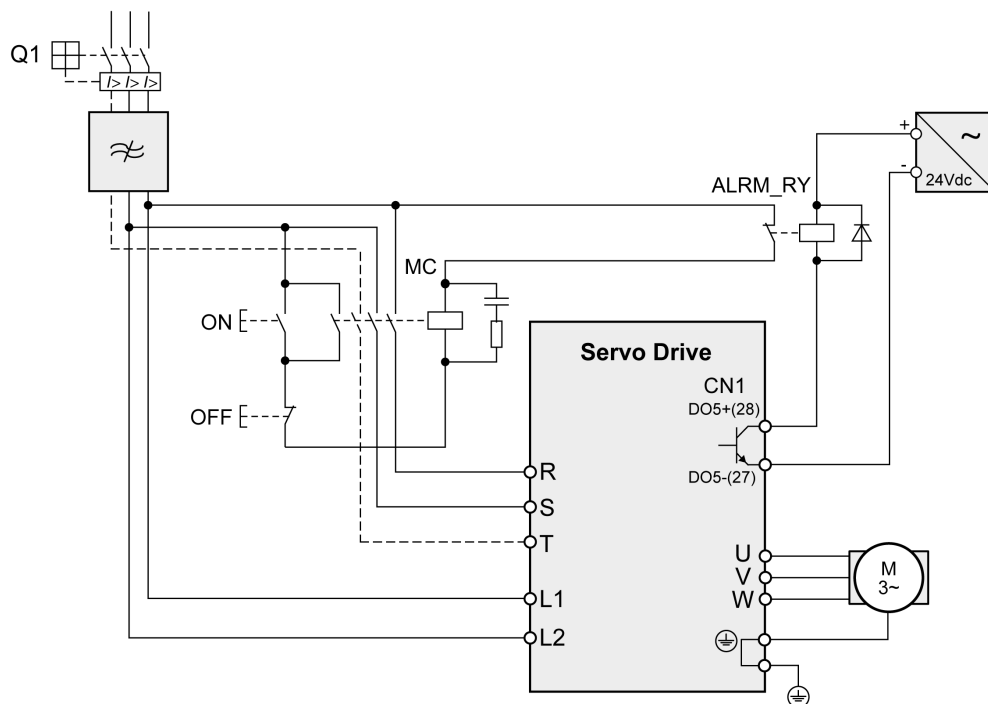
Connection	Meaning
R, S, T	Power stage supply
L1, L2	Logic supply

- Verify the type of mains. For the approved types of mains, refer to chapter Electrical Data Drive ([see page 37](#)).
- Connect the mains cable.
- Verify that the connector locks snap in properly at the housing.

Wiring Diagram for Devices That Can Be Connected Via a Single-Phase or Three Phases

Drives with a continuous power from 50 W to 1500 W can be connected via a single-phase or via three phases. Drives with a continuous power of more than 1500 W must be connected via three phases.

Wiring diagram for devices that can be connected via a single-phase or three-phases



Connection Braking Resistor (Resistor)

An insufficiently rated braking resistor can cause overvoltage on the DC bus. Overvoltage on the DC bus causes the power stage to be disabled. The motor is no longer actively decelerated.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Verify that the braking resistor has a sufficient rating by performing a test run under maximum load conditions.
- Verify that the parameter settings for the braking resistor are correct.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Internal Braking Resistor

A braking resistor is integrated in the device to absorb braking energy. The drive is shipped with the internal braking resistor active.

External Braking Resistor

An external braking resistor is required for applications in which the motor must be decelerated quickly and the internal braking resistor cannot absorb the excess braking energy.

Selection and rating of the external braking resistor are described in chapter Rating the Braking Resistor (*see page 103*). For suitable braking resistors, refer to chapter Accessories and Spare Parts (*see page 89*).

Cable Specifications

For further information, refer to chapter Cables (*see page 100*).

Shield:	Required, both ends grounded
Twisted Pair:	-
PELV:	-
Cable composition:	Minimum conductor cross section: Same cross section as logic supply. The conductors must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.
Maximum cable length:	3 m (9.84 ft)
Special characteristics:	Temperature resistance

The braking resistors listed in chapter Accessories and Spare Parts (*see page 89*) have a 3-wire, temperature-resistant cable with a length of 0.75 m (2.46 ft) to 3 m (9.84 ft).

Properties of the Terminals (Resistor)

The terminals are approved for stranded conductors and solid conductors. Use cable ends (ferrules), if possible.

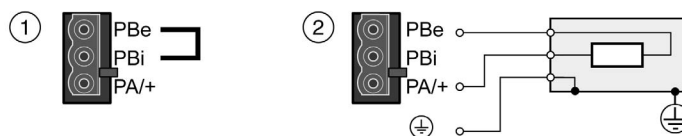
LXM26D	Unit	UA5, U01, U02, U04, U07, U10, U15	U20, U30, U45
Connection cross section	mm ² (AWG)	0.75 ... 2.5 (20 ... 14)	0.75 ... 6 (20 ... 10)
Stripping length	mm (in)	8 ... 9 (0.31 ... 0.35)	15 (0.59)

The terminals are approved for fine-stranded conductors and solid conductors. Respect the maximum permissible connection cross section. Take into account the fact that cable ends (ferrules) increase the conductor cross section.

NOTE: If you use cable ends (ferrules), use only cable ends (ferrules) with collars for these terminals.

Wiring Diagram

Wiring diagram internal or external braking resistor



Item	Description
1	Internal braking resistor activated
2	Connection external braking resistor

Connecting the External Braking Resistor

- Remove power from all supply voltages. Respect the safety instructions concerning electrical installation.
- Verify that no voltages are present.
- Ground the ground connection (PE) of the braking resistor.
- Connect the external braking resistor to the device.
- Connect a large surface area of the cable shield to the central grounding point of your system.

⚠ DANGER

ELECTRIC SHOCK, EXPLOSION, OR ARC FLASH

- Disconnect all power from all equipment including connected devices prior to removing any covers or doors, or installing or removing any accessories, hardware, cables, or wires.
- Place a "Do Not Turn On" or equivalent hazard label on all power switches and lock them in the non-energized position.
- Wait 15 minutes to allow the residual energy of the DC bus capacitors to discharge.
- Do not assume that the DC bus is voltage-free when the DC bus LED is off.
- Block the motor shaft to prevent rotation prior to performing any type of work on the drive system.
- Do not create a short-circuit across the DC bus terminals or the DC bus capacitors.
- Replace and secure all covers, accessories, hardware, cables, and wires and confirm that a proper ground connection exists before applying power to the unit.
- Use only the specified voltage when operating this equipment and any associated products.

Failure to follow these instructions will result in death or serious injury.

Connecting the Motor Phases (Motor)

High voltages may be present at the motor connection. The motor itself generates voltage when the motor shaft is rotated. AC voltage can couple voltage to unused conductors in the motor cable.

DANGER

ELECTRIC SHOCK

- Verify that no voltage is present prior to performing any type of work on the drive system.
- Block the motor shaft to prevent rotation prior to performing any type of work on the drive system.
- Insulate both ends of unused conductors of the motor cable.
- Supplement the motor cable grounding conductor with an additional protective ground conductor to the motor housing.
- Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment.

Failure to follow these instructions will result in death or serious injury.

Incorrect wiring of the motor connection may cause live wires to be exposed outside of the motor connector below the HMI.

DANGER

ELECTRIC SHOCK CAUSED BY INCORRECT WIRING

- Verify that the protective ground connection (PE) of the device is connected to ground.
- Do not remove the cable end (ferrule) from the protective ground terminal (PE) of the motor connector until you are prepared to wire the protective ground conductor of the motor to the protective ground terminal (PE) of the motor connector.
- Verify that no bare metal of the wires is exposed outside of the motor connector housing when wiring the motor connector.
- Regularly, as part of a maintenance plan, assure that the motor wires are secured in the terminals of the motor connector due to vibration or other influences.

Failure to follow these instructions will result in death or serious injury.

Drive systems may perform unintended movements if unapproved combinations of drive and motor are used. Even if motors are similar, different adjustment of the encoder system may be a source of hazards. Even if the connectors for motor connection and encoder connection match mechanically, this does not imply that the motor is approved for use.

WARNING

UNINTENDED MOVEMENT

Only use approved combinations of drive and motor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table ([see page 18](#)).

Route the cables from the motor and the encoder to the device (starting from the motor). Due to the pre-assembled connectors, this direction is often faster and easier.

Cable Specifications

For further information, refer to chapter Cables ([see page 100](#)).

Shield:	Required, both ends grounded
Twisted Pair:	-
PELV:	The wires for the holding brake must be PELV-compliant.
Cable composition:	3 wires for motor phases The conductors must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.

Maximum cable length:	Depends on the required limit values for conducted interference. Category C3: 20 m (65.6 ft)
Special characteristics:	Contains wires for the temperature sensor

Note the following information:

- You may only connect the original motor cable.
- If you do not connect the wires at the motor end, you must isolate each wire individually (inductive voltages).
- Use pre-assembled cables to reduce the risk of wiring errors.

Properties of the Terminals (Motor)

The terminals are approved for stranded conductors and solid conductors. Use cable ends (ferrules), if possible.

LXM26D	Unit	UA5, U01, U02, U04, U07, U10, U15	U20, U30, U45
Connection cross section	mm ² (AWG)	0.75 ... 2.5 (20 ... 14)	0.75 ... 6 (20 ... 10)
Stripping length	mm (in)	8 ... 9 (0.31 ... 0.35)	15 (0.59)

Monitoring

The drive monitors the motor phases for:

- Short circuit between the motor phases
- Short circuit between the motor phases and ground (Not applicable for LXM26DUA5 ... U07)

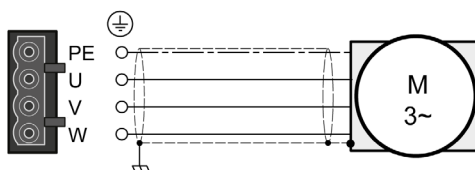
Short circuits between the motor phases and the DC bus, the braking resistor, or the holding brake wires are not detected.

When a short-circuit is detected, power is removed by disabling the power stage. The firmware reports error AL001. Once you have resolved the issue of the over-current, you can re-enable the power stage of the drive.

NOTE: After three successive unsuccessful retries of resetting the power stage, the reset will be blocked for a minimum of one minute.

Wiring Diagram Motor

Wiring diagram motor



Connection	Meaning	Color ⁽¹⁾ (IEC 757)
U	Motor phase	RD
V		WH
W		BK
PE	Protective ground conductor	GN/YE

(1) Color information relates to the cables available as accessories.

Connecting the Motor Cable

- Note the information on EMC, refer to chapter Electromagnetic Compatibility (EMC) ([see page 96](#)).
- Connect the motor phases and protective ground conductor to the connector labelled **Motor**. Verify that the connections U, V, W, and PE (ground) match at the motor and the device.
- Verify that the connector locks snap in properly at the housing.

Holding Brake Connection

The holding brake in the motor has the task of holding the motor position when the power stage is disabled. The holding brake is not a safety function and not a service brake.

A motor with a holding brake requires a suitable holding brake controller which releases the brake when the power stage is enabled and locks the motor shaft when the power stage is disabled.

The holding brake is connected to one of the digital outputs **DO1...DO5**. The signal output function **BRKR** must be assigned to the digital output to which the holding brake is connected. The signal output function **BRKR** releases the holding brake when the power stage is enabled. When the power stage is disabled, the holding brake is reapplied.

The factory settings for the signal outputs depend on the operating mode, see chapter Setting the Digital Signal Outputs (see page 276). Depending on the operating mode, the signal output function is either assigned to the digital output DO4 or not assigned at all. When you reset the drive to the factory settings with P2-08 = 10, the assignments of the signal output functions are also reset to the factory settings.

When you switch the operating mode using the parameter P1-01 or the signal input functions V-Px and V-T, the signal output functions may also be reset to the factory settings for the new operating mode. If you use the setting D = 0 of parameter P1-01, the assignment of the signal output functions remains the same in the new operating mode.

Resetting the drive to the factory settings or switching the operating mode can modify the assignment of the signal output functions in such a way that the holding brake is released unintentionally.

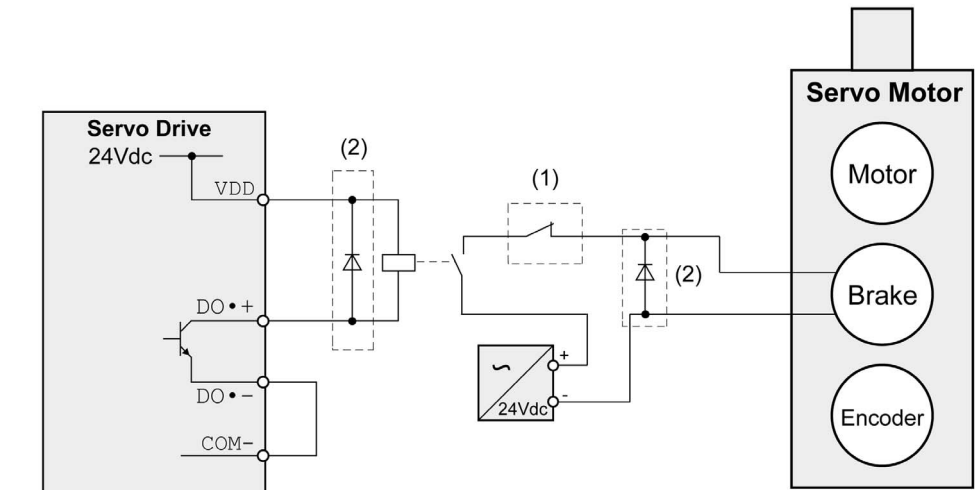
⚠ WARNING

UNINTENDED EQUIPMENT OPERATION

- Verify that the digital output to which you have assigned the signal output function **BRKR** has been properly wired and configured.
- Before switching to a different operating mode, verify that the signal output function **BRKR** for the holding brake will not be assigned to an incorrect digital output in the new operating mode.
- Before resetting the drive to the factory settings, verify that the signal output function **BRKR** for the holding brake will be assigned to the correct digital output or reassign the signal output function **BRKR** after the factory reset according to the requirements of your application prior to starting the system.
- In all cases, take all necessary measures to prevent unintended movements of the load caused by a release of the holding brake.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Example (negative logic) of wiring the holding brake



Item	Description
1	Triggering an EMERGENCY STOP should apply the holding brake
2	Flyback diode

Chapter 10

Motor Installation

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Mechanical Installation Motor	150
Connections and Pin Assignments	153
Connection of Motor and Encoder	156
Holding Brake Connection	158

Mechanical Installation Motor

Motors are very heavy relative to their size. The mass of the motor can cause injuries and damage.

WARNING

HEAVY AND/OR FALLING PARTS

- Use a suitable crane or other suitable lifting gear for mounting the motor if this is required by the weight of the motor.
- Use the necessary personal protective equipment (for example, protective shoes, protective glasses and protective gloves).
- Mount the motor so that it cannot come loose (use of securing screws with appropriate tightening torque), especially in cases of fast acceleration or continuous vibration.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Motors can generate strong local electrical and magnetic fields. This can cause interference in sensitive devices.

WARNING

ELECTROMAGNETIC FIELDS

- Keep persons with electronic medical implants, such as pacemakers, away from the motor.
- Do not place electromagnetically sensitive devices in the vicinity of the motor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The metal surfaces of the product may exceed 70 °C (158 °F) during operation.

WARNING

HOT SURFACES

- Avoid unprotected contact with hot surfaces.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of hot surfaces.
- Verify that the heat dissipation is sufficient by performing a test run under maximum load conditions.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

CAUTION

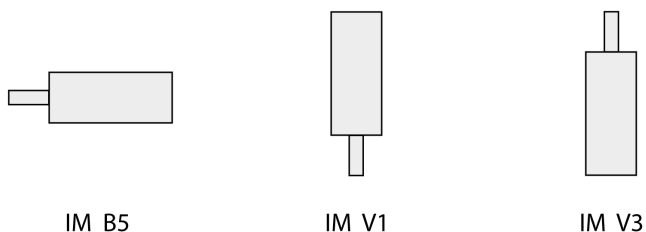
IMPROPER APPLICATION OF FORCES

- Do not use the motor as a step to climb into or onto the machine.
- Do not use the motor as a load-bearing part.
- Use hazard labels and guards on your machine to help prevent the improper application of forces on the motor.

Failure to follow these instructions can result in injury or equipment damage.

Mounting Position

The following mounting positions are defined and permissible as per IEC 60034-7:



Mounting

When the motor is mounted to the mounting surface, it must be accurately aligned axially and radially and make even contact with the mounting surface. All mounting screws must be tightened with the specified tightening torque. No uneven mechanical load may be applied while the mounting screws are tightened. For data, dimensions, and degrees of protection (IP), refer to chapter Motor ([see page 45](#)).

Mounting Situation

NOTICE

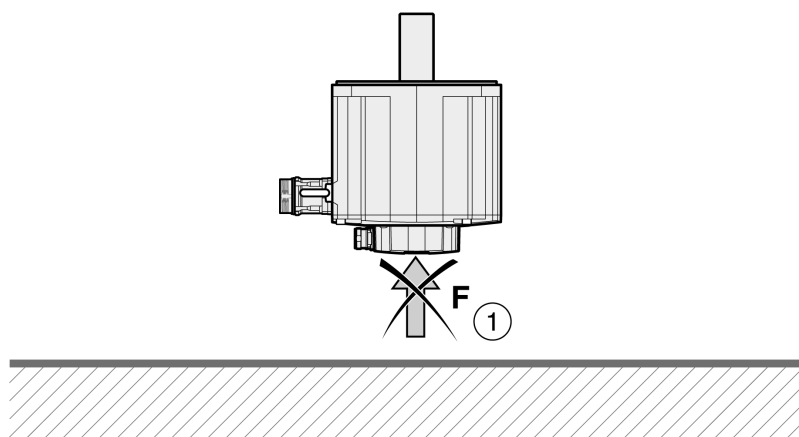
FORCES APPLIED TO THE REAR SIDE OF THE MOTOR

- Do not place the motor on the rear side.
- Protect the rear side of the motor from impact.
- Do not lift motors via the rear side.
- Only lift motors equipped with eyebolts via the eyebolts.

Failure to follow these instructions can result in equipment damage.

Special Characteristics BCH2•H, BCH2•M, BCH2•R

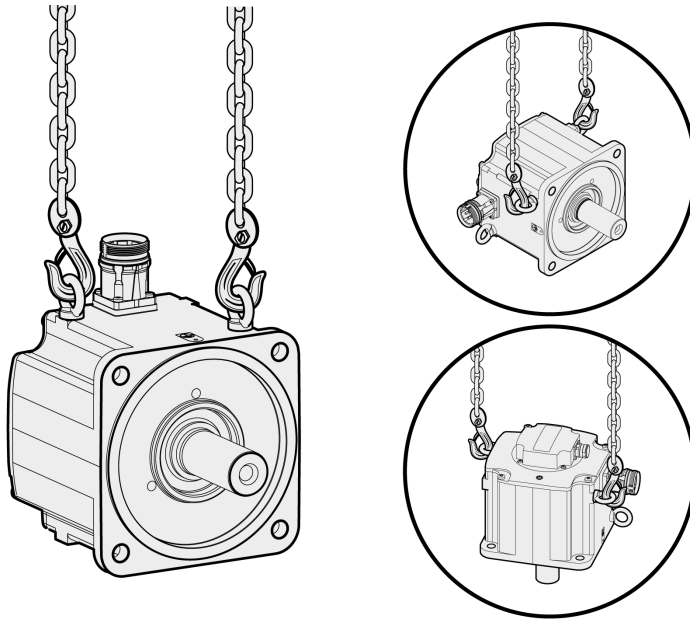
Rear side of motor



Item	Description
1	Protect the rear side of the motor from application of forces.

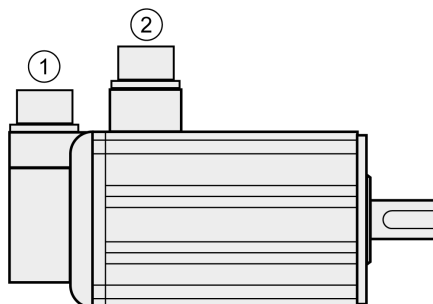
Eyebolts BCH2•R

Consider the mass of the product when mounting the motor. It may be necessary to use suitable lifting gear.



Connections and Pin Assignments

Connection overview



Item	Description
1	Encoder connection
2	Motor connection

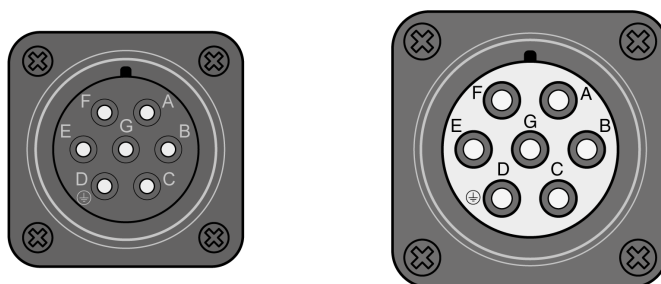
Pin Assignment Motor Connection

Pin assignments of motor phases and holding brake

Motor connection plastic connector (type A and type B), drive side:



Motor connection MIL connector (type C and type D), motor side:



Pin Type A	Pin Type B	Pin Type C and D	Signal	Meaning	Color ⁽¹⁾ (IEC 757)
1	1	E	U	Motor phase U	RD
2	2	G	V	Motor phase V	WH
3	4	B	W	Motor phase W	BK
4	5	D	PE	Protective ground (protective earth)	GN/YE
–	3	F	BRAKE_24V	Supply voltage holding brake 24 Vdc	BU
(1) Color information relates to the cables available as accessories.					

Pin Type A	Pin Type B	Pin Type C and D	Signal	Meaning	Color ⁽¹⁾ (IEC 757)
–	6	A	BRAKE_0V	Reference potential holding brake 0 Vdc	BN
–	–	C	–	Reserved	–

(1) Color information relates to the cables available as accessories.

⚠ WARNING

UNINTENDED EQUIPMENT OPERATION

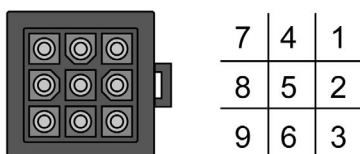
Do not connect any wiring to reserved, unused connections, or to connections designated as No Connection (N.C.).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

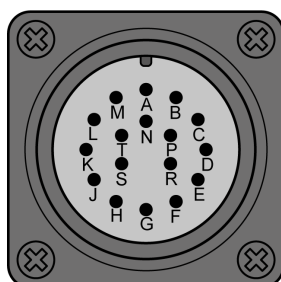
Pin Assignment Encoder Connection

Pin assignment of the encoder.

Encoder connection plastic connector (Type A), drive side:



Encoder connection MIL connector (Type B), motor side:



Pin Type A	Pin Type B	Signal	Meaning	Color ⁽¹⁾ (IEC 757)
1	A	T+	Data	BU
2	C	–	Reserved	–
3	D	–	Reserved	–
4	B	T-	Data	BU/BK
5	F	–	Reserved	–
6	G	–	Reserved	–
7	S	DC+5 V	Supply voltage	RD/WH
8	R	GND	Reference potential	BK/WH
9	L	Shield	Shield	BK
–	E	–	Reserved	–
–	H	–	Reserved	–
–	J	–	Reserved	–

(1) Color information relates to the cables available as accessories.

Pin Type A	Pin Type B	Signal	Meaning	Color ⁽¹⁾ (IEC 757)
–	K	–	Reserved	–
–	M	–	Reserved	–
–	N	–	Reserved	–
–	P	–	Reserved	–
–	T	–	Reserved	–
(1) Color information relates to the cables available as accessories.				

WARNING

UNINTENDED EQUIPMENT OPERATION

Do not connect any wiring to reserved, unused connections, or to connections designated as No Connection (N.C.).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Mating Connector

For suitable mating connectors, refer to chapter Connectors and Adapters (*see page 84*).

Connection of Motor and Encoder

The motor is designed for operation via a drive. Connecting the motor directly to line voltage will damage the motor and can cause fires.

⚠ DANGER

FIRE HAZARD DUE TO INCORRECT CONNECTION

Only connect the motor to a matching, approved drive.

Failure to follow these instructions will result in death or serious injury.

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table ([see page 18](#)).

High voltages may be present at the motor connection. The motor itself generates voltage when the motor shaft is rotated. AC voltage can couple voltage to unused conductors in the motor cable.

⚡ ⚠ DANGER

ELECTRIC SHOCK

- Verify that no voltage is present prior to performing any type of work on the drive system.
- Block the motor shaft to prevent rotation prior to performing any type of work on the drive system.
- Insulate both ends of unused conductors of the motor cable.
- Supplement the motor cable grounding conductor with an additional protective ground conductor to the motor housing.
- Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment.

Failure to follow these instructions will result in death or serious injury.

Drive systems may perform unintended movements if unapproved combinations of drive and motor are used. Even if motors are similar, different adjustment of the encoder system may be a source of hazards. Even if the connectors for motor connection and encoder connection match mechanically, this does not imply that the motor is approved for use.

⚠ WARNING

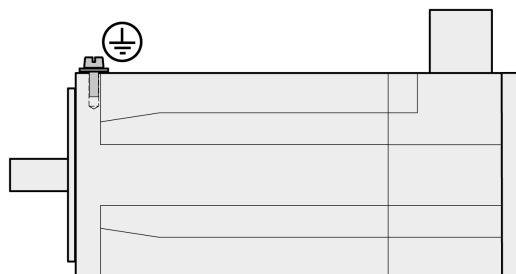
UNINTENDED MOVEMENT

Only use approved combinations of drive and motor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table ([see page 18](#)).

Protective Ground Conductor Connection



- Ground the motor via a grounding screw if grounding via the flange and the protective ground conductor of the motor cable is not sufficient.
- Use parts with suitable corrosion protection.

Connecting the Cables

Incorrect installation of the cable may destroy the insulation. Broken conductors in the cable or improperly connected connectors may be melted by arcs.

DANGER

ELECTRIC SHOCK, ARC FLASH AND FIRE CAUSED BY INCORRECT INSTALLATION OF THE CABLE

- Disconnect all power before plugging in or unplugging the connectors.
- Verify correct pin assignment of the connectors according to the specifications in this chapter before connecting the cables.
- Verify that the connectors are properly inserted and locked before applying power.
- Avoid forces or movements of the cable at the cable entries.

Failure to follow these instructions will result in death or serious injury.

- Connect the motor cable and the encoder cable to the drive according to the wiring diagram of the drive.
- If your motor is equipped with a holding brake, follow the instructions in chapter Holding Brake Connection ([see page 158](#)).

Holding Brake Connection

The holding brake in the motor has the task of holding the motor position when the power stage is disabled. The holding brake is not a safety function and not a service brake.

A motor with a holding brake requires a suitable holding brake controller which releases the brake when the power stage is enabled and locks the motor shaft when the power stage is disabled.

See chapter Holding Brake Connection (*see page 148*) for additional information.

As a result of damage to the insulation of the motor cable, mains voltage may get to the wires for the holding brake.

DANGER

ELECTRICAL SHOCK CAUSED BY DAMAGE TO THE MOTOR CABLE

- Use a PELV power supply for the holding brake.
- Insulate both ends of unused conductors of the motor cable.

Failure to follow these instructions will result in death or serious injury.

When the product is operated for the first time, there is a risk of unanticipated movements caused by, for example, incorrect wiring or unsuitable parameter settings. Releasing the holding brake can cause an unintended movement, for example, lowering of the load in the case of vertical axes.

WARNING

UNINTENDED MOVEMENT

- Verify that there are no persons or obstacles in the zone of operation when performing a test of the holding brake.
- Take appropriate measures to avoid damage caused by falling or lowering loads or other unintended movements.
- Run initial tests without coupled loads.
- Verify that a functioning emergency stop push-button is within reach of all persons involved in running tests.
- Anticipate movements in unintended directions or oscillations of the motor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Cable Specifications

For further information on cable specifications, refer to chapter Cables (*see page 100*).

Chapter 11

Verifying Installation

Verifying Installation

Verify the mechanical installation of the entire drive system:

- Does the installation meet the specified distance requirements?
- Did you tighten all fastening screws with the specified tightening torque?

Verify the electrical connections and the wiring:

- Did you connect all protective ground conductors?
- Do all fuses have the correct rating; are the fuses of the specified type?
- Did you connect all wires of the cables or insulate them?
- Did you properly connect and install all cables and connectors?
- Are the mechanical locks of the connectors correct and effective?
- Did you properly connect the signal wires?
- Are the required shield connections EMC-compliant?
- Did you take all measures for EMC compliance?
- Does the drive installation conform to all local, regional, and national electrical safety codes for the eventual placement of the equipment?

Verify that all covers and seals of the control cabinet are properly installed to meet the required degree of protection.

Part V

Commissioning

What Is in This Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
12	Overview	163
13	Integrated HMI	167
14	Commissioning Procedure	175
15	Tuning the Control Loops	183

Chapter 12

Overview

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
General	164
Commissioning Tools	166

General

You must recommission an already configured device if you want to use it under changed operating conditions.

Unsuitable settings or unsuitable data may trigger unintended movements, trigger signals, damage parts and disable monitoring functions. Some parameters and other operational data do not become active until after a restart.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Only start the system if there are no persons or obstructions in the zone of operation.
- Do not operate the drive system with undetermined parameter values.
- Never modify a parameter value unless you fully understand the parameter and all effects of the modification.
- Restart the drive and verify the saved operational data and/or parameter values after modification.
- Carefully run tests for all operating states and potential error situations when commissioning, upgrading or otherwise modifying the operation of the drive.
- Verify the functions after replacing the product and also after making modifications to the parameter values and/or other operational data.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

If the power stage is disabled unintentionally, for example as a result of a power outage, errors or functions, the motor is no longer decelerated in a controlled way.

WARNING

UNINTENDED EQUIPMENT OPERATION

Verify that movements without braking effect cannot cause injuries or equipment damage.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Applying the holding brake while the motor is running will cause excessive wear and loss of the braking force.

WARNING

LOSS OF BRAKING FORCE DUE TO WEAR OR HIGH TEMPERATURE

- Do not use the holding brake as a service brake.
- Do not exceed the maximum number of brake applications and the kinetic energy during braking of moving loads.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The metal surfaces of the product may exceed 70 °C (158 °F) during operation.

WARNING

HOT SURFACES

- Avoid unprotected contact with hot surfaces.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of hot surfaces.
- Verify that the heat dissipation is sufficient by performing a test run under maximum load conditions.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Rotating parts may cause injuries and may catch clothing or hair. Loose parts or parts that are out of balance may be ejected.

WARNING

MOVING, UNGUARDED EQUIPMENT

Verify that rotating parts cannot cause injuries or equipment damage.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

When the product is operated for the first time, there is a risk of unanticipated movements caused by, for example, incorrect wiring or unsuitable parameter settings. Releasing the holding brake can cause an unintended movement, for example, lowering of the load in the case of vertical axes.

WARNING

UNINTENDED MOVEMENT

- Verify that there are no persons or obstacles in the zone of operation when performing a test of the holding brake.
- Take appropriate measures to avoid damage caused by falling or lowering loads or other unintended movements.
- Run initial tests without coupled loads.
- Verify that a functioning emergency stop push-button is within reach of all persons involved in running tests.
- Anticipate movements in unintended directions or oscillations of the motor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The product can be accessed via different types of access channels. Simultaneous access via multiple access channels or the use of exclusive access may cause unintended equipment operation.

WARNING

UNINTENDED EQUIPMENT OPERATION

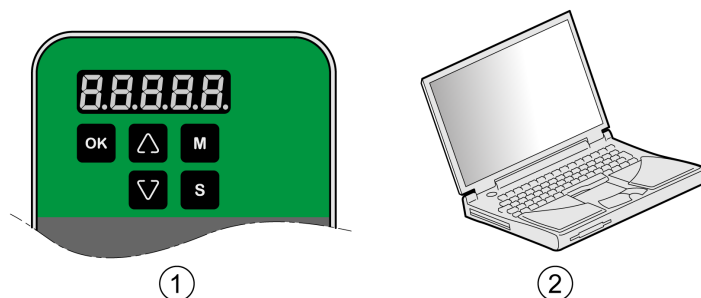
- Verify that simultaneous access via multiple access channels cannot cause unintended triggering or blocking of commands.
- Verify that the use of exclusive access cannot cause unintended triggering or blocking of commands.
- Verify that the required access channels are available.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Commissioning Tools

Overview

The following tools ([see page 84](#)) can be used for commissioning, parameterization, and diagnostics:



Item	Description
1	Integrated HMI
2	PC with commissioning software LXM26 DTM Library

Device settings can be duplicated. Stored device settings can be transferred to a device of the same type. Duplicating the device settings can be used if multiple devices are to have the same settings, for example, when devices are replaced.

Chapter 13

Integrated HMI

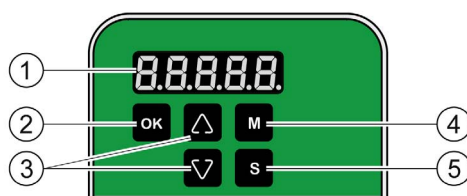
What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Overview	168
Integrated HMI Structure	169
7-Segment Display	170
Status Information Via the HMI	172

Overview

The integrated HMI allows you to edit parameters, start the operating mode Jog or perform autotuning via the integrated Human-Machine Interface (HMI). Diagnostics information (such as parameter values or error codes) can also be displayed. The individual sections on commissioning and operation include information on whether a function can be carried out via the integrated HMI or whether the commissioning software must be used.



Item	Description
1	5-digit 7-segment display
2	OK key
3	Arrow keys
4	M key
5	S key

Incorrect wiring of the motor connection may cause live wires to be exposed outside of the motor connector below the HMI.

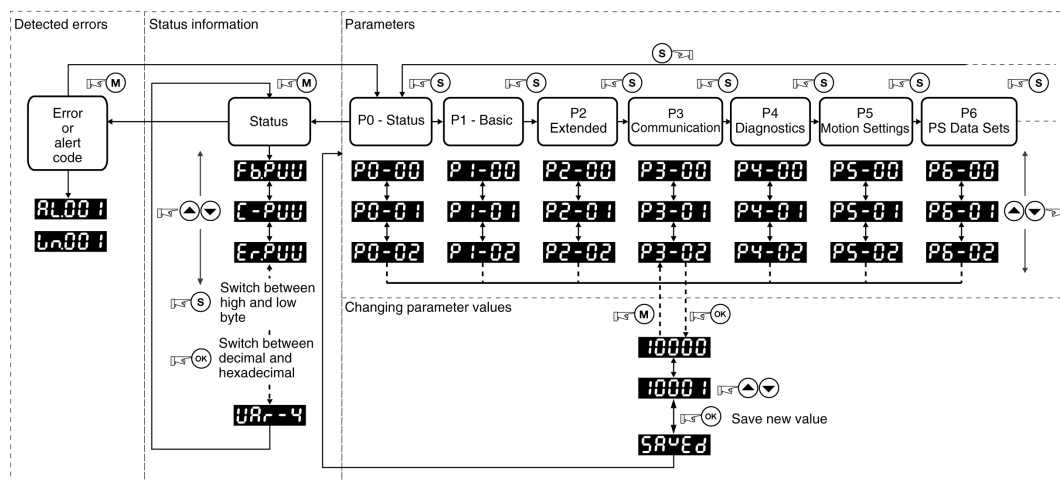
DANGER

ELECTRIC SHOCK CAUSED BY INCORRECT WIRING

- Verify that the protective ground connection (PE) of the device is connected to ground.
- Do not remove the cable end (ferrule) from the protective ground terminal (PE) of the motor connector until you are prepared to wire the protective ground conductor of the motor to the protective ground terminal (PE) of the motor connector.
- Verify that no bare metal of the wires is exposed outside of the motor connector housing when wiring the motor connector.
- Regularly, as part of a maintenance plan, assure that the motor wires are secured in the terminals of the motor connector due to vibration or other influences.

Failure to follow these instructions will result in death or serious injury.

Integrated HMI Structure



When the drive is powered on, the display shows the name of the selected status information function for approximately one second; after that, it displays the corresponding actual value or status value.

Element	Function
HMI display	The 5-digit 7-segment display shows actual values, parameter settings, status information, and error codes.
M key	The M key lets you switch between the type of information displayed: status information/actual values, error codes, and parameters. If an error is detected, the display shows the error code. If you press the M while the error is active, you can display other information; however, after approximately 20 seconds without interaction, the error code is displayed again.
S key	The S lets you scroll through the parameter groups. After you have selected a parameter and its value is displayed, you can use the S key to move the cursor to the left. The digit at the current cursor position flashes. The arrow keys let you change the value at the current cursor position.
Arrow keys	The arrow keys let you scroll through the actual values/status information and the parameters within a parameter group. Use the arrow keys to increase or decrease values.
OK key	After you have selected a parameter, press the OK key to display the current parameter value. The arrow keys let you change the displayed value. Pressing the OK key again saves the value.

7-Segment Display

Saving Settings

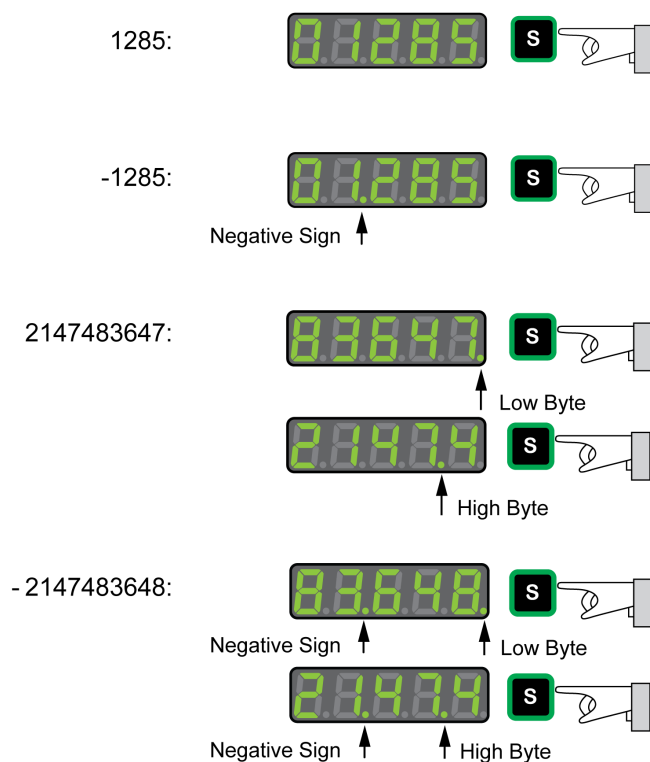
If you set a new parameter value and press the **OK** key, a message is displayed for approximately one second to provide feedback.

7-segment display	Description
<i>S R U E d</i>	The new parameter value was successfully saved.
<i>r - O L Y</i>	The parameter value is a read-only value and cannot be saved (Read-Only).
<i>P r o t</i>	Changing a parameter value requires exclusive access. See chapter Access Channels (see page 268).
<i>O u t - r</i>	The new parameter value is outside the permissible value range (Out of range).
<i>S r v O n</i>	The new parameter value can only be saved when the power stage is disabled (Servo On).
<i>P o - O n</i>	The new parameter value becomes active the next time the product is powered on (Power On).
<i>E r r o r</i>	Displayed whenever a value you have entered for a parameter is, for various reasons, rejected by the drive.

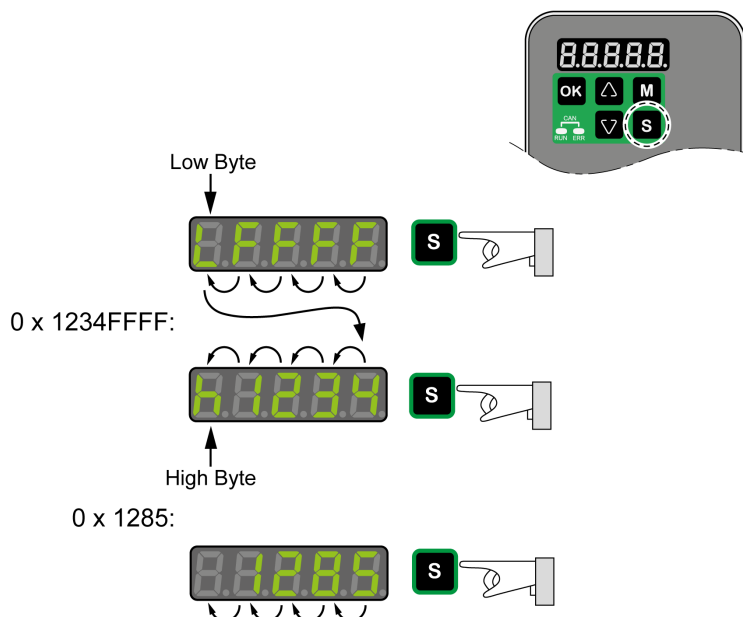
Representation of Numerical Values on the 7-Segment Display

The illustration below shows the decimal representation of a 16-bit value and a 32-bit value as a positive value and as a negative value each.

Example of representation of decimal values



Example of representation of hexadecimal values



Changing the Sign Via the 7-Segment Display

7-segment display	Description
2 4 6 8 0 2 4. 6 8 0 ? 3 4 3 E ? C b C 2	You can change the sign of a value by holding down the S key for a period of more than 2 seconds. Negative decimal values are represented with a dot between the second and the third position. Negative hexadecimal values are represented as a two's complement.

Alert Messages and Error Messages on the 7-Segment Display

7-segment display	Description
? n n n n	If an alert condition is detected, Wnnnn is displayed. Win identifies the code as an alert. The subsequent 3 digit nnn represent the number of the alert. See chapter Alert Codes and Error Codes (see page 344) for a list of alerts.
AL n n n	If an error is detected ALnnn is displayed. AL identifies the code as a detected error. The subsequent 3 digit nnn represent the error number. For a list of error codes, refer to Alert Codes and Error Codes (see page 344).
S? D P	The display shows STOP if exclusive access is enabled while the power stage is still enabled. For further information on access channels, refer to Access Channels (see page 268).

Status Information Via the HMI

After you have powered on the drive, status information is displayed via the HMI. Use the parameter **P0-02** to select the type of status information to be displayed. For example, if you set the parameter **P0-02** to the value 7, the speed of rotation of the motor after is displayed after you have powered on the drive.

Setting P0-02	Description
0	Actual position (with gear ratio applied) in the unit PUU
1	Target position (with gear ratio applied) in the unit PUU
2	Deviation between actual position and target position (with gear ratio applied) in the unit PUU
3	Actual position in motor increments (1280000 pulses/revolution)
4	Target position in motor increments (1280000 pulses/revolution)
5	Deviation between actual position and target position in motor increments (1280000 pulses/revolution)
6	Reference value in kilopulses per second (kpps)
7	Actual velocity in rpm
8	Voltage for target velocity in V
9	Target velocity in rpm
10	Voltage for target torque in V
11	Target torque in percent of continuous motor current
12	Available current overhead used in percent of continuous motor current
13	Peak current overhead consumed since the last power cycle of the drive in percent of continuous motor current (maximum value of occurring in setting 12 since last power cycle)
14	Mains voltage in V
15	Ratio of load inertia and motor inertia (divided by 10)
16	Power stage temperature in degrees Celsius (°C)
17	Resonance frequency in Hz
18	Absolute pulse number relative to encoder
19	Mapping parameter 1: Content of parameter P0-25 (mapping target is specified via parameter P0-35)
20	Mapping parameter 2: Content of parameter P0-26 (mapping target is specified via parameter P0-36)
21	Mapping parameter 3: Content of parameter P0-27 (mapping target is specified via parameter P0-37)
22	Mapping parameter 4: Content of parameter P0-28 (mapping target is specified via parameter P0-38)
23	Status indication 1: Content of parameter P0-09 (the status information to be displayed is specified by parameter P0-17)
24	Status indication 2: Content of parameter P0-10 (the status information to be displayed is specified by parameter P0-18)
25	Status indication 3: Content of parameter P0-11 (the status information to be displayed is specified by parameter P0-19)
26	Status indication 4: Content of parameter P0-12 (the status information to be displayed is specified by parameter P0-20)
27	Reserved
39	Status of digital inputs (content of P4-07)
40	Status of digital outputs (content of P4-09)
41	Drive status (content of P0-46)
42	Operating mode (content of P1-01)
49	Actual position encoder (content of P5-18)
50	Target velocity in rpm

Setting P0-02	Description
53	Target torque in 0.1 percent of the nominal torque
54	Actual torque in 0.1 percent of the nominal torque
55	Actual torque in 0.01 A
77	Target velocity in rpm in operating modes PT and PS
96	Firmware version and firmware revision of drive (P0-00 and P5-00)
111	Number of detected errors

Chapter 14

Commissioning Procedure

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Commissioning Software	176
Setting the Device Address, Baud Rate and Connection Settings	177
Verifying the Direction of Movement	179
Test Operation in Operating Mode Velocity (V)	181

Commissioning Software

The commissioning software LXM26 DTM Library has a graphic user interface and is used for commissioning, diagnostics, and testing settings.

Online Help

The commissioning software offers help functions, which can be accessed via **? - Help Topics** or by pressing the F1 key.

Source of Commissioning Software

The latest version of the commissioning software LXM26 DTM Library is available for download from the Internet.

<http://www.schneider-electric.com>

Setting the Device Address, Baud Rate and Connection Settings

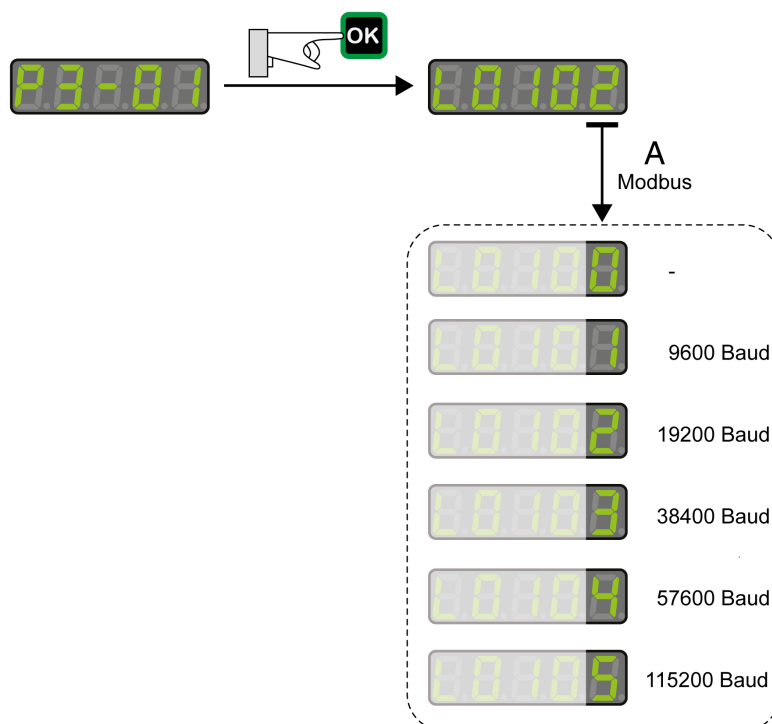
Each device is identified by a unique address. Each device must have its own unique node address, which may only be assigned once in the network. The transmission rate (baud rate) must be the same for all devices in the network.

Use the parameter P3-00 to set the Modbus device address.

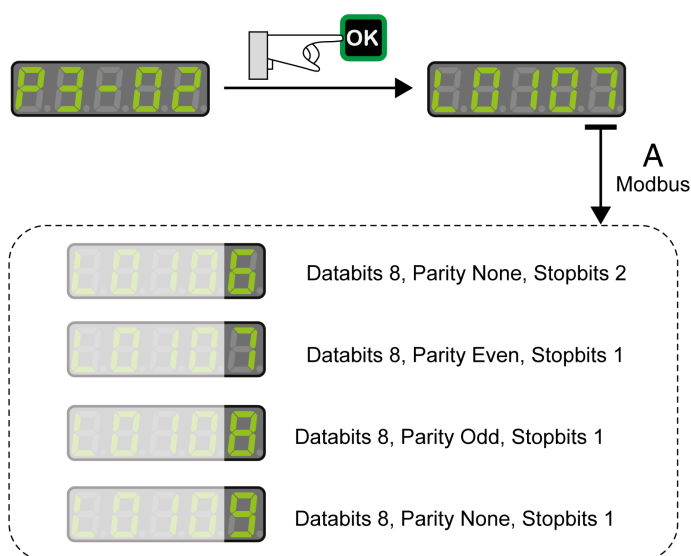
Use the parameter P3-01 to set the baud rate.

Use the parameter P3-02 to set the connection settings.

Setting the baud rate:



Modbus Connection Settings



! WARNING

UNINTENDED EQUIPMENT OPERATION

- Verify that there is only one master controller configured on the network or remote link.
- Verify that all devices have unique addresses.
- Confirm that the device address is unique before placing the system into service.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P3-00 ADR	Device Address Modbus Applicable operating mode: PT, PS, V, T The device address must be unique. Changed settings become active the next time the product is powered on.	- 1 127 247 Decimal	u16 RW per.	Modbus 400 _h
P3-01 BRT	Transmission Rate Applicable operating mode: PT, PS, V, T This parameter is used to set the data transmission rate. Changed settings become active the next time the product is powered on.	- 0 _h 102 _h 405 _h Hexadecimal	u16 RW per.	Modbus 402 _h
P3-02 PTL	Modbus Connection Settings Applicable operating mode: PT, PS, V, T This parameter specifies the Modbus connection settings. Changed settings become active the next time the product is powered on.	- 6 _h 7 _h 9 _h Hexadecimal	u16 RW per.	Modbus 404 _h
P3-03 FLT	Detected Modbus Communication Errors - Handling Applicable operating mode: PT, PS, V, T This parameter specifies the response of the drive to a detected communication error. Value 0: Detected alert Value 1: Detected error	- 0 _h 0 _h 1 _h Hexadecimal	u16 RW per.	Modbus 406 _h
P3-04 CWD	Modbus Connection Monitoring Applicable operating mode: PT, PS, V, T This parameter specifies the maximum permissible duration for communication timeout. When this time has elapsed, the communication timeout is treated as a detected error. Setting this parameter to 0 to disables connection monitoring.	ms 0 0 20000 Decimal	u16 RW per.	Modbus 408 _h
P3-07 CDT	Modbus Response Delay Time Applicable operating mode: PT, PS, V, T This parameter specifies the time delay with which the drive responds to the Modbus master.	0.5 ms 0 0 1000 Decimal	u16 RW per.	Modbus 40E _h

Verifying the Direction of Movement

Direction of Movement

⚠ WARNING

UNINTENDED MOVEMENT CAUSED BY INTERCHANGED MOTOR PHASES

Do not interchange the motor phases.

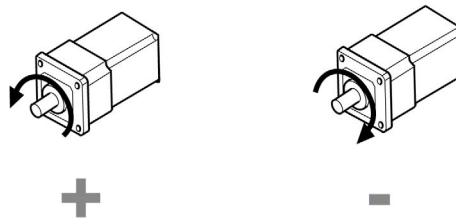
Failure to follow these instructions can result in death, serious injury, or equipment damage.

If your application requires an inversion of the direction of movement, you may parameterize the direction of movement.

Movements are made in positive or in negative directions.

Definition of the direction of movement: Positive direction of movement is when the motor shaft rotates counterclockwise as you look at the end of the protruding motor shaft.

Direction of movement with factory settings



Verifying the Direction of Movement

- Start the operating mode Jog. (HMI: **P 4 - 0 5**)
The HMI displays the velocity in the unit rpm for the operating mode JOG.
- Set a velocity suitable for your application and conform with the OK key.
The HMI displays **J O G**.

Movement in positive direction:

- Press the **Up Arrow** key.
A movement is made in positive direction.

Movement in negative direction:

- Press the **Down Arrow** key.
A movement is made in negative direction.

Press the M key to terminate the operating mode Jog.

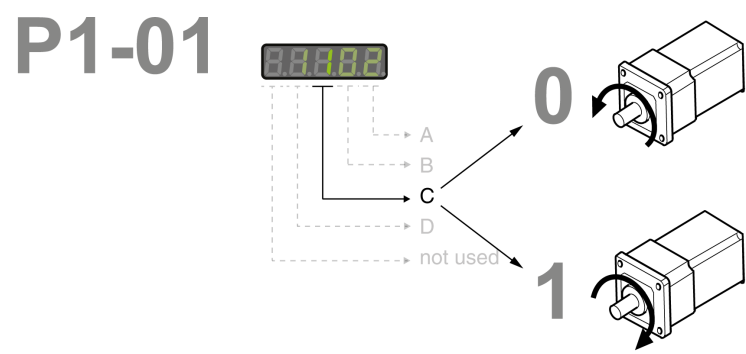
Changing the Direction of Movement

If the expected direction of movement and the actual direction of movement are not identical, you can invert the direction of movement.

- Inversion of direction of movement is not activated:
Movements are made in positive direction with positive target values.
- Inversion of direction of movement is activated:
Movements are made in positive direction with negative target values.

The parameter **P1-01 C = 1** allows you to invert the direction of movement.

Changing the direction of movement



Test Operation in Operating Mode Velocity (V)

- Select the operating mode Velocity (V) via the parameter $P1-01 = 2$. Refer to Setting the Operating Mode ([see page 286](#)).
- Set the parameter $P1-01$ to $D=1$. This assigns defaults to the signal input functions for the operating mode Velocity (V), DI6...DI8 presets must be modified for this test.
New settings for the parameter $P1-01$ do not become active until the drive is powered on the next time.
- Restart the drive.
- Select the following signal input functions via the parameters P2-10 to P2-17:

Digital input	Parameter	Setting	Signal	Function	Pin at CN1
DI1	P2-10	0101 _h	SON	Enable power stage	9
DI2	P2-11	0109 _h	TRQLM	Activate Torque Limitation	10
DI3	P2-12	0114 _h	SPD0	Velocity Reference Value Bit 0	34
DI4	P2-13	0115 _h	SPD1	Velocity Reference Value Bit 1	8
DI5	P2-14	0102 _h	FAULT_RESET	Fault Reset	33
DI6	P2-15	0 _h	-	-	32
DI7	P2-16	0 _h	-	-	31
DI8	P2-17	0 _h	-	-	30

For further information on the settings, refer to Setting the Digital Signal Inputs ([see page 270](#)).

Error Messages HMI

If the default presets of the signal inputs OPST, CWL(NL), and CCWL(PL/LIMP) are still present, the following error codes can be displayed:

- AL013: Parameter $P2-17$ not set to 0 (deactivated).
- AL014: Parameter $P2-15$ not set to 0 (deactivated).
- AL015: Parameter $P2-16$ not set to 0 (deactivated).

For further information on error messages, refer to Diagnostics and Troubleshooting ([see page 344](#)).

Target Velocity

The target velocity is selected via the signal input functions SPD0 (least significant bit) and SPD (most significant bit):

	Signal state of the digital signal inputs		Target velocity via:		Range
	SPD1	SPD0			
S1	0	0	External analog signal	Voltage between V_REF (pin 42) and GND (pin 44)	-10 ... 10 Vdc
S2	0	1	Internal parameters	P1-09	-60000 ... 60000 x 0.1 rpm
S3	1	0		P1-10	
S4	1	1		P1-11	

- Enable the power stage via DI1 (SON).
If DI3 (SPD0) and DI4 (SPD1) are deactivated, the target velocity is supplied via the analog input V_REF.
- Activate DI3 (SPD0).
The target velocity is supplied via the parameter $P1-09$. The factory setting for the target velocity is 1000 rpm.

Chapter 15

Tuning the Control Loops

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Tuning the Control Loops	184
Easy Tuning	185
Comfort Tuning	186
Manual Tuning	191

Tuning the Control Loops

Autotuning and manual tuning move the motor in order to tune the control loops. Incorrect parameters may cause unintended movements or the loss of monitoring functions.

WARNING

UNINTENDED MOVEMENT

- Only start the system if there are no persons or obstructions in the zone of operation.
- Verify that the values for the parameters `P9-26` and `P9-27` do not exceed the available movement range.
- Verify that the parameterized movement ranges are available.
- In determining the available movement range, consider the additional distance for the deceleration ramp in the case of an EMERGENCY STOP.
- Verify that the parameter settings for a Quick Stop are correct.
- Verify correct operation of the limit switches.
- Verify that a functioning emergency stop push-button is within reach of all persons involved in the operation.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Autotuning adapts the control performance of the drive to the mechanical system used and optimizes the control loop settings appropriately. External factors such as a load at the motor are considered. The control loop settings can also be optimized by using manual tuning.

Two autotuning methods and manual tuning are provided for control loop optimization:

- **Easy Tuning:** This type of autotuning is performed without user intervention. For most applications, Easy Tuning yields good, highly dynamic results.
- **Comfort Tuning:** This type of autotuning is performed with user intervention. You can select optimization criteria and set parameters for movement, direction, and velocity.
- **Manual Tuning:** This type of tuning allows you to perform test movements and optimize the control loop settings using the Scope function.

Easy Tuning

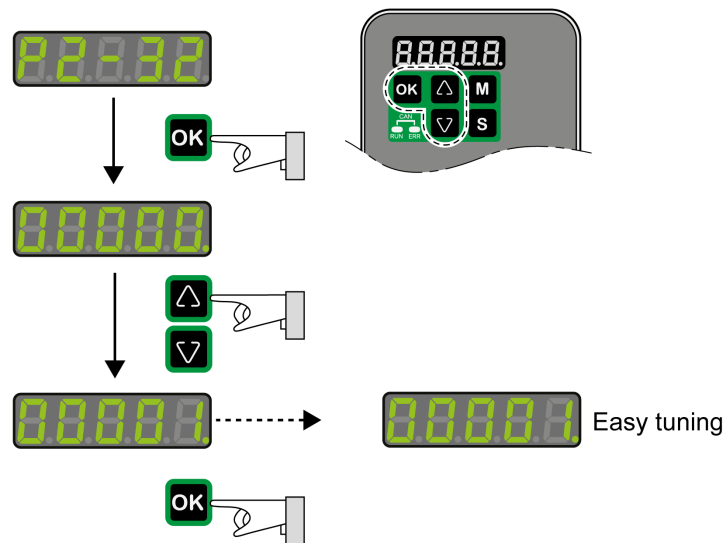
Easy Tuning is started via the HMI or the commissioning software LXM26 DTM Library.

Easy Tuning requires an available movement range of 5 revolutions. During Easy Tuning, movements of 2.5 revolutions are performed in positive direction of movement and 2.5 revolutions in negative direction of movement. If this movement range is not available, you must use Comfort Tuning. Comfort Tuning allows you to set the movement range and the direction of movement manually.

Easy Tuning can be used for a ratio of motor inertia to load inertia of up to 1:50.

Performing Easy Tuning

Set the parameter P2-32 to 1 to perform Easy Tuning.



After you have started Easy Tuning via P2-32, the display of the HMI shows the progress as a percentage from **tn000** to **tn100**.

Press the **M** button of the HMI to cancel autotuning.

If autotuning completes successfully, the display of the HMI shows the message **done**.

Press the **OK** key of the HMI to save the control loop parameters. The display of the HMI briefly shows the message **saved**.

Press the **M** key of the HMI to discard the autotuning results.

If autotuning does not complete successfully, the display of the HMI shows the message **ERROR**. The cause can be read with the parameter P9-30.

The parameter P9-37 provides additional information on the last event that occurred during autotuning.

Comfort Tuning

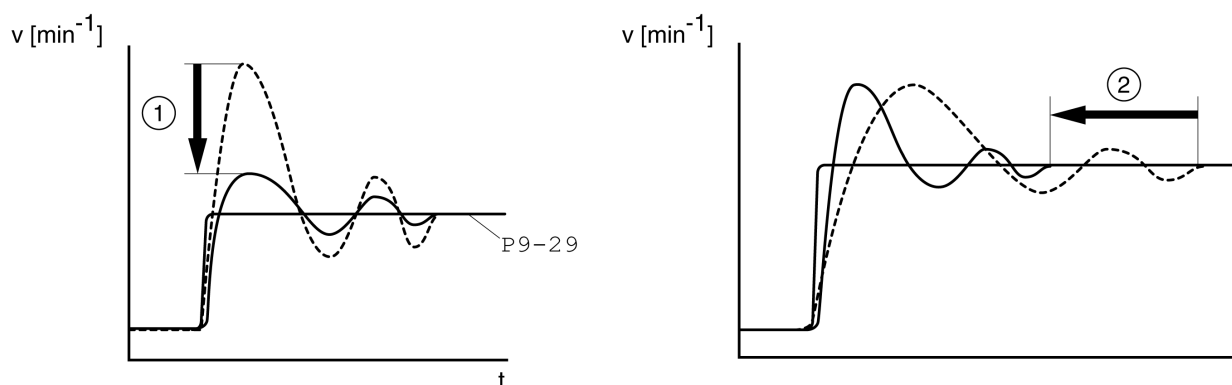
Comfort Tuning allows you to select optimization criteria and set values for the movement.

Optimization Criteria for Comfort Tuning

Comfort Tuning allows you to select an optimization criterion for autotuning. The following optimization criteria are available:

- Optimization of the control loop parameters for minimum settling time with vibration suppression
- Optimization of the control loop parameters for minimum overshoot with vibration suppression
- Optimization of the control loop parameters for minimum settling time without vibration suppression
- Optimization of the control loop parameters for minimum overshoot without vibration suppression

The illustration below shows optimization for minimum overshoot and optimization for minimum settling time.



Item	Description
1	Optimization for minimum overshoot
2	Optimization for minimum settling time

Vibration suppression compensates resonance frequencies of the mechanical system. The option Vibration Suppression is available for both optimization criteria.

Parameters for the Movement for Comfort Tuning

The following settings must be made for Comfort Tuning:

- Direction of movement
- Velocity
- Acceleration and deceleration
- Movement range
- Smoothing

These values must be as close as possible to the values used in the actual application. If you enter implausible values, Comfort Tuning is canceled.

Setting the Direction of Movement

Set the direction of movement via the parameter P9-20.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-20 LTNCYCLE	Autotuning - Direction of Movement Applicable operating mode: PT, PS, V This parameter sets the direction of movement for autotuning. Value 0: Both directions of movement Value 2: One direction of movement	- 0 0 3 Decimal	s16 RW -	Modbus A28 _h

Setting the Velocity

Set the velocity via the parameter P9-29.

The velocity must be between 10 ... 100 % of the nominal velocity n_N .

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-29 LTNVCRUISE	Autotuning - Velocity Applicable operating mode: PT, PS, V Bits 0 ... 15: Velocity for positive direction of movement Bits 16 ... 31: Velocity for negative direction of movement	0.1rpm 0.1rpm - - - Decimal	u32 RW -	Modbus A3A _h

Setting Acceleration and Deceleration

Set the acceleration and the deceleration with the P9-31 parameter.

The value for the acceleration and the value for the deceleration must be between $t_{\min}$ and $t_{\max}$:

$$t_{\min} = \frac{100}{90} 20\pi \frac{J_M + J_{\text{load}}}{M_{\max}} \quad t_{\max} = \frac{100}{33} 20\pi \frac{J_M + J_{\text{load}}}{M_N}$$

J_M = Moment of inertia of the motor in kg cm²

J_{load} = Moment of inertia of the load in kg cm²

$M_{\max}$ = Peak torque in Nm

M_N = Nominal torque in Nm

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-31 PTACCDEC	Autotuning - Acceleration and Deceleration Applicable operating mode: PT, PS, V Bits 0 ... 15: Acceleration for Autotuning Bits 16 ... 31: Deceleration for Autotuning	ms ms 6 6 6000 6000 65500 65500 Decimal	u32 RW -	Modbus A3E _h

Setting the Movement Range

Set the movement range via parameters P9-26 and P9-27.

The movement range must be sufficiently large to allow for a constant movement at the set speed in addition to the acceleration phase and the deceleration phase.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-26 PTPOS	Autotuning - Movement Range in Direction 1 Applicable operating mode: PS This parameter specifies the movement range for autotuning in direction of movement 1. The sign of the value determines the direction of movement: Positive value: Positive direction of movement as set via parameter P1-01 Negative value: Negative direction of movement as set via parameter P1-01 See parameter P9-20 to select one direction of movement or both directions of movement for Comfort Tuning.	PUU -2147483647 0 2147483647 Decimal	s32 RW -	Modbus A34 _h
P9-27 PTNEG	Autotuning - Movement Range in Direction 2 Applicable operating mode: PS This parameter specifies the movement range for autotuning in direction of movement 2. The sign of the value determines the direction of movement: Positive value: Positive direction of movement as set via parameter P1-01 Negative value: Negative direction of movement as set via parameter P1-01 See parameter P9-20 for Comfort Tuning in a single or in both directions of movement. See parameter P9-20 to select one direction of movement or both directions of movement for Comfort Tuning.	PUU -2147483647 0 2147483647 Decimal	s32 RW -	Modbus A36 _h

Setting Smoothing

Comfort Tuning uses S-curve smoothing by default. The value for smoothing via the S-curve is optimized during Comfort Tunings.

The parameter P9-23 allows you to change from automatic smoothing to manual smoothing.

The following options are available for manual smoothing:

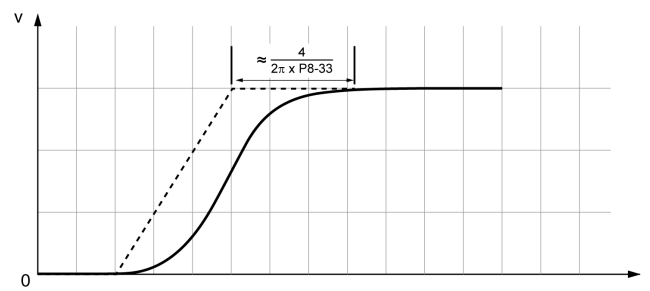
- No smoothing
- Smoothing via low-pass filter with a fixed value
- Smoothing via S-curve with a fixed value

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-23 LTNSTIFF	Defines which values are used for the position command filters. Applicable operating mode: PT, PS, V Value 0: Automatic smoothing via S-curve optimization of the value Value 1: Manual smoothing	- 0 0 1 Decimal	u16 RW -	Modbus A2E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-34 MOVESMOOTH-MODE	Smoothing Filter for Operating modes PT and PS - Type Applicable operating mode: PT, PS Value 0: No smoothing Value 1: LPF smoothing Value 2: S-curve smoothing Setting can only be changed if power stage is disabled.	- 0 2 2 Decimal	u16 RW per.	Modbus 944 _h

The illustration below shows the movement during Comfort Tuning if smoothing via the low-pass filter is used:

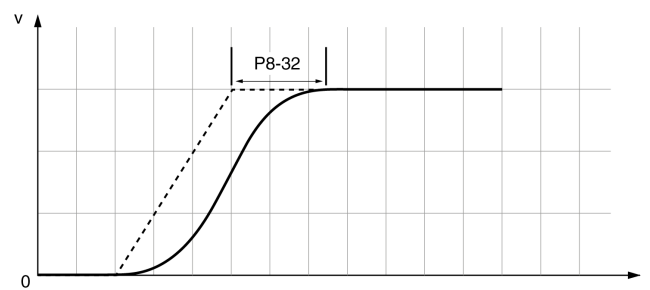
Comfort Tuning with smoothing via low-pass filter



Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-33 MOVESMOOTH-LPFHZ	Low Pass Filter Setting Applicable operating mode: PT, PS	Hz 1 5000 5000 Decimal	u16 RW per.	Modbus 942 _h

The illustration below shows the movement during Comfort Tuning if smoothing via an S-curve is used:

Comfort Tuning with smoothing via S-curve



Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-32 MOVES- MOOTHAVG	S-Curve Setting Applicable operating mode: PT, PS Setting can only be changed if power stage is disabled.	0.01 ms 25 1500 25600 Decimal	u32 RW per.	Modbus 940 _h

Performing Comfort Tuning

Start Comfort Tuning by selecting the required method via the parameter P2-32.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-32 ATMODE	Autotuning Applicable operating mode: PT, PS, V This parameter is used to start autotuning with the selected autotuning method. Value 0: Stop Autotuning Value 1: Easy Tuning Value 2: Comfort Tuning [minimum settling time, vibration suppression] Value 3: Comfort Tuning [minimum overshoot, vibration suppression] Value 52: Comfort Tuning [minimum settling time, no vibration suppression] Value 53: Comfort Tuning [minimum overshoot, no vibration suppression]	- 0 0 56 Decimal	u16 RW -	Modbus 340 _h

If you want Comfort Tuning in both directions, set parameter P9-20 to 0. Then set the parameters P9-26 and P9-27 to the same values, but with different signs (for example, P9-26 = -20000 and P9-27 = +20000). The value determines the movement range in both directions.

If you want Comfort Tuning in a single direction, set parameter P9-20 to 2. Then set the parameters P9-26 and P9-27 to the same values. The sign of the value determines the direction for Comfort Tuning. For example, if you set P9-26 = -20000 and P9-27 = -20000, Comfort Tuning is performed in negative direction of movement with a movement range of 20000 PUU.

NOTE: If you do not enter consistent values for parameters P9-26 and P9-27, the autotuning is unsuccessful. Parameter P9-30 contains the information on the unsuccessful autotuning attempt.

After you have started the required Comfort Tuning method via P2-32, the display of the HMI shows the progress as a percentage from **E n 000** to **E n 100**.

Press the **M** button of the HMI to cancel autotuning.

If autotuning completes successfully, the display of the HMI shows the message **d o n ?**.

Press the **OK** key of the HMI to save the control loop parameters. The display of the HMI briefly shows the message **???? d**.

Press the **M** key of the HMI to discard the autotuning results.

If autotuning does not complete successfully, the display of the HMI shows the message **E ?? 0 ?**. The cause can be read with the parameter P9-30.

The parameter P9-37 provides additional information on the last event that occurred during autotuning.

Manual Tuning

Manual tuning is performed in the operating mode Internal Profile. Manual tuning allows you to perform test movements and optimize the control loop settings using the Scope function.

NOTE: Manual tuning should only be attempted by trained persons who are familiar with and understand the contents of this manual and all other pertinent product documentation. These persons must have sufficient technical training, knowledge, and experience and be able to foresee and detect potential hazards and issues that may be caused by manual tuning, by changing the settings and by the mechanical, electrical, and electronic equipment of the entire system in which the product is used. No responsibility is assumed by Schneider Electric for any consequences arising out of the use of manual tuning.

Procedure for Manual Tuning

The control loop parameters are tuned in the following sequence:

Step	Item	Parameters
1	Derivative gain	P8-00 (LTND)
2	Low-pass filter	P8-14 (NLFILTDAMPING) P8-15 (NLFILTT1)
3	Retuning of the derivative gain	P8-00 (LTND)
4	Proportional gain	P8-03 (LTNP)
5	Derivative-integral gain	P8-02 (LTNIV)
6	Integral gain	P8-01 (LTNI)
7	Compensation of the flexibility of the mechanical system	P8-05 (NLAFFLPFHZ) P8-20 (NLPEAFF)

Depending on the requirements concerning the control performance, steps 2 and 3 can be omitted. Perform a movement in both directions after each of the steps below to check the recorded parameter values on the Scope tab of the commissioning software LXM26 DTM Library.

Step 1: Setting the Derivative Gain

The objective of tuning the derivative gain is to achieve a current ripple that is as low as possible. The optimum value primarily depends on the load.

Criteria for a well-tuned derivative gain include:

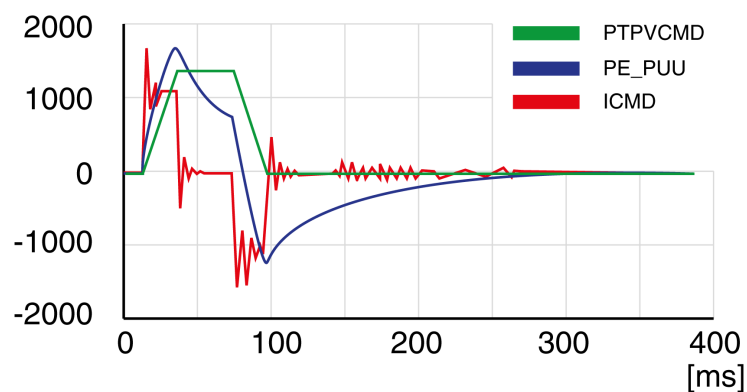
- For loads less than twice the rotor inertia: 5 % of the nominal current may be acceptable
- For greater loads: 10 % of the nominal current may be acceptable

The derivative gain is set via parameter P8-00 (LTND).

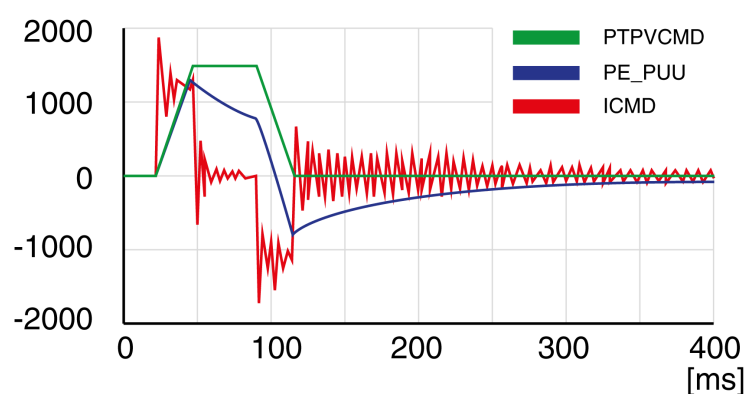
Procedure:

- Set the value of parameter P8-03 (LTNP) to 150 (corresponds to 15 Hz).
- Set the value of parameter P8-01 (LTNI) to 0.
- Set the value of parameter P8-02 (LTNIV) to 0.
- Progressively increase the value of parameter P8-00 (LTND) until the oscilloscope shows oscillation of the reference current, P11-11 (TCMD).

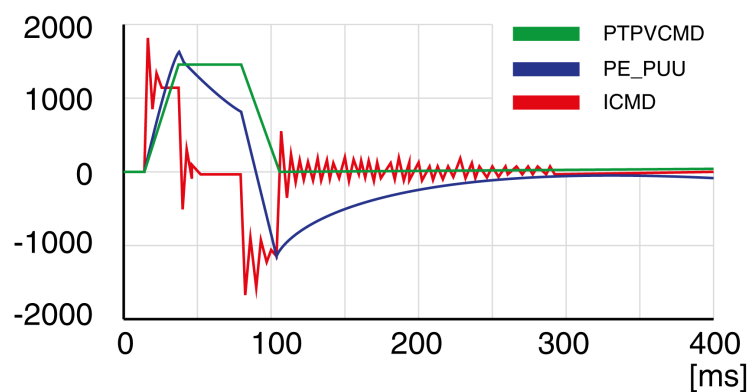
Example P8-00 (LTND) set to 1340 (134 Hz)



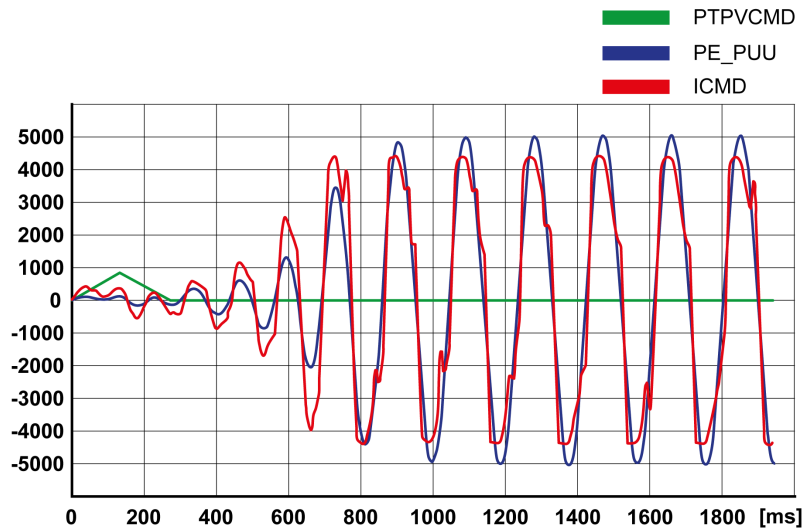
Example P8-00 (LTND) set too high at 2000 (200 Hz)



Example P8-00 (LTND) OK at 1500 (150 Hz)



Example P8-00 (LTND) set too low at 100 (10 Hz)



NOTE: The process of tuning requires trials of successive approximations. Values that are too high or too low relative to the other relevant values might cause instability. If it is necessary to have a low or high value of the parameter in the preceding example, you may need to adjust the values of the other relevant parameters to compensate and achieve a stable system.

Step 2: Setting the Low-Pass Filter

Setting the low-pass filter is an optional step in manual tuning of the control loop parameters. The low-pass filter parameters are optimized after you have tuned the derivative gain. The objective of tuning the low-pass filter parameters is to suppress high-frequency resonance and reduce the response time of the control loops to a minimum.

The parameter P8-14 (NLFILTDAMPING) maintains the bandwidth of the low-pass filter up to the cutoff frequency. The parameter value is expressed as a percentage. The parameter P8-15 (NLFILTT1) sets the inverse frequency of the cutoff frequency. The parameter P8-14 (NLFILTDAMPING) can also be used independently to allow for a certain degree of compensation of system-related bandwidth limits.

Criteria for a well-tuned low-pass filter include:

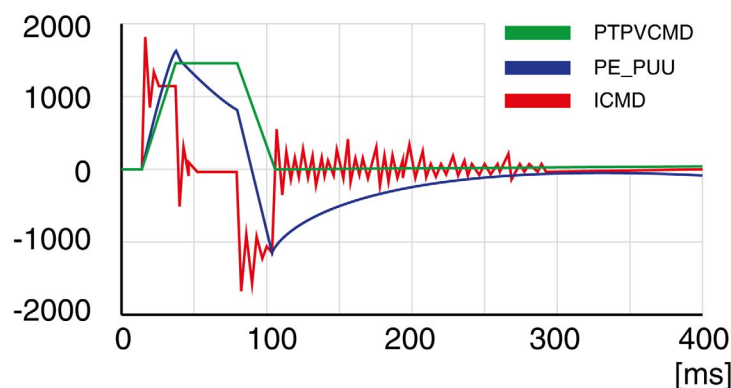
- The value of parameter P8-14 (NLFILTDAMPING) is as high as possible.
- The value of parameter P8-15 (NLFILTT1) is as low as possible.

The low-pass filter is set via parameters P8-14 (NLFILTDAMPING) and P8-15 (NLFILTT1).

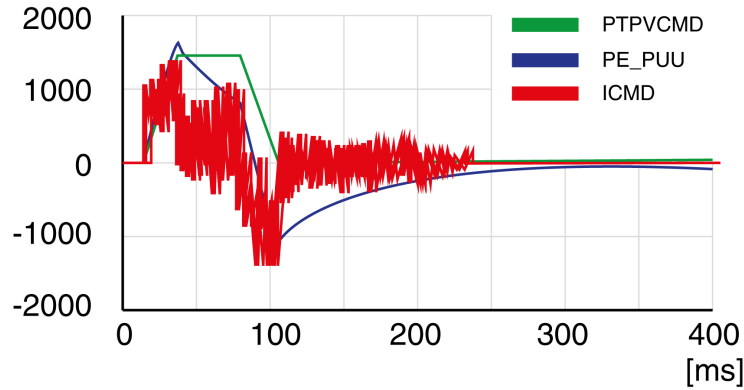
Procedure:

- Progressively increase the value of parameter P8-14 (NLFILTDAMPING) until the oscilloscope shows noise and/or oscillation of the reference current, P11-11 (TCMD).
- Progressively decrease the value of parameter P8-15 (NLFILTT1) until the oscilloscope shows noise and/or oscillation of the reference current P11-11 (TCMD).
- Increase the value of parameter P8-15 (NLFILTT1) by 20 %, however, by at least 0.05 ms.

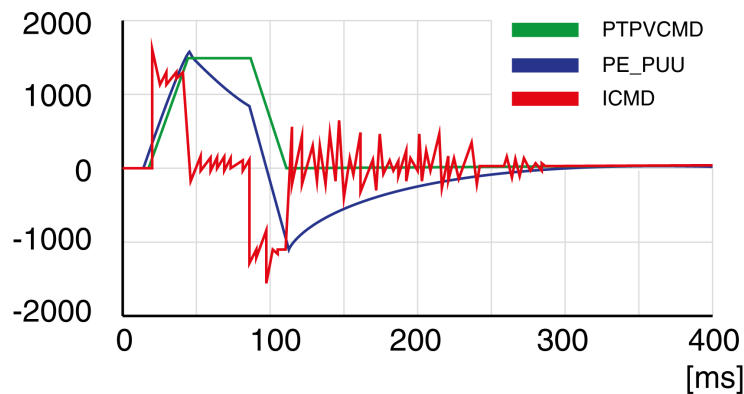
Example P8-14 (NLFILTDAMPING) OK (75 %)



Example P8-15 (NLFILTT1) too low (0.5 ms)



Example P8-15 (NLFILTT1) OK (1.2 ms)



Step 3: Re-Tuning of the Derivative Gain

If you have changed the low-pass filter values in parameters P8-14 (NLFILTDAMPING) and P8-15 (NLFILTT1), the derivative gain can be set to a greater value via parameter P8-00 (LTND). Follow the procedure described in step 1.

The objective of tuning the proportional gain is to get a constant and low position deviation in the acceleration phase, the constant velocity phase, and the deceleration phase and to have no oscillations during the transitions between these phases. In the oscilloscope, this is indicated by a shape that is as square and as flat as possible.

Criteria for a well-tuned proportional gain include:

- No or minimum overshoot of position deviation
- No or minimum current ripple
- No or minimum oscillations at standstill

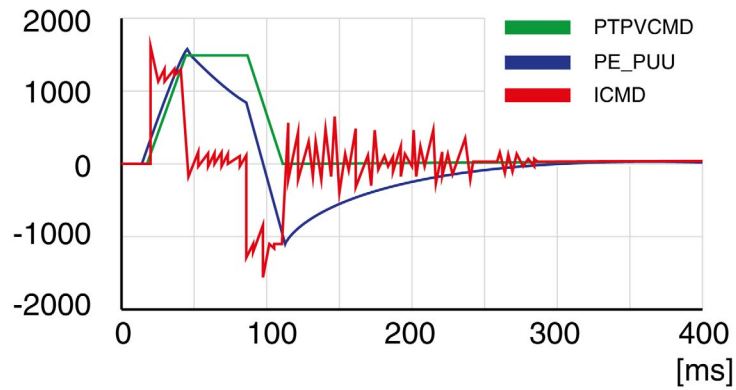
Step 4: Setting the Proportional Gain

The proportional gain is set via parameter P8-03 (LTNP).

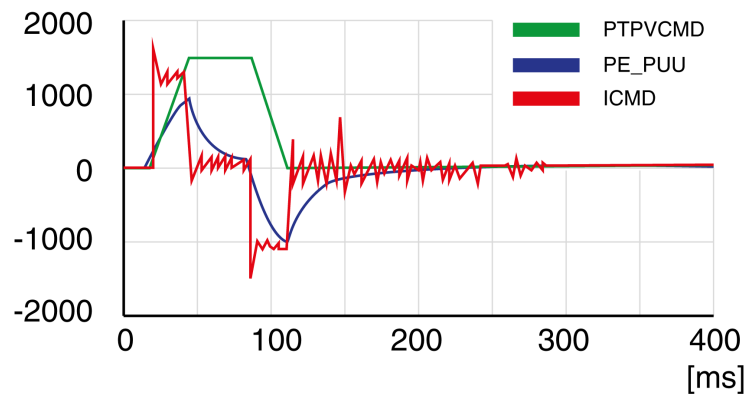
Procedure:

- Progressively increase the value of parameter P8-03 (LTNP) to find the optimum value. The figures below show examples of the plot as the value approaches the optimum value.

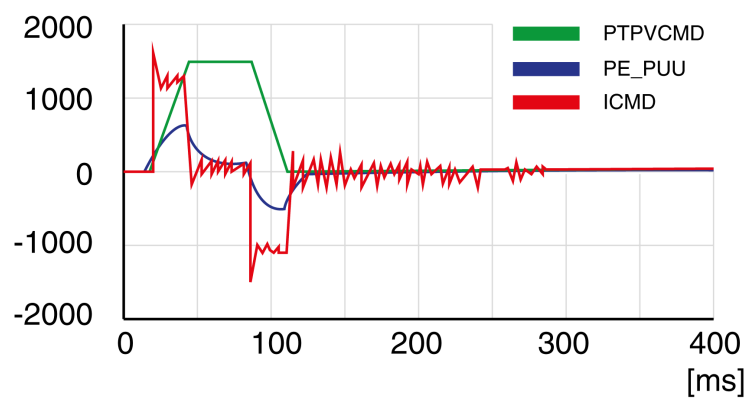
Example P8-03 (LTNP) starting value (13 Hz)



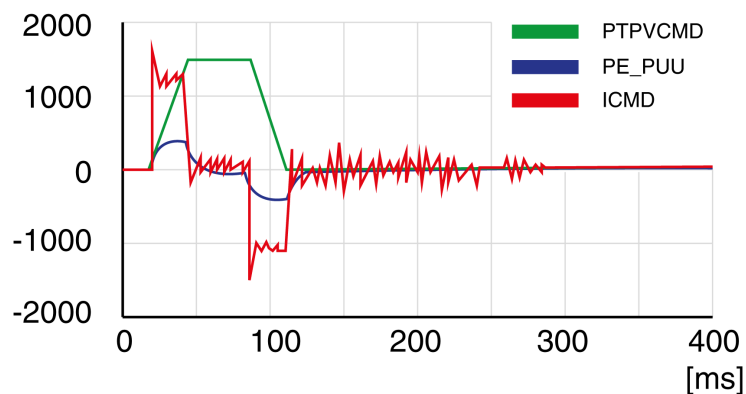
Example P8-03 (LTNP) position deviation decreased (25 Hz)



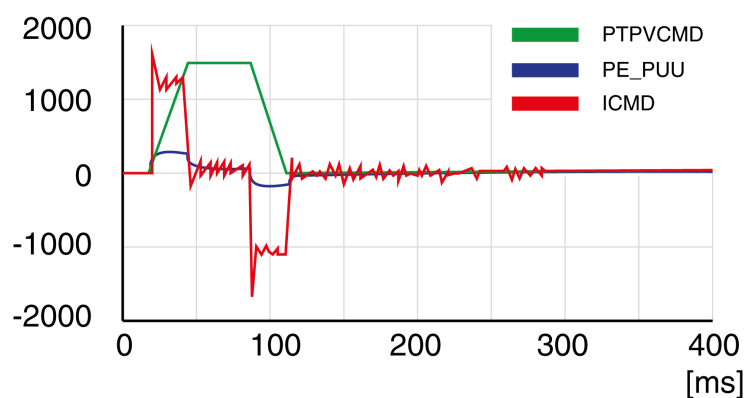
Example P8-03 (LTNP) position deviation further decreased (35 Hz)



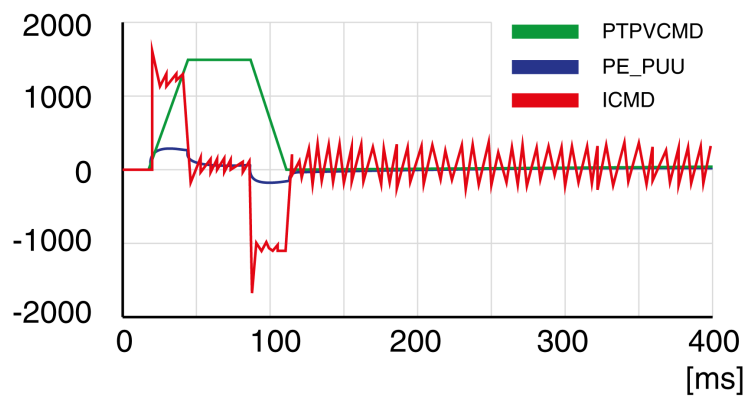
Example P8-03 (LTNP) position deviation further decreased (45 Hz)



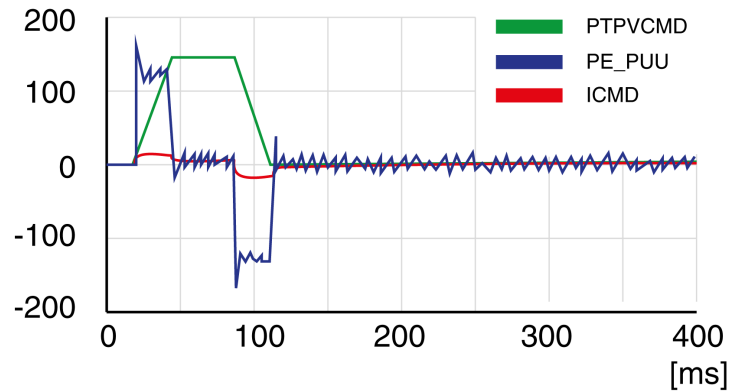
Example P8-03 (LTNP) value too high - oscillation at standstill (65 Hz)



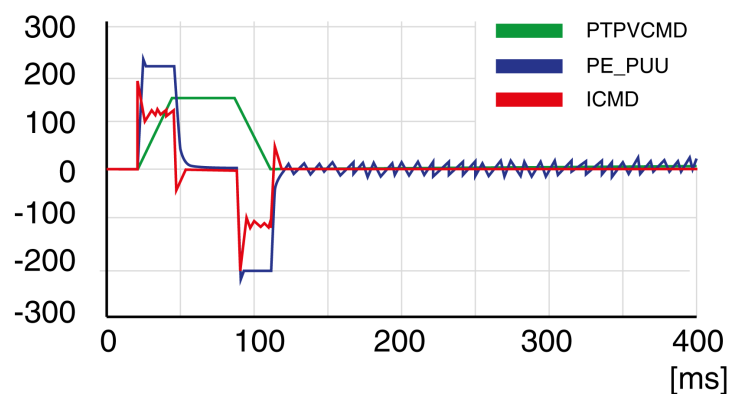
Example P8-03 (LTNP) value too high - oscillation at standstill (75 Hz)



Example P8-03 (LTNP) value too high - oscillation at standstill, overshoot of position deviation (100 Hz)



Example P8-03 (LTNP) OK (65 Hz)



Step 5: Setting the Derivative-Integral Gain

The objective of tuning the derivative-integral gain is to reduce the position deviation. As a general rule, the value for the derivative-integral gain (P8-02LTNIV) is within the following range:

$$P8-03 (LTNP) / 2 < P8-02 (LTNIV) < 2 \times P8-03 (LTNP)$$

Progressively increasing the value of the derivative-integral gain progressively decreases the position deviation during the acceleration phase, the constant velocity phase, and the deceleration phase.

Criteria for a well-tuned derivative-integral gain include:

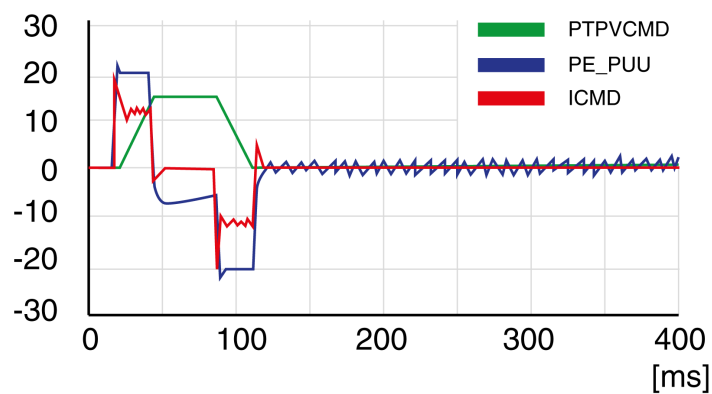
- Position deviation decreases rapidly after each transition of the movement phases (jerk)
- No or minimum overshoot of position deviation
- No or minimum oscillations during transitions between the movement phases
- Oscillations at standstill as low as possible (+/- 1 encoder increment)

The derivative-integral gain is set via parameter P8-02 (LTNIV).

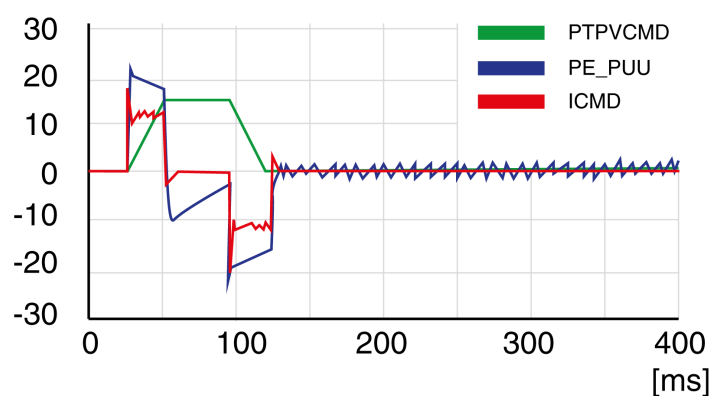
Procedure:

- Progressively increase the value of parameter P8-02 (LTNIV) to find the optimum value. The figures below show examples of the plot as the value approaches the optimum value.

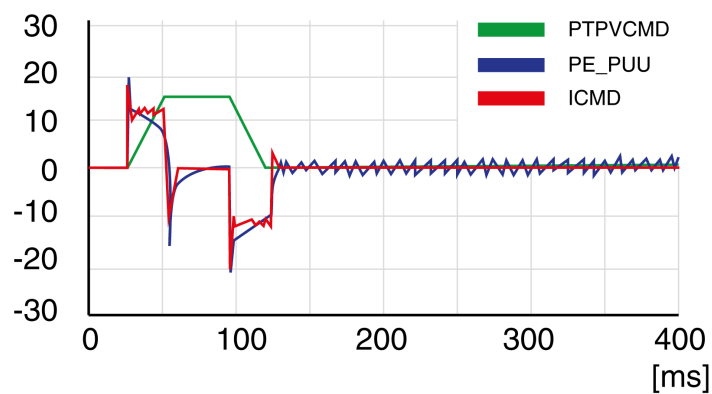
Example P8-02 (LTNIV) starting value (30 Hz)



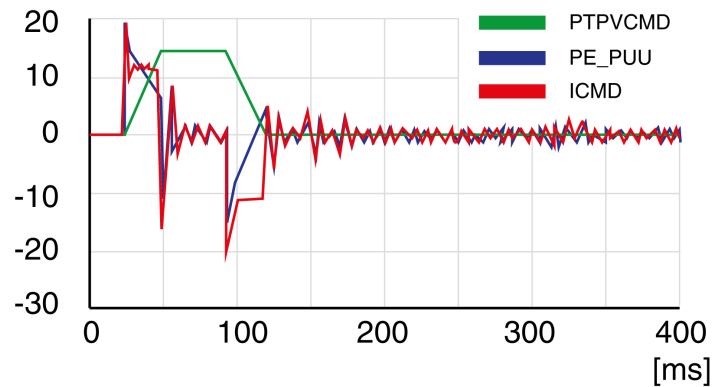
Example P8-02 (LTNIV) position deviation decreased (60 Hz)



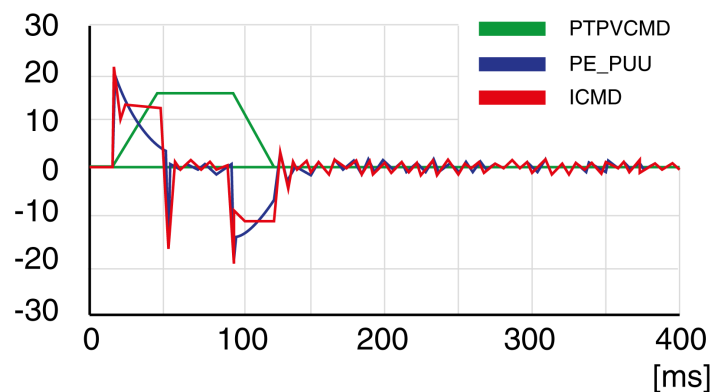
Example P8-02 (LTNIV) position deviation decreases rapidly when target velocity is reached (90 Hz)



Example P8-02 (LTNIV) value too high - oscillation at standstill, overshoot of position deviation (120 Hz)



Example P8-02 (LTNIV) OK (90 Hz)



Step 6: Setting the Integral Gain

The objective of tuning the integral gain is to reduce the position deviation during movements and at standstill.

Criteria for a well-tuned integral gain include:

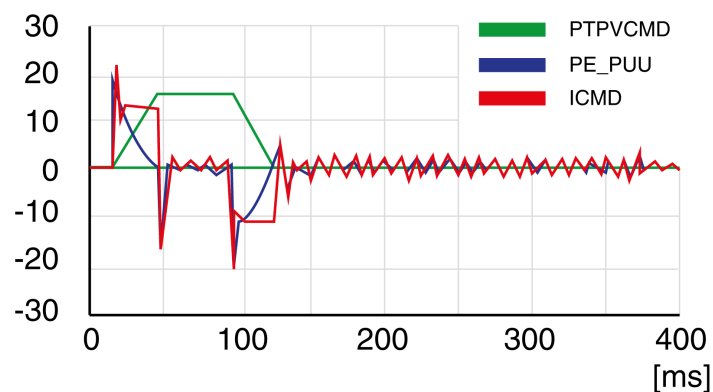
- Position deviation further reduced
- No or minimum overshoot of position deviation at the end of the deceleration phase
- Oscillations at standstill as low as possible (+/- 1 encoder increment)

The integral gain is set via parameter P8-01 (LTNI).

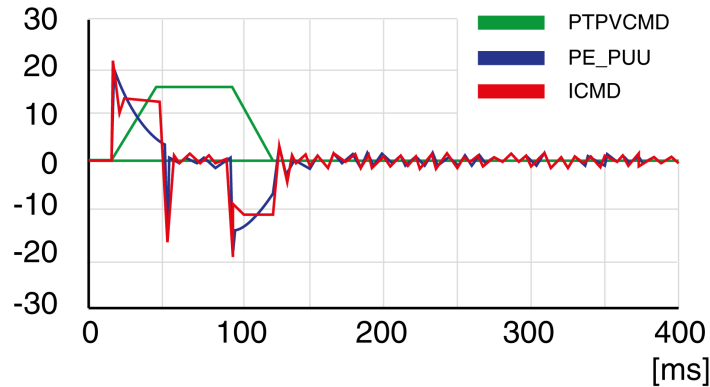
Procedure:

- Progressively increase the value of parameter P8-01 (LTNI) until the oscilloscope shows overshoot or oscillations. The figures below show examples of the plot as the value approaches the optimum value.

Example P8-01 (LTNI) value too high - oscillation at standstill, overshoot of position deviation (50 Hz)



Example P8-01 (LTNI) OK (25 Hz)



Step 7: Compensation of the Flexibility of the Mechanical System

The parameters for compensation of the system flexibility reduce the vibrations caused by abrupt changes in the acceleration (jerk). The parameters can also be used to further minimize overshoot or settling time.

The value of parameter P8-20 (NLPEAFF) reflects the oscillation frequency of the mechanical system, i.e. the coupling between the motor and the load. The coupling can be very rigid (for example, a direct drive or a low-backlash coupling) and less rigid (for example, a belt drive or an elastic coupling). Systems with a high rigidity require a high value. Systems with high load inertia and less rigid couplings require lower values. The less rigid the coupling, the lower this frequency. Depending on the application, the typical value range is 400 ... 30 Hz.

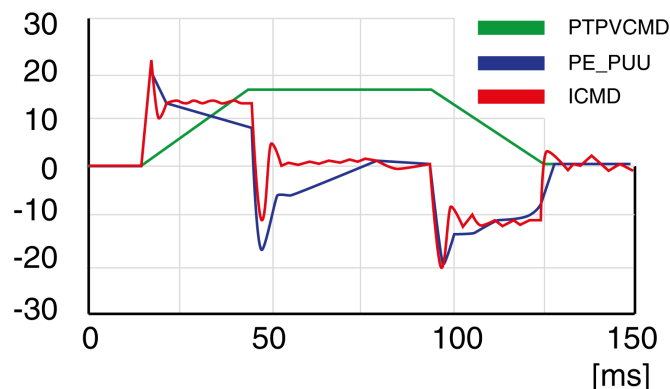
The parameter P8-05 (NLAFFLPFHZ) sets a low-pass filter for the acceleration profile. If the target value has a relatively low resolution as, for example, in the case of a pulse train input, the calculated acceleration may be subject to noise. The low-pass filter set via this parameter can be used to smooth the acceleration profile. The parameter can be used if the flexibility compensation set via parameter P8-20 (NLPEAFF) results in noise.

The compensation of the flexibility of the mechanical system is set via parameters P8-05 (NLAFFLPFHZ) and P8-20 (NLPEAFF).

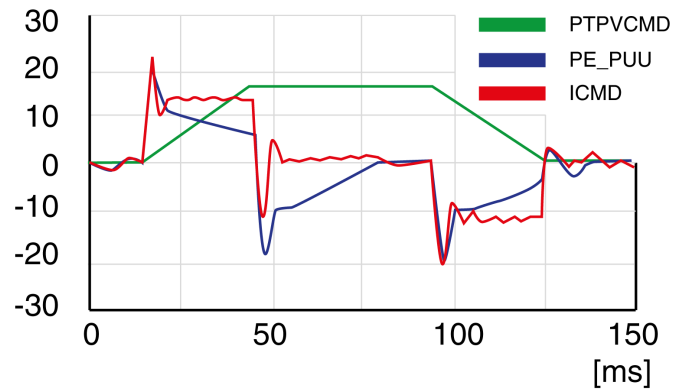
Procedure:

- Set the value of parameter P8-05 (NLAFFLPFHZ) to a value three times as high as that of parameter P8-20 (NLPEAFF). With this value, the bandwidth of this low-pass filter is sufficiently higher than the response time of the system.
- Progressively decrease the value of parameter P8-20 (NLPEAFF) to find the optimum value. The optimum value depends on your optimization criterion: either short settling time or low position deviation. Start with a high frequency of 400 Hz. Decrease the value and compare the amplitudes for the position deviation and the settling time. Select the most suitable value according to your optimization criterion. The figures below show examples of the plot as the value approaches the optimum value.

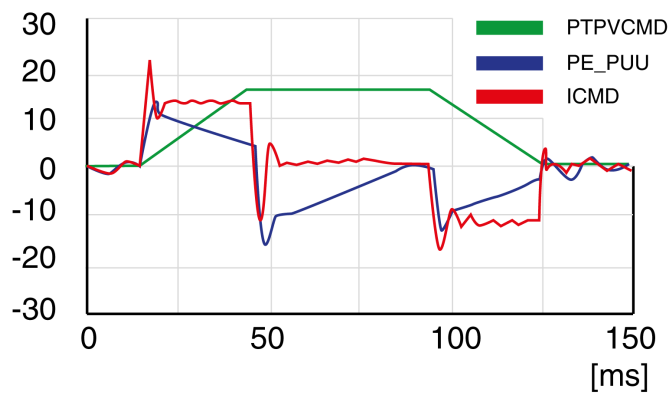
Example P8-20 (NLPEAFF) without compensation of the flexibility (5000 Hz)



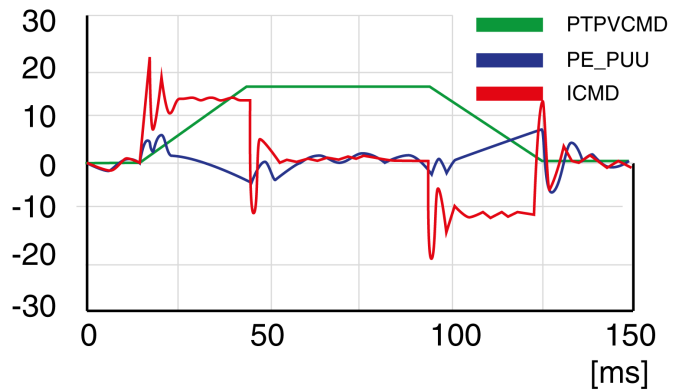
Example P8-20 (NLPEAFF) maximum position deviation decreased (300 Hz)



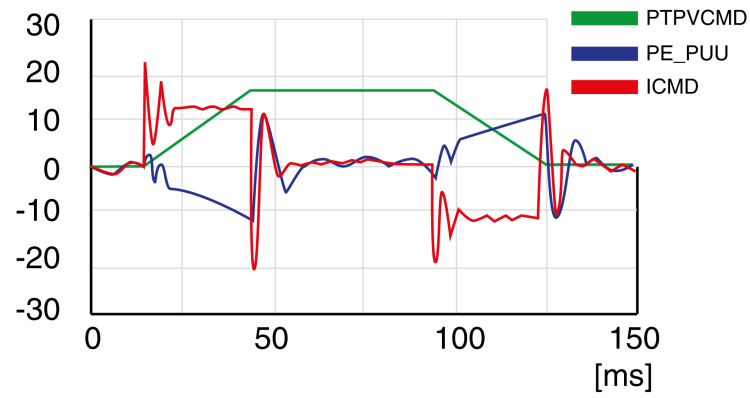
Example P8-20 (NLPEAFF) maximum position deviation further decreased (220 Hz)



Example P8-20 (NLPEAFF) minimum position deviation, short settling time, oscillation at standstill (120 Hz)



Example P8-20 (NLPEAFF) negative position deviation during acceleration phase (100 Hz)



Part VI

Parameters

Chapter 16

Parameters

What Is in This Chapter?

This chapter contains the following topics:

Topic	Page
Representation of the Parameters	206
P0 - Status Parameters	207
P1 - Basic Parameters	212
P2 - Extended Parameters	224
P3 - Communication Parameters	231
P4 - Diagnostics Parameters	232
P5 - Motion Settings	236
P6 - Position Sequence Data Sets Group 1	241
P7 - Position Sequence Data Sets Group 2	248
P8 - Control Loops	254
P9 - DTM Data	260

Representation of the Parameters

This chapter provides an overview of the parameters which can be used for operating the product.

Unsuitable settings or unsuitable data may trigger unintended movements, trigger signals, damage parts and disable monitoring functions. Some parameters and other operational data do not become active until after a restart.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Only start the system if there are no persons or obstructions in the zone of operation.
- Do not operate the drive system with undetermined parameter values.
- Never modify a parameter value unless you fully understand the parameter and all effects of the modification.
- Restart the drive and verify the saved operational data and/or parameter values after modification.
- Carefully run tests for all operating states and potential error situations when commissioning, upgrading or otherwise modifying the operation of the drive.
- Verify the functions after replacing the product and also after making modifications to the parameter values and/or other operational data.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

NOTE: Possible values of a parameter that are not described are considered as reserved and must not be used.

Parameter Name

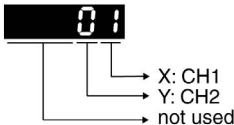
The parameter name uniquely identifies a parameter.

Unit

The unit of the value.

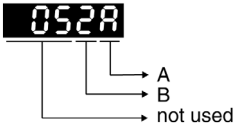
P0 - Status Parameters

P0 - Status Parameters

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P0-00 VER	Firmware Version Applicable operating mode: PT, PS, V, T	- 0 _h 0 _h FFFF _h Hexadecimal	u16 RO -	Modbus 100 _h
P0-01 ALE	Error code of detected error Applicable operating mode: PT, PS, V, T This parameter contains the error number of the most recently detected error. For a list of the detected error codes, refer to Error Codes (see page 344).	- 0 _h 0 _h FFFF _h Hexadecimal	u16 RW -	Modbus 102 _h
P0-02 STS	Drive Status Displayed by HMI Applicable operating mode: PT, PS, V, T This parameter selects the type of status information to be displayed on the HMI. Example: If the setting is 7, the HMI displays the speed of rotation of the motor. For further information, refer to chapter Status Information via the HMI (see page 172).	- 0 0 123 Decimal	u16 RW per.	Modbus 104 _h
P0-03 MON	Function of Analog Outputs Applicable operating mode: PT, PS, V, T This parameter specifies the functions of the analog outputs.  XY: (X: MON1; Y: MON2) 0: Actual velocity (+/-8 V correspond to maximum velocity) 1: Actual torque (+/-8 V correspond to maximum torque) 2: Reference value in kilopulses per second (+8 V correspond to 4.5 Mpps) 3: Target velocity (+/-8 V correspond to maximum target velocity) 4: Target torque (+/-8 V correspond to maximum target torque) 5: DC bus voltage (+/-8 V correspond to 450 V) 6: Reserved 7: Reserved See P1-04 and P1-05 for setting a voltage percentage (scaling). Example: P0-03 = 01: Voltage value at analog output indicates the actual velocity. Velocity = (maximum velocity x V1 / 8) x P1-04 / 100 if the output voltage value of MON2 is V1.	- 0 _h 0 _h 77 _h Hexadecimal	u16 RW per.	Modbus 106 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P0-08 TSON	Operating Hour Meter in Seconds Applicable operating mode: PT, PS, V, T	s 0 - 4294967295 Decimal	u32 RO -	Modbus 110 _h
P0-09 CM1	Status Value 1 Applicable operating mode: PT, PS, V, T This parameter is used to provide the value of one of the status indications in P0-02. The value of this parameter is determined via P0-17. Examples: If the status of the drive is read via the HMI and if P0-02 is set to 23, VAR-1 is displayed for approximately two seconds by the HMI, followed by the value of this parameter. If the setting of P0-17 is 3, reading this parameter displays the actual position in pulses. For reading the status via Modbus, read two 16-bit data stored in the addresses of 0012H and 0013H to generate 32-bit data. (0013H : 0012H) = (high byte : low byte)	- -2147483647 - 2147483647 Decimal	s32 RO -	Modbus 112 _h
P0-10 CM2	Status Value 2 Applicable operating mode: PT, PS, V, T This parameter is used to provide the value of one of the status indications in P0-02. The value of this parameter is determined via P0-18. See P0-09 for details.	- -2147483647 - 2147483647 Decimal	s32 RO -	Modbus 114 _h
P0-11 CM3	Status Value 3 Applicable operating mode: PT, PS, V, T This parameter is used to provide the value of one of the status indications in P0-02. The value of this parameter is determined via P0-19. See P0-09 for details.	- -2147483647 - 2147483647 Decimal	s32 RO -	Modbus 116 _h
P0-12 CM4	Status Value 4 Applicable operating mode: PT, PS, V, T This parameter is used to provide the value of one of the status indications in P0-02. The value of this parameter is determined via P0-20. See P0-09 for details.	- -2147483647 - 2147483647 Decimal	s32 RO -	Modbus 118 _h
P0-13 CM5	Status Value 5 Applicable operating mode: PT, PS, V, T This parameter is used to provide the value of one of the status indications in P0-02. The value of this parameter is determined via P0-21. See P0-09 for details.	- -2147483647 - 2147483647 Decimal	s32 RO -	Modbus 11 A _h
P0-17 CMA1	Indicate status value 1 Applicable operating mode: PT, PS, V, T This parameter is used to select a drive status provided in P0-02. The selected status is indicated via P0-09. Example: If the setting of P0-17 is 7, reading P0-09 returns the speed of rotation of the motor in rpm.	- 0 0 123 Decimal	u16 RW per.	Modbus 122 _h

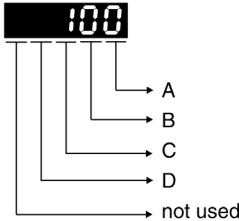
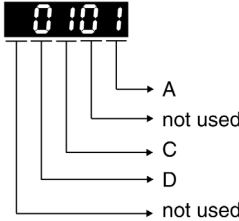
Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P0-18 CMA2	Indicate status value 2 Applicable operating mode: PT, PS, V, T This parameter is used to select a drive status provided in P0-02. The selected status is indicated via P0-10. See P0-17 for details.	- 0 0 123 Decimal	u16 RW per.	Modbus 124 _h
P0-19 CMA3	Indicate status value 3 Applicable operating mode: PT, PS, V, T This parameter is used to select a drive status provided in P0-02. The selected status is indicated via P0-11. See P0-17 for details.	- 0 0 123 Decimal	u16 RW per.	Modbus 126 _h
P0-20 CMA4	Indicate status value 4 Applicable operating mode: PT, PS, V, T This parameter is used to select a drive status provided in P0-02. The selected status is indicated via P0-12. See P0-17 for details.	- 0 0 123 Decimal	u16 RW per.	Modbus 128 _h
P0-21 CMA5	Indicate status value 5 Applicable operating mode: PT, PS, V, T This parameter is used to select a drive status provided in P0-02. The selected status is indicated via P0-13. See P0-17 for details.	- 0 0 123 Decimal	u16 RW per.	Modbus 12 A _h
P0-25 MAP1	Parameter Mapping 1 Applicable operating mode: PT, PS, V, T The parameters from P0-25 ... P0-32 are used to read and write the values of parameters with non-consecutive communication addresses. You can set P0-35 ... P0-42 as the required read and write mapping parameter numbers. When P0-25 ... P0-32 are read, the read or write values are equivalent to the values of the parameters specified via P0-35 ... P0-42, and vice versa. See P0-35 for details.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW -	Modbus 132 _h
P0-26 MAP2	Parameter Mapping 2 Applicable operating mode: PT, PS, V, T See P0-25 and P0-36 for details.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW -	Modbus 134 _h
P0-27 MAP3	Parameter Mapping 3 Applicable operating mode: PT, PS, V, T See P0-25 and P0-37 for details.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW -	Modbus 136 _h
P0-28 MAP4	Parameter Mapping 4 Applicable operating mode: PT, PS, V, T See P0-25 and P0-38 for details.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW -	Modbus 138 _h
P0-29 MAP5	Parameter Mapping 5 Applicable operating mode: PT, PS, V, T See P0-25 and P0-39 for details.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW -	Modbus 13 A _h

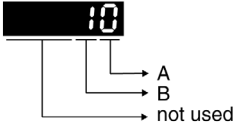
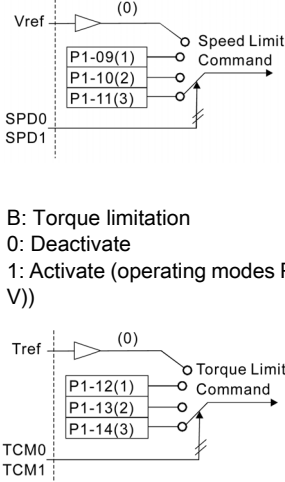
Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P0-30 MAP6	Parameter Mapping 6 Applicable operating mode: PT, PS, V, T See P0-25 and P0-40 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW -	Modbus 13C _h
P0-31 MAP7	Parameter Mapping 7 Applicable operating mode: PT, PS, V, T See P0-25 and P0-41 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW -	Modbus 13E _h
P0-32 MAP8	Parameter Mapping 8 Applicable operating mode: PT, PS, V, T See P0-25 and P0-42 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW -	Modbus 140 _h
P0-35 MAPA1	Block Data Read/Write P0-35...P0-42 1 Applicable operating mode: PT, PS, V, T The parameters P0-35 ... P0-42 specify the required read and write parameter numbers for P0-25 ... P0-32. They read and write the values of the parameters whose communication addresses are not consecutive. The read/write parameter can be a single 32-bit parameter or two 16-bit parameters.  A: Parameter group code in hexadecimal format B: Parameter number in hexadecimal format Example: If you want to read and write the value of P1-44 (32-bit parameter) via P0-25, set P0-35 to 012C012C _h . If you want to read and write the values of P2-02 (16-bit parameter) and P2-04 (16-bit parameter) via P0-25, set P0-35 to 02040202 _h .	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 146 _h
P0-36 MAPA2	Block Data Read/Write P0-35...P0-42 2 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 148 _h
P0-37 MAPA3	Block Data Read/Write P0-35...P0-42 3 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 14 A _h
P0-38 MAPA4	Block Data Read/Write P0-35...P0-42 4 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 14C _h

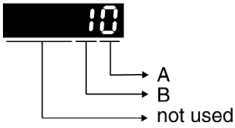
Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P0-39 MAPA5	Block Data Read/Write P0-35...P0-42 5 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 14E _h
P0-40 MAPA6	Block Data Read/Write P0-35...P0-42 6 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 150 _h
P0-41 MAPA7	Block Data Read/Write P0-35...P0-42 7 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 152 _h
P0-42 MAPA8	Block Data Read/Write P0-35...P0-42 8 Applicable operating mode: PT, PS, V, T See P0-35 for details.	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RW per.	Modbus 154 _h
P0-46 SVSTS	State of Signal Output Functions Applicable operating mode: PT, PS, V, T This parameter is used to indicate the state of the signal output function of the drive in hexadecimal format. If the function is assigned to a digital output, it would represent the state of the output given no forcing on the output. Bit 0: SRDY (Servo ready) Bit 1: SON (Servo On) Bit 2: ZSPD (Zero speed) Bit 3: TSPD (Speed reached) Bit 4: TPOS (Movement completed) Bit 5: TQL (Torque Limit Reached) Bit 6: ERR (Error Detected) Bit 7: BRKR (Holding brake control) Bit 8: HOMED_OK (Homing completed) Bit 9: OLW (Motor Overload Alert) Bit 10: WARN (indicates that one of the following conditions has been detected: Hardware limit switch triggered, undervoltage, Nodeguard alert, Operational Stop (OPST)) Bits 11 ... 15: Reserved The parameter can also be read via the fieldbus.	- 0 _h 0 _h FFF _h Hexadecimal	u16 RO -	Modbus 15C _h
P0-47 LAST_WRN	Number of Last Alert Applicable operating mode: PT, PS, V, T This parameter contains the number of the last detected alert. After a Fault Reset, the number is cleared.	- 0 _h 0 _h FFF _h Hexadecimal	u16 RO -	Modbus 15E _h

P1 - Basic Parameters

P1 - Basic Parameters

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-00 PTT	Reference Value Signal - Pulse Settings Applicable operating mode: PT  This parameter is used to configure the reference value signals for the operating mode PT. A: Type of reference value signals B: Signal frequency C: Input polarity D: Source of reference value signals Setting can only be changed if power stage is disabled.	- 0 _h 2 _h 1132 _h Hexadecimal	u16 RW per.	Modbus 200 _h
P1-01 CTL	Operating Mode and Direction of Rotation Applicable operating mode: PT, PS, V, T  A: Operating mode Refer to chapter Setting the Operating Mode (see page 286). C: Direction of movement Refer to chapter Verifying the Direction of Movement (see page 179). D: Signal input functions and signal output functions after operating mode switching Value 0: The assignments of the signal input functions and the signal output functions (P2-10 ... P2-22) remain identical for the new operating mode. Value 1: The assignments of the signal input functions and the signal output functions (P2-10 ... P2-22) are set to the default presets of the new operating mode. Refer to chapters Default Presets of the Signal Inputs (see page 270) and Default Presets of the Signal Outputs (see page 276). Changed settings become active the next time the product is powered on.	- 0 _h 0 _h 110 A _h Hexadecimal	u16 RW per.	Modbus 202 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-02 PSTL	Velocity and Torque Limitations Activation/Deactivation Applicable operating mode: PT, PS, V, T This parameter activates/deactivates velocity limitation and torque limitation. It can also be activated via the signal input functions SPDLM and TRQLM. The signal input functions SPD0 and SPD1 are used to select velocity values set via P1-09 to P1-11. The signal input functions TCM0 and TCM1 are used to select torque values set via P1-12 to P1-14.  A: Velocity limitation 0: Deactivate 1: Activate (in operating mode T)  B: Torque limitation 0: Deactivate 1: Activate (operating modes PT, PS, , and V))	- 0 _h 0 _h 11 _h Hexadecimal	u16 RW per.	Modbus 204 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-03 AOUT	Polarity of Analog Outputs / Polarity of Pulse Outputs Applicable operating mode: PT, PS, V, T  This parameter is used to specify the polarity of analog outputs MON1 and MON2 and the polarity of pulse outputs. A: Polarity of analog outputs MON1 and MON2 0: MON1(+), MON2(+) 1: MON1(+), MON2(-) 2: MON1(-), MON2(+) 3: MON1(-), MON2(-) B: Polarity of pulse outputs 0: Not inverted 1: Inverted	- 0 _h 0 _h 13 _h Hexadecimal	u16 RW per.	Modbus 206 _h
P1-04 MON1	Scaling Factor Analog Output 1 Applicable operating mode: PT, PS, V, T	% 1 100 100 Decimal	u16 RW per.	Modbus 208 _h
P1-05 MON2	Scaling Factor Analog Output 2 Applicable operating mode: PT, PS, V, T	% 1 100 100 Decimal	u16 RW per.	Modbus 210 A _h
P1-09 SP1	Target Velocity/Velocity Limitation 1 Applicable operating mode: V, T Target velocity 1 In the operating mode V, this parameter specifies the first target velocity. Velocity limitation 1 In the operating mode T, this parameter specifies the first velocity limitation.	0.1rpm -60000 10000 60000 Decimal	s32 RW per.	Modbus 212 _h
P1-10 SP2	Target Velocity/Velocity Limitation 2 Applicable operating mode: V, T Target velocity 2 In the operating mode V, this parameter specifies the second target velocity. Velocity limitation 2 In the operating mode T, this parameter specifies the second velocity limitation.	0.1rpm -60000 20000 60000 Decimal	s32 RW per.	Modbus 214 _h
P1-11 SP3	Target Velocity/Velocity Limitation 3 Applicable operating mode: V, T Target velocity 3 In the operating mode V, this parameter specifies the third target velocity. Velocity limitation 3 In the operating mode T, this parameter specifies the third velocity limitation.	0.1rpm -60000 30000 60000 Decimal	s32 RW per.	Modbus 216 _h

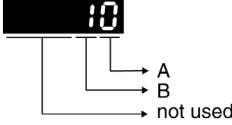
Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-12 TQ1	Target Torque/Torque Limitation 1 Applicable operating mode: PT, PS, V, T Target torque 1 in percent of nominal current In the operating mode T, this parameter specifies the first target torque. Torque limitation 1 in percent of nominal current In the operating modes PT, PS and V, this parameter specifies the first torque limitation. The signal output function TQL is activated if the torque reaches the torque limitations set via the parameters P1-12 ... P1-14 or via an analog input.	% -300 100 300 Decimal	s16 RW per.	Modbus 218 _h
P1-13 TQ2	Target Torque/Torque Limitation 2 Applicable operating mode: PT, PS, V, T Target torque 2 in percent of nominal current In the operating mode T, this parameter specifies the second target torque. Torque limitation 2 in percent of nominal current In the operating modes PT, PS and V, this parameter specifies the second torque limitation. The signal output function TQL is activated if the torque reaches the torque limitations set via the parameters P1-12 ... P1-14 or via an analog input.	% -300 100 300 Decimal	s16 RW per.	Modbus 21 A _h
P1-14 TQ3	Target Torque/Torque Limitation 3 Applicable operating mode: PT, PS, V, T Target torque 3 in percent of nominal current In the operating mode T, this parameter specifies the third target torque. Torque limitation 3 in percent of nominal current In the operating modes PT, PS and V, this parameter specifies the third torque limitation. The signal output function TQL is activated if the torque reaches the torque limitations set via the parameters P1-12 ... P1-14 or via an analog input.	% -300 100 300 Decimal	s16 RW per.	Modbus 21C _h
P1-15 LINELOSSMODE	Mains Phase Monitoring - Response to Missing Mains Phase Applicable operating mode: PT, PS, V, T This parameter specifies the response of the drive if the mains phase monitoring function detects an error. Value 0: Detected error if power stage is enabled or disabled Value 1: Detected error if power stage is enabled, alert if power stage is disabled Value 2: Alert if power stage is enabled or disabled	- 0 0 2 Decimal	u16 RW per.	Modbus 21E _h
P1-16 LINELOSSRE-COVER	Mains Phase Monitoring - Fault Reset Applicable operating mode: PT, PS, V, T This parameter specifies the type of Fault Reset after a detected mains phase error has been removed. Value 0: No automatic Fault Reset Value 1: Automatic Fault Reset	- 0 0 1 Decimal	u16 RW per.	Modbus 220 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-17 LINELOSSTYPE	Mains Phase Monitoring - Type Applicable operating mode: PT, PS, V, T This parameter specifies the type of mains phase monitoring Value 0: No mains phase monitoring Value 1: Mains phase monitoring single-phase connection Value 2: Mains phase monitoring three-phase connection	- 0 0 2 Decimal	u16 RW per.	Modbus 222 _h
P1-18	Reserved	—	—	—
P1-19 DISTIME	Active Disable - Delay Time Power Stage Applicable operating mode: PT, PS, V, T This parameter specifies the delay time between standstill of the motor and disabling the power stage.	ms 0 0 6500 Decimal	u16 RW per.	Modbus 226 _h
P1-20 ESTOPI LIM	Current Limit During Quick Stop Applicable operating mode: PT, PS, V This parameter specifies the maximum current during a Quick Stop (expressed as factor of P1-78).	0.001 1 1000 1000 Decimal	s16 RW per.	Modbus 228 _h
P1-21 FOLD	Status of Foldback Current Drive Applicable operating mode: PT, PS, V, T This parameter indicates whether the foldback current limit is greater than or less than the maximum current of the drive (see P1-78). Value 0: Foldback current limit greater than P1-78 Value 1: Foldback current limit is less than P1-78	- 0 - 1 Decimal	u16 RO -	Modbus 22 A _h
P1-22 IFOLD	Foldback Current Limit - Drive Applicable operating mode: PT, PS, V, T Drive foldback current limit	0.01 A 0 - 30000 Decimal	u32 RO -	Modbus 22C _h
P1-23 IFOLD FTHRESH	Current Monitoring Drive - Detected Error Threshold Foldback Current Applicable operating mode: PT, PS, V, T This parameter specifies the threshold value used by the drive current monitoring function to detect a drive foldback current error.	0.01 A 0 - 30000 Decimal	u32 RW per.	Modbus 22E _h
P1-24 IFOLD WTHRESH	Current Monitoring Drive - Alert Threshold Foldback Current Applicable operating mode: PT, PS, V, T This parameter specifies the threshold value used by the drive current monitoring function to trigger a drive foldback current alert.	0.01 A 0 - 30000 Decimal	u32 RW per.	Modbus 230 _h
P1-25	Reserved	—	—	—
P1-26 MIFOLD	Foldback Current Limit - Motor Applicable operating mode: PT, PS, V, T Motor foldback current limit	0.01 A 0 - 30000 Decimal	u32 RO -	Modbus 234 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-27 MIFOLD- THRESH	Motor Current Monitoring - Detected Error Threshold Foldback Current Applicable operating mode: PT, PS, V, T This parameter specifies the threshold value used by the motor current monitoring function to detect a motor foldback current error.	0.01 A 0 - 30000 Decimal	u32 RW per.	Modbus 236 _h
P1-28 MIFOLDW- THRESH	Motor Current Monitoring - Alert Threshold Foldback Current Applicable operating mode: PT, PS, V, T This parameter specifies the threshold value used by the motor current monitoring function to trigger a motor foldback current alert.	0.01 A 0 - 30000 Decimal	u32 RW per.	Modbus 238 _h
P1-29 OVTHRESH	DC Bus Overvoltage Monitoring - Threshold Applicable operating mode: PT, PS, V, T This parameter specifies the threshold value used by the DC bus overvoltage monitoring function.	V - - - Decimal	u16 RO -	Modbus 23 A _h
P1-30 COMMERR- MAXCNT	Commutation Monitoring - Maximum Counter Value Applicable operating mode: PT, PS, V, T	ms 0 0 0 Decimal	u16 RW -	Modbus 23C _h
P1-32 LSTP	Stop Method Applicable operating mode: PT, PS, V This parameter specifies how the motor is stopped if the power stage is to be disabled (includes signal input function OPST) or if an error is detected. Value 0 _h : Deceleration ramp Value 10 _h : Coast to stop Value 20 _h : Deceleration ramp to velocity P1-38, then coast to stop (actual velocity must be less than the value of P1-38 for 50 ms before coasting to stop starts) In the operating mode Torque (T), the deceleration ramp is not used. Instead, the current is set to zero. Depending on the event that triggered the stop, the following deceleration ramps are used: - Signal input function STOP: P5-20 - Transmission error detected: P5-21 - Position overflow: P5-22 - Triggering of negative software limit switch: P5-23 - Triggering of positive software limit switch: P5-24 - Triggering of negative hardware limit switch: P5-25 - Triggering of positive hardware limit switch: P5-26 - Any other event: P1-68 The delay time between standstill of the motor and disabling the power stage is set via P1-19.	- 0 _h 0 _h 20 _h Hexadecimal	u16 RW per.	Modbus 240 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-34 TACC	Acceleration Period Applicable operating mode: PT, V The acceleration period is the time in milliseconds required to accelerate from motor standstill to 6000 rpm. For operating mode V, this parameter specifies the acceleration. For operating mode PT, this parameter specifies an acceleration limitation for the pulses at the PTI interface.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 244 _h
P1-35 TDEC	Deceleration Period Applicable operating mode: PT, V The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. For operating mode V, this parameter specifies the deceleration. For operating mode PT, this parameter specifies a deceleration limitation for the pulses at the PTI interface.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 246 _h
P1-37 LMJR	Ratio of Load Inertia to Motor Inertia Applicable operating mode: PT, PS, V, T This parameter specifies the ratio of load inertia to motor inertia (J_{load} / J_{motor}). J_{load} : Total moment of inertia of external mechanical load J_{motor} : Moment of inertia of motor	0.1 0 10 20000 Decimal	u32 RW per.	Modbus 24 A _h
P1-38 ZSPD	Signal Output Function ZSPD / Signal Input Function ZCLAMP - Velocity Applicable operating mode: PT, PS, V, T This parameter specifies the velocity for the signal output function ZSPD. The signal output function ZSPD indicates that the velocity of the motor is less than the velocity value set via this parameter. This parameter specifies the velocity for the signal input function ZCLAMP. The signal input function ZCLAMP stops the motor. The velocity of the motor must be below the velocity value set via this parameter.	0.1rpm 0 100 2000 Decimal	s32 RW per.	Modbus 24C _h
P1-39 SSPD	Signal Output Function TSPD - Velocity Applicable operating mode: PT, PS, V, T This parameter specifies the velocity for the signal output function TSPD. The signal output function TSPD indicates that the velocity of the motor is greater than the velocity value set via this parameter.	rpm 0 3000 5000 Decimal	u32 RW per.	Modbus 24E _h
P1-40 VCM	Velocity Target Value and Velocity Limitation 10 V Applicable operating mode: PT, PS, V, T In the operating mode V, this parameter specifies the target velocity that corresponds to the maximum input voltage of 10 V. In the operating mode T, this parameter specifies the velocity limitation that corresponds to the maximum input voltage of 10 V. Example: If the value of this parameter is 3000 in the operating mode V and if the input voltage is 10 V, the target velocity is 3000 rpm.	rpm 0 - 10001 Decimal	s32 RW per.	Modbus 250 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-41 TCM	Torque Target Value and Torque Limitation 10 V Applicable operating mode: PT, PS, V, T In the operating mode T, this parameter specifies the target torque that corresponds to the maximum input voltage of 10 V. In the operating modes PT, PS and V, this parameter specifies the torque limitation that corresponds to the maximum input voltage of 10 V. Example: If the value of this parameter is 100 in the operating mode T and if the input voltage is 10 V, the target torque is 100 % of the nominal torque. Setting can only be changed if power stage is disabled.	% 0 100 1000 Decimal	u16 RW per.	Modbus 252 _h
P1-42 MBT1	Delay Time of Holding Brake Applicable operating mode: PT, PS, V, T This parameter specifies the time between enabling the power stage and starting a movement (opening time for the holding brake).	ms 0 0 1000 Decimal	u16 RW per.	Modbus 254 _h
P1-44 GR1	Electronic Gear Ratio - Numerator 1 Applicable operating mode: PT, PS This parameter is used to set the numerator of the gear ratio. The denominator of the gear ratio is set via P1-45. In the operating mode PS, the value of this parameter can only be changed when the power stage is disabled.	- 1 128 536870911 Decimal	u32 RW per.	Modbus 258 _h
P1-45 GR2	Electronic Gear Ratio - Denominator Applicable operating mode: PT, PS This parameter is used to set the denominator of the gear ratio. The numerator of the gear ratio is set via P1-44. Setting can only be changed if power stage is disabled.	- 1 10 2147483647 Decimal	u32 RW per.	Modbus 25 A _h
P1-46 ENCOUTRES	Encoder Simulation Resolution Applicable operating mode: PT, PS, V, T This parameter specifies the number of increments (AB signal) per revolution. The calculation of the range of this parameter depends on the value of P1-55. Setting can only be changed if power stage is disabled.	LPR - 2048 - Decimal	s32 RW per.	Modbus 25C _h
P1-47 SPOK	Signal Output Function SP_OK - Velocity Applicable operating mode: V This parameter specifies the velocity deviation window for the signal output function SP_OK. The signal output function SP_OK indicates that actual velocity is within the velocity deviation window.	rpm 0 10 300 Decimal	u32 RW per.	Modbus 25E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-48 MCOK	Signal Output Function MC_OK - Settings Applicable operating mode: PS This parameter specifies the behavior of the signal output function MC_OK after it has been activated. The signal output function MC_OK indicates that both the signal output functions CMD_OK and TPOS have been activated. In addition, you can specify whether a detected position deviation is to trigger a detected error.  A: Behavior of MC_OK after deactivation of TPOS Value 0: When TPOS is deactivated, MC_OK is deactivated. Value 1: When TPOS is deactivated, MC_OK remains activated. B: Response to detected position deviation via TPOS if A is set to 0 Value 0: No response Value 1: Detected alert Value 2: Detected error	- 0 _h 0 _h 21 _h Hexadecimal	u16 RW per.	Modbus 260 _h
P1-52 REGENRES	Braking Resistor - Resistance Applicable operating mode: PT, PS, V, T This parameter is used to set the resistance of the braking resistor. Value -1: No braking resistor	Ohm -1 - 32767 Decimal	s16 RW per.	Modbus 268 _h
P1-53 REGENPOW	Braking Resistor - Power Applicable operating mode: PT, PS, V, T This parameter is used to set the power of the braking resistor. Value -1: No braking resistor	W -1 - 32767 Decimal	s16 RW per.	Modbus 26 A _h
P1-54 PER	Signal Output Function TPOS - Trigger Value Applicable operating mode: PT, PS This parameter specifies the position deviation value used to activate the signal output function TPOS. Operating mode PT: The signal output function TPOS indicates that the position deviation is within the tolerance set via this parameter. Operating mode PS: The signal output function TPOS indicates that the position deviation at the target position is within the tolerance set via this parameter.	PUU 0 12800 1280000 Decimal	u32 RW per.	Modbus 26C _h
P1-55 VLIM	Maximum Velocity - User-Defined Applicable operating mode: PT, PS, V, T This parameter specifies the maximum velocity. Factory setting: maximum motor speed. Setting can only be changed if power stage is disabled.	rpm 10 - 6000 Decimal	u32 RW per.	Modbus 26E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-57 CRSHA	Torque Monitoring - Torque Value Applicable operating mode: PT, PS, V, T This parameter is used to configure the torque monitoring function. The torque monitoring function detects an error (AL030) if the torque value set via this parameter is exceeded for a period of time set via P1-58.	% 0 0 300 Decimal	u16 RW per.	Modbus 272 _h
P1-58 CRSHT	Torque Monitoring - Time Value Applicable operating mode: PT, PS, V, T This parameter is used to configure the torque monitoring function. The torque monitoring function detects an error (AL030) if the torque value set via P1-57 is exceeded for a period of time set via this parameter.	ms 1 1 1000 Decimal	u16 RW per.	Modbus 274 _h
P1-59 VELCMD- MOVEAVG	S Curve Filter for Operating Mode Velocity Applicable operating mode: V This parameter specifies the moving average time in [us] for the S curve filter in the operating mode Velocity. The value of this parameter must be a multiple of 125. This filter changes a linear acceleration into an S curve. Setting can only be changed if power stage is disabled.	us 0 0 255875 Decimal	u32 RW per.	Modbus 276 _h
P1-60 COMMERRT- THRESH	Commutation Monitoring - Time Threshold Applicable operating mode: PT, PS, V, T	ms 0 0 3000 Decimal	u16 RW per.	Modbus 278 _h
P1-61 COMMERRV- THRESH	Commutation Monitoring - Velocity Threshold Applicable operating mode: PT, PS, V, T	0.1rpm 0 600 60000 Decimal	u32 RW per.	Modbus 27 A _h
P1-62 THERMODE	Motor Overtemperature Monitoring - Response Applicable operating mode: PT, PS, V, T This parameter specifies the response of the drive if the temperature monitoring function detects motor overtemperature. Value 0: Disable power stage immediately Value 3: Ignore overtemperature Value 4: Alert Value 5: Alert first, then detected error if condition persists after P1-63	- 0 0 5 Decimal	u16 RW per.	Modbus 27C _h
P1-63 THERMTIME	Motor Overtemperature Monitoring - Delay Time Applicable operating mode: PT, PS, V, T This parameter specifies the delay time between the detection of motor overtemperature and the transition to the operating state Fault (see P1-62).	s 0 30 300 Decimal	u16 RW per.	Modbus 27E _h

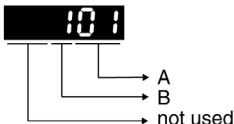
Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-64 UVMODE	Undervoltage Monitoring - Response Applicable operating mode: PT, PS, V, T This parameter specifies the response of the drive if the undervoltage monitoring function detects undervoltage. Value 0: Detected error Value 1: Alert (if power stage is enabled) Value 2: Alert first, then detected error if condition persists after P1-67 (if power stage is enabled) Value 3: Detected error (if power stage is enabled)	- 0 0 3 Decimal	u16 RW per.	Modbus 280 _h
P1-65	Reserved	—	—	—
P1-66 MFOLD	Status of Foldback Current Motor Applicable operating mode: PT, PS, V, T This parameter indicates whether the foldback current limit is greater than or less than the maximum current of the motor (see P1-78). Value 0: Foldback current limit greater than P1-78 Value 1: Foldback current limit is less than P1-78	- 0 - 1 Decimal	u16 RO -	Modbus 284 _h
P1-67 UVTIME	Undervoltage Monitoring - Delay Time Applicable operating mode: PT, PS, V, T This parameter specifies the delay time between the detection of an undervoltage condition (displayed as "u") and the response of the drive to this condition as specified in P1-64.	s 0 30 300 Decimal	u16 RW per.	Modbus 286 _h
P1-68 DECSTOP	Active Disable - Deceleration Ramp Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a power stage Disable request, see P1-32.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 288 _h
P1-69 DECSTOPTIME	Disable - Deceleration Time Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a power stage Disable request, see P1-32. If the value of this parameter is not 0, this parameter overrides P1-68. Setting can only be changed if power stage is disabled.	ms 0 0 6500 Decimal	u16 RW per.	Modbus 28 A _h
P1-70 IMAXHALT	Signal Input Function HALT - Maximum Current Applicable operating mode: T This parameter specifies the maximum current for the signal input function Halt. The maximum value for this parameter is the value of P1-79.	0.01 A - 0 - Decimal	u32 RW per.	Modbus 28C _h
P1-71 REGENMAXON-TIME	Braking Resistor - Maximum Time in Braking Applicable operating mode: PT, PS, V, T This parameter specifies the maximum time in braking for the braking resistor. The maximum time in braking is the maximum period of time during which the braking resistor may be activated.	ms 10 40 100 Decimal	u16 RW per.	Modbus 28E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-72 REGENFLTMODE	Braking Resistor Overload Monitoring - Response Applicable operating mode: PT, PS, V, T This parameter specifies the response of the drive if the braking resistor overload monitoring function detects braking resistor overload. Value 0: Alert Value 1: Detected error	- 0 0 1 Decimal	u16 RW per.	Modbus 290 _h
P1-78 ILIM	User-Defined Maximum Current Applicable operating mode: PT, PS, V, T This parameter is specifies a user-defined maximum current for the drive. The maximum value of this parameter is the value of P1-79.	0.01 A - - - Decimal	u32 RW per.	Modbus 29C _h
P1-79 IMAX	Maximum Current Applicable operating mode: PT, PS, V, T This parameter indicates the maximum current for a drive / motor combination.	0.01 A - - - Decimal	u32 RO -	Modbus 29E _h
P1-80 DIPEAK	Maximum Peak Current Applicable operating mode: PT, PS, V, T This parameter indicates the maximum peak current of the drive.	0.01 A - - - Decimal	u32 RO -	Modbus 2A0 _h
P1-81 DICONT	Nominal Current Applicable operating mode: PT, PS, V, T This parameter indicates the nominal current of the drive.	0.01 A - - - Decimal	u32 RO -	Modbus 2A2 _h
P1-84 CFG_MOTOR	Configured motor type Applicable operating mode: PT, PS, V, T	- 0 - 2147483647 Decimal	u32 RW per.	Modbus 2A8 _h

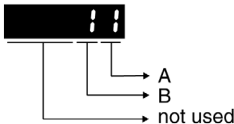
P2 - Extended Parameters

P2 - Extended Parameters

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-01 PPR	Gain Switching - Rate for Position Loop Applicable operating mode: PT, PS This parameter specifies the gain switching rate for the position loop. The gain switching function is configured via this parameter and parameters P2-05, P2-27 and P2-29.	% 10 100 500 Decimal	u16 RW per.	Modbus 302 _h
P2-05 SPR	Gain Switching - Rate for Velocity Loop Applicable operating mode: PT, PS, V, T This parameter specifies the gain switching rate for the velocity loop. The gain switching function is configured via this parameter and parameters P2-01, P2-27 and P2-29.	% 10 100 500 Decimal	u16 RW per.	Modbus 30 A _h
P2-08 PCTL	Factory Reset / Save Parameters Applicable operating mode: PT, PS, V, T This parameter provides the following functions: - Reset the parameters to the factory settings - Save the current parameter values Changes to this parameter are only possible when the power stage is disabled. The factory settings do not become effective until after you have powered the drive off and on again. Value 10: Reset the parameter values to the factory settings Value 11: Save the parameter values	- 0 0 406 Decimal	u16 RW -	Modbus 310 _h
P2-09 DRT	Debounce Time - Inputs Applicable operating mode: PT, PS, V, T This parameter specifies the debounce time for the digital inputs DI1 ... DI5 and DI8. See P2-24 for the debounce time for the fast digital inputs DI6 and DI7.	ms 0 2 20 Decimal	u16 RW per.	Modbus 312 _h
P2-10 DITF1	Signal Input Function for DI1 Applicable operating mode: PT, PS, V, T The parameters P2-10 ... P2-17 are used to assign signal input functions to the digital inputs DI1 ... DI8 and to configure the type of digital input (normally closed, normally open). A: Signal input functions: For the values, refer to chapter Setting the Digital Signal Inputs (see page 270). B: Type: 0: Normally closed (contact b) 1: Normally open (contact a) Example: If the setting of P2-10 is 101, the signal input function assigned to digital input 1 is SON (0x01) and the type of contact is a normally open contact. The drive must be restarted after the parameters have been changed. Forcing of digital inputs is configured via P3-06 and activated via P4-07. Setting can only be changed if power stage is disabled.	- 0 _h 101 _h 146 _h Hexadecimal	u16 RW per.	Modbus 314 _h

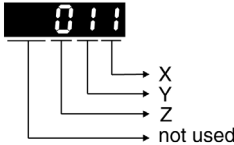
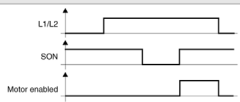
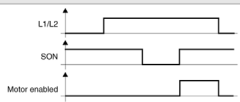
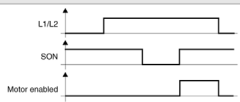
Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-11 DITF2	Signal Input Function for DI2 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 104 _h 146 _h Hexadecimal	u16 RW per.	Modbus 316 _h
P2-12 DITF3	Signal Input Function for DI3 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 116 _h 146 _h Hexadecimal	u16 RW per.	Modbus 318 _h
P2-13 DITF4	Signal Input Function for DI4 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 117 _h 146 _h Hexadecimal	u16 RW per.	Modbus 31 A _h
P2-14 DITF5	Signal Input Function for DI5 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 102 _h 146 _h Hexadecimal	u16 RW per.	Modbus 31C _h
P2-15 DITF6	Signal Input Function for DI6 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 22 _h 146 _h Hexadecimal	u16 RW per.	Modbus 31E _h
P2-16 DITF7	Signal Input Function for DI7 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 23 _h 146 _h Hexadecimal	u16 RW per.	Modbus 320 _h
P2-17 DITF8	Signal Input Function for DI8 Applicable operating mode: PT, PS, V, T See P2-10 for details. Setting can only be changed if power stage is disabled.	- 0 _h 21 _h 146 _h Hexadecimal	u16 RW per.	Modbus 322 _h
P2-18 DOTF1	Signal Output Function for DO1 Applicable operating mode: PT, PS, V, T The parameters P2-18 ... P2-22 are used to assign signal output functions to the digital outputs DO1 ... DO5 and to configure the type of digital output (normally closed, normally open).  A: Signal output functions: For the values, refer to chapter Setting the Digital Signal Outputs (see page 276). B: Type: 0: Normally closed (contact b) 1: Normally open (contact a) Example: If the setting of P2-18 is 101, the signal output function assigned to digital output 1 is SRDY (0x01) and the type of contact is a normally open contact.	- 0 _h 101 _h 137 _h Hexadecimal	u16 RW per.	Modbus 324 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-19 DOTF2	Signal Output Function for DO2 Applicable operating mode: PT, PS, V, T See P2-18 for details.	- 0 _h 103 _h 137 _h Hexadecimal	u16 RW per.	Modbus 326 _h
P2-20 DOTF3	Signal Output Function for DO3 Applicable operating mode: PT, PS, V, T See P2-18 for details.	- 0 _h 109 _h 137 _h Hexadecimal	u16 RW per.	Modbus 328 _h
P2-21 DOTF4	Signal Output Function for DO4 Applicable operating mode: PT, PS, V, T See P2-18 for details.	- 0 _h 105 _h 137 _h Hexadecimal	u16 RW per.	Modbus 32 A _h
P2-22 DOTF5	Signal Output Function for DO5 Applicable operating mode: PT, PS, V, T See P2-18 for details.	- 0 _h 7 _h 137 _h Hexadecimal	u16 RW per.	Modbus 32C _h
P2-23 DOTF6	Signal Output Function for DO6(OCZ) Applicable operating mode: PT, PS, V, T Only the signal output function ESIM can be assigned to the digital output DO6(OCZ). Use P2-18 ... P2-22 for assigning other signal output functions to the other digital outputs DO1 ... DO5. See P2-18 for details.	- 0 _h 40 _h 137 _h Hexadecimal	u16 RW per.	Modbus 32E _h
P2-24 FDRT	Debounce Time - Fast Inputs Applicable operating mode: PT, PS, V, T This parameter specifies the debounce time for the digital inputs DI6 and DI7. See P2-09 for the debounce time for the digital inputs DI1 ... DI5 and DI8.	us 0 50 100 Decimal	u16 RW per.	Modbus 330 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-27 GCC	Gain Switching - Conditions and Type Applicable operating mode: PT, PS, V, T This parameter specifies the conditions for and the type of gain switching. The gain switching function is configured via this parameter and parameters P2-01, P2-05 and P2-29.  A: Conditions for gain switching: 0: Disabled 1: Signal input function GAINUP is active 2: In operating modes PT and PS, the position deviation is greater than the value of P2-29 3: Pulse frequency is greater than the value of P2-29 4: Velocity is greater than the value of P2-29 5: Signal input function GAINUP is not active 6: In operating modes PT and PS, the position deviation is less than the value of P2-29 7: Pulse frequency is less than the value of P2-29 8: Velocity is less than the value of P2-29	- 0 _h 0 _h 18 _h Hexadecimal	u16 RW per.	Modbus 336 _h
P2-29 GPE	Gain Switching - Comparison Value Applicable operating mode: PT, PS, V, T This parameter specifies the comparison value used for the conditions for gain switching. Depending on the selected condition, the value entered represents the number of pulses (position deviation), the pulse frequency or the velocity. The gain switching function is configured via this parameter and parameters P2-01, P2-05 and P2-27.	- 0 _h 138800 _h 3A9800 _h Hexadecimal	u32 RW per.	Modbus 33 A _h
P2-30 INH	Auxiliary Functions Applicable operating mode: PT, PS, V, T Value 0: Disabled Value 1: Enable the power stage	- -8 0 8 Decimal	s16 RW -	Modbus 33C _h
P2-31 LTNEFFORT	Autotuning Optimization Value Threshold Applicable operating mode: PT, PS, V This parameter is used to change the gain.	0.001 100 1000 10000 Decimal	u32 RW -	Modbus 33E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-32 ATMODE	Autotuning Applicable operating mode: PT, PS, V This parameter is used to start autotuning with the selected autotuning method. Value 0: Stop Autotuning Value 1: Easy Tuning Value 2: Comfort Tuning [minimum settling time, vibration suppression] Value 3: Comfort Tuning [minimum overshoot, vibration suppression] Value 52: Comfort Tuning [minimum settling time, no vibration suppression] Value 53: Comfort Tuning [minimum overshoot, no vibration suppression]	- 0 0 56 Decimal	u16 RW -	Modbus 340 _h
P2-34 VEMAX	Velocity Monitoring - Threshold Value Applicable operating mode: V This parameter specifies the velocity threshold for the velocity monitoring function. If this value is exceeded, error AL555 is detected.	0.1rpm 0 50000 60000 Decimal	u32 RW per.	Modbus 344 _h
P2-35 PDEV	Position Deviation Monitoring - Threshold Value Applicable operating mode: PT, PS This parameter specifies the position deviation threshold for the position deviation monitoring function. If this value is exceeded, error AL009 is detected.	PUU 1 100000 128000000 Decimal	u32 RW per.	Modbus 346 _h
P2-36 PT_PULSE_FLTR	PTI Interface Debounce Time - Pulse Applicable operating mode: PT, PS, V, T This parameter specifies the debounce time of the pulse input of the PTI interface.	16.6666*ns 0 30 511 Decimal	u16 RO -	Modbus 348 _h
P2-37 PT_DIRECT_FLTR	PTI Interface Debounce Time - Direction Applicable operating mode: PT, PS, V, T This parameter specifies the debounce time of the direction input of the PTI interface.	16.6666*ns 0 30 511 Decimal	u16 RO -	Modbus 34 A _h
P2-44 AUTOR_DOMS	Status of Data Set Sequences in Operating Mode PS Applicable operating mode: PS This parameter provides information on the status of the sequence of data sets processed with the signal input functions. Value 0: The functions assigned to the digital outputs DO1 ... DO6 via the parameters P2-18 ... P2-23 are active. Value 1: The digital outputs provide information on the status of the sequence of data sets. When this parameter is reset to 0, the previous assignments and configurations of the digital outputs as set via the parameters P2-18 ... P2-23 are restored. See Status of Data Set Sequences for details.	- 0 _h 0 _h 1 _h Hexadecimal	u16 RW per.	Modbus 358 _h
P2-50 DCLR	Signal Input Function CLRPOS - Trigger Applicable operating mode: PT, PS This parameter specifies how the signal input function CLRPOSDEV is triggered. The signal input function CLRPOSDEV resets the position deviation to zero. Value 0: Rising edge Value 1: Level	- 0 _h 0 _h 1 _h Hexadecimal	u16 RW per.	Modbus 364 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P2-60 GR2	Electronic Gear Ratio - Numerator 2 Applicable operating mode: PT, PS This parameter can be used to set an additional gear ratio. The additional gear ratio can be selected via the signal input functions GNUM0 and GNUM1. See P1-44 for details.	- 1 128 536870911 Decimal	u32 RW per.	Modbus 378 _h
P2-61 GR3	Electronic Gear Ratio - Numerator 3 Applicable operating mode: PT, PS See P2-60 for details.	- 1 128 536870911 Decimal	u32 RW per.	Modbus 37 A _h
P2-62 GR4	Electronic Gear Ratio - Numerator 4 Applicable operating mode: PT, PS See P2-60 for details.	- 1 128 536870911 Decimal	u32 RW per.	Modbus 37C _h
P2-65 GBIT	Special Function 1 Applicable operating mode: PT, PS, V Bits 0 ... 5: Reserved (must be set to 0). Bit 6: Reference pulse monitoring 0: Function activated 1: Function deactivated Bits 7 ... 8: Reserved (must be set to 0). Bit 9: Motor phase monitoring 0: Function deactivated 1: Function activated Bit 9: Motor phase monitoring 0: Function deactivated 1: Function activated Bit 10: Acceleration and deceleration for ZCLAMP: 0: Immediate stop. Motor is locked at the position where it was when ZCLAMP became active. 1: Motor is decelerated with deceleration ramp setting. Motor is locked at the position where standstill is reached. Bit 11: NL(CWL)/PL(CCWL) pulse input inhibit function 0: Function activated 1: Function deactivated If P8-31 is set to 1 or 3 and if a hardware limit switch is triggered, a Fault Reset clears the missing master pulses. Only use the pulse inhibit function with settings 1 or 3 of P8-31 if you do not need a Fault Reset after a detected hardware limit switch error. To achieve this, set the Automatic Fault Reset function of P2-68 to 1.	- 0 _h 200 _h 3FC0 _h Hexadecimal	u16 RW per.	Modbus 382 _h
P2-65(continued)	Bit 12: Mains phase monitoring 0: Function activated (AL022) 1: Function deactivated Bit 13: Encoder simulation output monitoring 0: Function activated (AL018) 1: Function deactivated Bits 14 ... 15: Reserved (must be set to 0).			

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus						
P2-66 GBIT2	Special Function 2 Applicable operating mode: PT, PS, V, T Bits 0 ... 1: Reserved (must be set to 0). Bit 2: This bit specifies the type of Fault Reset after a detected undervoltage error has been removed. 0: No automatic Fault Reset 1: Automatic Fault Reset Bits 3 ... 7: Reserved (must be set to 0).	- 0 0 4 Decimal	u16 RW per.	Modbus 384 _h						
P2-68 AEAL	Auto-Enable and Automatic Hardware Limit Switch Fault Reset Applicable operating mode: PT, PS, V, T  X: Automatic power stage enabling 0: Trigger SON to enable power stage 1: Enable power stage automatically if SON is active after drive has been powered on <table><tr><th>X</th><th>FUNCTION</th></tr><tr><td>0</td><td></td></tr><tr><td>1</td><td></td></tr></table> Y: Automatic Fault Reset for limit switches 0: Detected hardware limit switch error (AL014 and AL015) requires Fault Reset 1: Detected hardware limit switch error (AL014 and AL015) can be reset without Fault Reset Z: Reserved 0: No detected error 1: Detected error, Fault Reset required Changed settings become active the next time the product is powered on.	X	FUNCTION	0		1		- 0 _h 0 _h 111 _h Hexadecimal	u16 RW per.	Modbus 388 _h
X	FUNCTION									
0										
1										

P3 - Communication Parameters

P3 - Communication Parameters

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P3-00 ADR	Device Address Modbus Applicable operating mode: PT, PS, V, T The device address must be unique. Changed settings become active the next time the product is powered on.	- 1 127 247 Decimal	u16 RW per.	Modbus 400 _h
P3-01 BRT	Transmission Rate Applicable operating mode: PT, PS, V, T This parameter is used to set the data transmission rate. For further information, refer to chapter Setting the Device Address, Baud Rate and Connection Settings (<i>see page 177</i>). Changed settings become active the next time the product is powered on.	- 0 _h 102 _h 405 _h Hexadecimal	u16 RW per.	Modbus 402 _h
P3-02 PTL	Modbus Connection Settings Applicable operating mode: PT, PS, V, T This parameter specifies the Modbus connection settings. For further information, refer to chapter Setting the Device Address, Baud Rate and Connection Settings (<i>see page 177</i>). Changed settings become active the next time the product is powered on.	- 6 _h 7 _h 9 _h Hexadecimal	u16 RW per.	Modbus 404 _h
P3-03 FLT	Detected Modbus Communication Errors - Handling Applicable operating mode: PT, PS, V, T This parameter specifies the response of the drive to a detected communication error. Value 0: Detected alert Value 1: Detected error	- 0 _h 0 _h 1 _h Hexadecimal	u16 RW per.	Modbus 406 _h
P3-04 CWD	Modbus Connection Monitoring Applicable operating mode: PT, PS, V, T This parameter specifies the maximum permissible duration for communication timeout. When this time has elapsed, the communication timeout is treated as a detected error. Setting this parameter to 0 to disables connection monitoring.	ms 0 0 20000 Decimal	u16 RW per.	Modbus 408 _h
P3-06 SDI	Digital Inputs - Forcing Settings Applicable operating mode: PT, PS, V, T This parameter determines whether or not a digital input can be forced. Bits 0 ... 7: Digital input DI1 ... digital input DI8 Bit settings: Value 0: Digital input cannot be forced Value 1: Digital input can be forced To actually start forcing, you must write P4-07. See P2-10 ... P2-17 for the assignment of signal input functions to the digital inputs.	- 0 _h 0 _h 7FF _h Hexadecimal	u16 RW -	Modbus 40C _h
P3-07 CDT	Modbus Response Delay Time Applicable operating mode: PT, PS, V, T This parameter specifies the time delay with which the drive responds to the Modbus master.	0.5ms 0 0 1000 Decimal	u16 RW per.	Modbus 40E _h

P4 - Diagnostics Parameters

P4 - Diagnostics Parameters

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-00 ASH1	Error History - Error Code of Most Recent Detected Error n Applicable operating mode: PT, PS, V, T This parameter indicates the error code of the most recent detected error. Writing 0 to this parameter clears the error history.	- 0 _h 0 _h 0 _h Hexadecimal	u16 RW -	Modbus 500 _h
P4-01 ASH2	Error History - Error Code of Most Recent Detected Error n - 1 Applicable operating mode: PT, PS, V, T This parameter indicates the error code of the detected error n-1, n being the most recent detected error.	- 0 _h 0 _h 0 _h Hexadecimal	u16 RO -	Modbus 502 _h
P4-02 ASH3	Error History - Error Code of Most Recent Detected Error n - 2 Applicable operating mode: PT, PS, V, T This parameter indicates the error code of the detected error n-2, n being the most recent detected error.	- 0 _h 0 _h 0 _h Hexadecimal	u16 RO -	Modbus 504 _h
P4-03 ASH4	Error History - Error Code of Most Recent Detected Error n - 3 Applicable operating mode: PT, PS, V, T This parameter indicates the error code of the detected error n-3, n being the most recent detected error.	- 0 _h 0 _h 0 _h Hexadecimal	u16 RO -	Modbus 506 _h
P4-04 ASH5	Error History - Error Code of Most Recent Detected Error n - 4 Applicable operating mode: PT, PS, V, T This parameter indicates the error code of the detected error n-4, n being the most recent detected error.	- 0 _h 0 _h 0 _h Hexadecimal	u16 RO -	Modbus 508 _h
P4-05 JOG	Jog Velocity Applicable operating mode: PT, PS, V, T For further information, refer to chapter Jog Operation (<i>see page 288</i>).	rpm 0 20 5000 Decimal	u32 RW per.	Modbus 50 A _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-06 FOT	Setting a signal output via parameter Applicable operating mode: PT, PS, V, T This parameter lets you set those signal outputs whose signal output functions have been set to SDO_0 ... SDO_5. Bit 0 = 1 sets those signal outputs whose signal output function has been set to SDO_0. Bit 1 = 1 sets those signal outputs whose signal output function has been set to SDO_1. Bit 2 = 1 sets those signal outputs whose signal output function has been set to SDO_2. Bit 3 = 1 sets those signal outputs whose signal output function has been set to SDO_3. Bit 4 = 1 sets those signal outputs whose signal output function has been set to SDO_4. Bit 5 = 1 sets those signal outputs whose signal output function has been set to SDO_5. Bit 6 = 1 sets those signal outputs whose signal output function has been set to SDO_6. Bit 7 = 1 sets those signal outputs whose signal output function has been set to SDO_7. See P2-18 ... P2-22 for assigning the functions to the digital outputs.	- 0 _h 0 _h FF _h Hexadecimal	u16 RW -	Modbus 50C _h
P4-07 ITST	State of Digital Inputs / Activate Forcing Applicable operating mode: PT, PS, V, T A read access to this parameter indicates the state of the digital inputs in the form of a bit pattern. Example: Read value 0x0011: Digital inputs 1 and 5 are logical 1 By writing this parameter, you can change the state of the inputs provided that the setting for the corresponding input in P3-06 allows for forcing (value 1 for the bit corresponding to the input). Example: Write value 0x0011: Digital inputs 1 and 5 are set to logical 1, regardless of the previous state See P3-06 for permitting forcing of individual digital inputs. See P2-10 ... P2-17 for the assignment of signal input functions to the digital inputs.	- 0 _h 0 _h FF _h Hexadecimal	u16 RW -	Modbus 50E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-08 PKEY	Status of HMI Keypad Applicable operating mode: PT, PS, V, T This parameter is used to verify proper operation of the keys on the HMI keypad of the drive As a bitwise: "1" - key is pressed, "0" - key is released. When: S key is indicated by bit0 M key is indicated by bit1 UP key is indicated by bit2 DOWN key is indicated by bit3 ENT key is indicated by bit4	- 0 _h 0 _h FF _h Hexadecimal	u16 RO -	Modbus 510 _h
P4-09 MOT	State of Digital Outputs Applicable operating mode: PT, PS, V, T This parameter indicates the state of the digital outputs DO1...DO6. Bit 0 = 1: DO1 is activated Bit 1 = 1: DO2 is activated Bit 2 = 1: DO3 is activated Bit 3 = 1: DO4 is activated Bit 4 = 1: DO5 is activated Bit 5 = 1: DO6 is activated	- 0 _h 0 _h 3F _h Hexadecimal	u16 RO -	Modbus 512 _h
P4-10 FLTHISTCLR	Clear Error History Applicable operating mode: PT, PS, V, T Writing 0 to this parameter clears the error history.	- 0 0 0 Decimal	u16 RW -	Modbus 514 _h
P4-22 ANIN1OFFSET	Analog Input 1 Offset Applicable operating mode: V This parameter specifies an offset for the analog input used in operating mode V.	mV -10000 0 10000 Decimal	s16 RW per.	Modbus 52C _h
P4-23 ANIN2OFFSET	Analog Input 2 Offset Applicable operating mode: T This parameter specifies an offset for the analog input used in operating mode T.	mV -10000 0 10000 Decimal	s16 RW per.	Modbus 52E _h
P4-24 LVL	Undervoltage Monitoring - Threshold Value Applicable operating mode: PT, PS, V, T This parameter specifies the threshold value for DC bus undervoltage monitoring. If the DC Bus voltage is less than the value of P4-24 x 2, the error AL003 is detected.	V 140 160 190 Decimal	u16 RW per.	Modbus 530 _h
P4-26 DO_FORCEABLE	Digital Outputs - Forcing Information Applicable operating mode: PT, PS, V, T This parameter shows whether or not a digital output can be forced. Bits 0 ... 4: Digital output DO1 ... digital output DO5 Bit settings: Value 0: Digital output cannot be forced Value 1: Digital output can be forced	- 1F _h 1F _h 1F _h Hexadecimal	u16 RO -	Modbus 534 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-27 DO_- FORCE_MASK	Digital Outputs - Forcing Settings Applicable operating mode: PT, PS, V, T This parameter determines whether or not a digital output can be forced. Bits 0 ... 4: Digital output DO1 ... digital output DO5 Bit settings: Value 0: Digital output cannot be forced Value 1: Digital output can be forced To actually start forcing, you must write P4-28. See P2-18 ... P2-22 for the assignment of signal output functions to the digital outputs.	- 0 _h 0 _h 1F _h Hexadecimal	u16 RW -	Modbus 536 _h
P4-28 DO_FORCE_VAL- UE	State of Digital Outputs / Activate Forcing Applicable operating mode: PT, PS, V, T A read access to this parameter indicates the state of the digital outputs in the form of a bit pattern. Example: Read value 0x0011: Digital outputs 1 and 5 are logical 1 By writing this parameter, you can change the state of the outputs provided that the setting for the corresponding output in P4-27 allows for forcing (value 1 for the bit corresponding to the output). Example: Write value 0x0011: Digital outputs 1 and 5 are set to logical 1, regardless of the previous state See P4-27 for permitting forcing of individual digital outputs. See P2-18 ... P2-22 for the assignment of signal output functions to the digital outputs.	- 0 _h 0 _h 1F _h Hexadecimal	u16 RW -	Modbus 538 _h

P5 - Motion Settings

P5- Motion Settings

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P5-00 REV	Firmware Revision Applicable operating mode: PT, PS, V, T This parameter contains the revision number of the firmware.	- 0 _h 0 _h FFFF _h Hexadecimal	u16 RO -	Modbus 600 _h
P5-04 HMOV	Homing - Homing Method Selection Applicable operating mode: PS This parameter is used to select the homing method and configure the behavior of the index pulse and the limit switches. For further information, refer to chapter Operating Mode Position Sequence (PS) (<i>see page 296</i>). Setting can only be changed if power stage is disabled.	- 0 _h 0 _h 128 _h Hexadecimal	u16 RW per.	Modbus 608 _h
P5-05 HOMESPEED1	Homing - Fast Velocity for Reference Movement Applicable operating mode: PS	0.1rpm 10 1000 60000 Decimal	u32 RW per.	Modbus 60 A _h
P5-06 HOMESPEED2	Homing - Slow Velocity for Reference Movement Applicable operating mode: PS	0.1rpm 10 200 60000 Decimal	u32 RW per.	Modbus 60 C _h
P5-07 PRCM	Operating Mode PS via Parameter Applicable operating mode: PS The operating mode Position Sequence (PS) provides 32 data sets that can be executed via the signal input functions POS0 ... POS4 and CTRG or via of this parameter. 0: Start operating mode Homing (Homing data set) 1 ... 32: Trigger data set (equivalent to the signal input functions CTRG and POSn). 33 ... 9999: Not permitted 1000: Stop movement (equivalent to the signal input function STOP) Values displayed via this parameter: If a data set is active, but not yet completed, the value displayed is the value of this parameter plus 10000. If a data set has been completed, the value displayed is the value of this parameter plus 20000. Example: Displayed value 10003: Data set 3 has been started, but is not yet completed. Displayed value 20003: Data set 3 has been completed. Refer to chapter Operating Mode Position Sequence (PS) (<i>see page 296</i>).	- 0 0 20032 Decimal	u16 RW -	Modbus 60 E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P5-08 POSLIMPOS	Positive Software Limit Switch - Position Applicable operating mode: PS Prerequisite: Software limit switches only work with a valid zero point. Setting can only be changed if power stage is disabled.	PUU -2147483647 134217727 2147483647 Decimal	s32 RW per.	Modbus 610 _h
P5-09 POSLIMNEG	Negative Software Limit Switch - Position Applicable operating mode: PS Prerequisite: Software limit switches only work with a valid zero point. Setting can only be changed if power stage is disabled.	PUU -2147483647 -134217727 2147483647 Decimal	s32 RW per.	Modbus 612 _h
P5-10 GEARACCTHRESH	Operating mode Pulse Train - Maximum Acceleration Applicable operating mode: PT This parameter is used to reduce the acceleration noise.	ms 6 6 65500 Decimal	u16 RW per.	Modbus 614 _h
P5-11 POSLIMHYST	Software Limit Switches - Hysteresis Value Applicable operating mode: PS This parameter specifies a hysteresis value for the software limit switches. Setting can only be changed if power stage is disabled.	PULSE 0 3556 35555 Decimal	u16 RW per.	Modbus 616 _h
P5-12 PROBE_1_LVL_PRD	Touch Probe Input 1 - Stable Level Duration Applicable operating mode: PT, PS This parameter specifies the period of time for which the level at Touch Probe input 1 must be stable.	31.25 μ s 2 5 32 Decimal	u16 RW per.	Modbus 618 _h
P5-13 POSLIMMODE	Software Limit Switches - Activation Applicable operating mode: PS This parameter activates/deactivates the software limit switches configured via P5-08 and P5-09. Prerequisite: Software limit switches only work with a valid zero point. Value 0: Deactivate software limit switches Value 1: Activate software limit switches Value 2...3: Reserved	- 0 0 1 Decimal	u16 RW per.	Modbus 61 A _h
P5-14 ICMDSLOPE	Motion Profile for Torque - Slope Applicable operating mode: T This parameter specifies the slope of the motion profile for torque.	mA/s 1 100000 30000000 Decimal	u32 RW per.	Modbus 61 C _h
P5-15 ICMDSLOPEEN	Motion Profile for Torque - Activation Applicable operating mode: T This parameter activates the motion profile for torque. Value 0: Deactivate Value 1: Activate Setting can only be changed if power stage is disabled.	- 0 0 1 Decimal	u16 RW per.	Modbus 61 E _h
P5-16 AXEN	Encoder Increments in PUU Applicable operating mode: PT, PS, V, T Setting can only be changed if power stage is disabled. This parameter specifies an offset to the encoder position.	PUU -2147483647 0 2147483647 Decimal	s32 RW -	Modbus 620 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P5-18 AXPC	External Encoder (Pulses) Applicable operating mode: PT, PS, V, T This parameter contains the cumulated pluses counted at the PTI input since the drive has been switched on.	- -2147483648 - 2147483647 Decimal	s32 RO -	Modbus 624 _h
P5-20 STP	Deceleration Ramp - Signal Input Function STOP Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a stop triggered via the signal input function STOP. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 50 65500 Decimal	u16 RW per.	Modbus 628 _h
P5-21 CTO	Deceleration Ramp - Detected Transmission Error Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a stop triggered if a transmission error is detected. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 50 65500 Decimal	u16 RW per.	Modbus 62 A _h
P5-22 OVF	Deceleration Ramp - Position Overflow Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a stop triggered if a position overflow is detected. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 62C _h
P5-23 SNL	Deceleration Ramp - Triggering of Negative Software Limit Switch Applicable operating mode: PS This parameter specifies the deceleration ramp for a stop triggered if the negative software limit switch is activated. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 50 65500 Decimal	u16 RW per.	Modbus 62E _h
P5-24 SPL	Deceleration Ramp - Triggering of Positive Software Limit Switch Applicable operating mode: PS This parameter specifies the deceleration ramp for a stop triggered if the positive software limit switch is activated. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 50 65500 Decimal	u16 RW per.	Modbus 630 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P5-25 NL	Deceleration Ramp - Triggering of Negative Hardware Limit Switch Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a stop triggered if the negative hardware limit switch is activated. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 632 _h
P5-26 PL	Deceleration Ramp - Triggering of Positive Hardware Limit Switch Applicable operating mode: PT, PS, V This parameter specifies the deceleration ramp for a stop triggered if the positive hardware limit switch is activated. The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 634 _h
P5-35 PROBES_POLARITY	Touch Probes Polarity Applicable operating mode: PT, PS, V, T This parameter specifies the touch probes polarity.	- 0 - 3 Decimal	u16 RO per.	Modbus 646 _h
P5-37 CAAX	Touch Probe Input 1 - Captured Position Applicable operating mode: PT, PS, V, T This parameter contains the position captured at Touch Probe input 1.	PUU -2147483647 0 2147483647 Decimal	s32 RO -	Modbus 64 A _h
P5-38 PROBE1_CNTR	Touch Probe Input 1 - Event Counter Applicable operating mode: PT, PS, V, T The value is increased by 1 each time a position has been captured at Touch Probe input 1.	- 0 0 65535 Decimal	u16 RO -	Modbus 64C _h
P5-39 CACT	Touch Probe Input 1 - Configuration Applicable operating mode: PT, PS, V, T X: Activate/deactivate position capture 0: Deactivate 1: Activate (is reset to 0 when the counter in P5-38 is incremented) Y: Reserved U: Reserved Z: Polarity of Touch Probe input 0: Normally open 1: Normally closed Where X is the least significant half-byte and U is the most significant half-byte of the X/Y/U/Z Integer.	- 0 _h 0 _h 101 _h Hexadecimal	u16 RW -	Modbus 64E _h
P5-57 CAAX2	Touch Probe Input 2 - Captured Position Applicable operating mode: PT, PS, V, T This parameter contains the position captured at Touch Probe input 2.	PUU -2147483647 0 2147483647 Decimal	s32 RO -	Modbus 672 _h
P5-58 PROBE2_CNTR	Touch Probe Input 2 - Event Counter Applicable operating mode: PT, PS, V, T The value is increased by 1 each time a position has been captured at Touch Probe input 2.	- 0 0 65535 Decimal	u16 RO -	Modbus 674 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P5-59 CACT2	Touch Probe Input 2 - Configuration Applicable operating mode: PT, PS, V, T X: Activate/deactivate position capture 0: Deactivate 1: Activate (is reset to 0 when the counter in P5-58 is incremented) Y: Reserved Z: Polarity of Touch Probe input 0: Normally open 1: Normally closed U: Reserved	- 0 _h 0 _h 101 _h Hexadecimal	u16 RW -	Modbus 676 _h
P5-76 HOME_OFF- SET_MOVE	Move Home Offset When Homing input is found Applicable operating mode: Fieldbus mode	- 0 0 1 Decimal	u16 RW per.	Modbus 698 _h
P5-77 PROBE_2_LVL_PRD	Touch Probe Input 2 - Stable Level Duration Applicable operating mode: PT, PS This parameter specifies the period of time for which the level at Touch Probe input 2 must be stable.	31.25 μ s 2 5 32 Decimal	u16 RW per.	Modbus 69 A _h

P6 - Position Sequence Data Sets Group 1

P6 - PS Data Sets Group 1

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-00 ODAT	Position of Homing Data Set Applicable operating mode: PS After a successful reference movement, this position is automatically set at the reference point. Bits 0...31: Position	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 700 _h
P6-01 ODEF	Subsequent Data Set and Auto-start of Homing Data Set Applicable operating mode: PS Bit 0: 0 = Do not start Homing after first power stage enable 1 = Start Homing after first power stage enable Bits 1...7: Reserved Bits 8...15: Number of the subsequent data set	- 0 _h 0 _h 2001 _h Hexadecimal	u32 RW per.	Modbus 702 _h
P6-02 PATHPOS1	Target Position of Data Set 1 Applicable operating mode: PS Bits 0...31: Target position	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 704 _h
P6-03 PATHCTRL1	Configuration of Data Set 1 Applicable operating mode: PS Bits 0...3: Reserved Bit 4: 0 = Wait for preceding data set to complete, then start this data set 1 = Start this data set immediately Bits 5...6: Reserved Bit 7: 0 = Absolute position 1 = Relative (incremental) position Bits 8...15: Reserved	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 706 _h
P6-04 PATHPOS2	Target Position of Data Set 2 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 708 _h
P6-05 PATHCTRL2	Configuration of Data Set 2 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 70 A _h
P6-06 PATHPOS3	Target Position of Data Set 3 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 70C _h
P6-07 PATHCTRL3	Configuration of Data Set 3 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 70E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-08 PATHPOS4	Target Position of Data Set 4 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 710 _h
P6-09 PATHCTRL4	Configuration of Data Set 4 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 712 _h
P6-10 PATHPOS5	Target Position of Data Set 5 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 714 _h
P6-11 PATHCTRL5	Configuration of Data Set 5 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 716 _h
P6-12 PATHPOS6	Target Position of Data Set 6 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 718 _h
P6-13 PATHCTRL6	Configuration of Data Set 6 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 71 A _h
P6-14 PATHPOS7	Target Position of Data Set 7 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 71C _h
P6-15 PATHCTRL7	Configuration of Data Set 7 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 71E _h
P6-16 PATHPOS8	Target Position of Data Set 8 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 720 _h
P6-17 PATHCTRL8	Configuration of Data Set 8 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 722 _h
P6-18 PATHPOS9	Target Position of Data Set 9 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 724 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-19 PATHCTRL9	Configuration of Data Set 9 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 726 _h
P6-20 PATHPOS10	Target Position of Data Set 10 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 728 _h
P6-21 PATHCTRL10	Configuration of Data Set 10 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 72 A _h
P6-22 PATHPOS11	Target Position of Data Set 11 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 72C _h
P6-23 PATHCTRL11	Configuration of Data Set 11 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 72E _h
P6-24 PATHPOS12	Target Position of Data Set 12 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 730 _h
P6-25 PATHCTRL12	Configuration of Data Set 12 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 732 _h
P6-26 PATHPOS13	Target Position of Data Set 13 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 734 _h
P6-27 PATHCTRL13	Configuration of Data Set 13 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 736 _h
P6-28 PATHPOS14	Target Position of Data Set 14 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 738 _h
P6-29 PATHCTRL14	Configuration of Data Set 14 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 73 A _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-30 PATHPOS15	Target Position of Data Set 15 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 73C _h
P6-31 PATHCTRL15	Configuration of Data Set 15 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 73E _h
P6-32 PATHPOS16	Target Position of Data Set 16 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 740 _h
P6-33 PATHCTRL16	Configuration of Data Set 16 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 742 _h
P6-34 PATHPOS17	Target Position of Data Set 17 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 744 _h
P6-35 PATHCTRL17	Configuration of Data Set 17 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 746 _h
P6-36 PATHPOS18	Target Position of Data Set 18 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 748 _h
P6-37 PATHCTRL18	Configuration of Data Set 18 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 74A _h
P6-38 PATHPOS19	Target Position of Data Set 19 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 74C _h
P6-39 PATHCTRL19	Configuration of Data Set 19 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 74E _h
P6-40 PATHPOS20	Target Position of Data Set 20 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 750 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-41 PATHCTRL20	Configuration of Data Set 20 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 752 _h
P6-42 PATHPOS21	Target Position of Data Set 21 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 754 _h
P6-43 PATHCTRL21	Configuration of Data Set 21 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 756 _h
P6-44 PATHPOS22	Target Position of Data Set 22 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 758 _h
P6-45 PATHCTRL22	Configuration of Data Set 22 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 75 A _h
P6-46 PATHPOS23	Target Position of Data Set 23 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 75C _h
P6-47 PATHCTRL23	Configuration of Data Set 23 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 75E _h
P6-48 PATHPOS24	Target Position of Data Set 24 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 760 _h
P6-49 PATHCTRL24	Configuration of Data Set 24 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 762 _h
P6-50 PATHPOS25	Target Position of Data Set 25 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 764 _h
P6-51 PATHCTRL25	Configuration of Data Set 25 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 766 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-52 PATHPOS26	Target Position of Data Set 26 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 768 _h
P6-53 PATHCTRL26	Configuration of Data Set 26 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 76 A _h
P6-54 PATHPOS27	Target Position of Data Set 27 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 76C _h
P6-55 PATHCTRL27	Configuration of Data Set 27 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 76E _h
P6-56 PATHPOS28	Target Position of Data Set 28 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 770 _h
P6-57 PATHCTRL28	Configuration of Data Set 28 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 772 _h
P6-58 PATHPOS29	Target Position of Data Set 29 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 774 _h
P6-59 PATHCTRL29	Configuration of Data Set 29 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 776 _h
P6-60 PATHPOS30	Target Position of Data Set 30 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 778 _h
P6-61 PATHCTRL30	Configuration of Data Set 30 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 77 A _h
P6-62 PATHPOS31	Target Position of Data Set 31 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 77C _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-63 PATHCTRL31	Configuration of Data Set 31 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 77E _h
P6-64 PATHPOS32	Target Position of Data Set 32 Applicable operating mode: PS See P6-02 for details.	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 780 _h
P6-65 PATHCTRL32	Configuration of Data Set 32 Applicable operating mode: PS See P6-03 for details.	- 0 _h 0 _h D0 _h Hexadecimal	u16 RW per.	Modbus 782 _h

P7 - Position Sequence Data Sets Group 2

P7 - PS Data Sets Group 2

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-00 HOME_ACC_DEC	Deceleration and Acceleration of Homing Data Set Applicable operating mode: PS Bits 0 ... 15: Deceleration Bits 16 ... 31: Acceleration	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 800 _h
P7-01 HOME_DLY	Waiting Time of Homing Data Set Applicable operating mode: PS Bits 0 ... 15: Waiting time until next dataset is started Bits 16 ... 31: Reserved	ms 0 0 32767 Decimal	u32 RW per.	Modbus 802 _h
P7-02 ACC_DEC1	Deceleration and Acceleration of Data Set 1 Applicable operating mode: PS Bits 0 ... 15: Deceleration Bits 16 ... 31: Acceleration	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 804 _h
P7-03 SPD_DLY1	Waiting Time and Target Velocity of Data Set 1 Applicable operating mode: PS Bits 0 ... 15: Waiting time until next dataset is started (in ms) Bits 16 ... 31: Target velocity (in rpm)	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 806 _h
P7-04 ACC_DEC2	Deceleration and Acceleration of Data Set 2 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 808 _h
P7-05 SPD_DLY2	Waiting Time and Target Velocity of Data Set 2 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 80 A _h
P7-06 ACC_DEC3	Deceleration and Acceleration of Data Set 3 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 80 C _h
P7-07 SPD_DLY3	Waiting Time and Target Velocity of Data Set 3 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 80 E _h
P7-08 ACC_DEC4	Deceleration and Acceleration of Data Set 4 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 810 _h
P7-09 SPD_DLY4	Waiting Time and Target Velocity of Data Set 4 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 812 _h
P7-10 ACC_DEC5	Deceleration and Acceleration of Data Set 5 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 814 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-11 SPD_DLY5	Waiting Time and Target Velocity of Data Set 5 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 816 _h
P7-12 ACC_DEC6	Deceleration and Acceleration of Data Set 6 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 818 _h
P7-13 SPD_DLY6	Waiting Time and Target Velocity of Data Set 6 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 81 A _h
P7-14 ACC_DEC7	Deceleration and Acceleration of Data Set 7 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 81 C _h
P7-15 SPD_DLY7	Waiting Time and Target Velocity of Data Set 7 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 81 E _h
P7-16 ACC_DEC8	Deceleration and Acceleration of Data Set 8 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 820 _h
P7-17 SPD_DLY8	Waiting Time and Target Velocity of Data Set 8 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 822 _h
P7-18 ACC_DEC9	Deceleration and Acceleration of Data Set 9 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 824 _h
P7-19 SPD_DLY9	Waiting Time and Target Velocity of Data Set 9 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 826 _h
P7-20 ACC_DEC10	Deceleration and Acceleration of Data Set 10 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 828 _h
P7-21 SPD_DLY10	Waiting Time and Target Velocity of Data Set 10 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 82 A _h
P7-22 ACC_DEC11	Deceleration and Acceleration of Data Set 11 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 82 C _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-23 SPD_DLY11	Waiting Time and Target Velocity of Data Set 11 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 82E _h
P7-24 ACC_DEC12	Deceleration and Acceleration of Data Set 12 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 830 _h
P7-25 SPD_DLY12	Waiting Time and Target Velocity of Data Set 12 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 832 _h
P7-26 ACC_DEC13	Deceleration and Acceleration of Data Set 13 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 834 _h
P7-27 SPD_DLY13	Waiting Time and Target Velocity of Data Set 13 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 836 _h
P7-28 ACC_DEC14	Deceleration and Acceleration of Data Set 14 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 838 _h
P7-29 SPD_DLY14	Waiting Time and Target Velocity of Data Set 14 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 83 A _h
P7-30 ACC_DEC15	Deceleration and Acceleration of Data Set 15 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 83C _h
P7-31 SPD_DLY15	Waiting Time and Target Velocity of Data Set 15 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 83E _h
P7-32 ACC_DEC16	Deceleration and Acceleration of Data Set 16 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 840 _h
P7-33 SPD_DLY16	Waiting Time and Target Velocity of Data Set 16 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 842 _h
P7-34 ACC_DEC17	Deceleration and Acceleration of Data Set 17 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 844 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-35 SPD_DLY17	Waiting Time and Target Velocity of Data Set 17 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 846 _h
P7-36 ACC_DEC18	Deceleration and Acceleration of Data Set 18 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 848 _h
P7-37 SPD_DLY18	Waiting Time and Target Velocity of Data Set 18 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 84 A _h
P7-38 ACC_DEC19	Deceleration and Acceleration of Data Set 19 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 84C _h
P7-39 SPD_DLY19	Waiting Time and Target Velocity of Data Set 19 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 84E _h
P7-40 ACC_DEC20	Deceleration and Acceleration of Data Set 20 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 850 _h
P7-41 SPD_DLY20	Waiting Time and Target Velocity of Data Set 20 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 852 _h
P7-42 ACC_DEC21	Deceleration and Acceleration of Data Set 21 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 854 _h
P7-43 SPD_DLY21	Waiting Time and Target Velocity of Data Set 21 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 856 _h
P7-44 ACC_DEC22	Deceleration and Acceleration of Data Set 22 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 858 _h
P7-45 SPD_DLY22	Waiting Time and Target Velocity of Data Set 22 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 85 A _h
P7-46 ACC_DEC23	Deceleration and Acceleration of Data Set 23 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 85C _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-47 SPD_DLY23	Waiting Time and Target Velocity of Data Set 23 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 85E _h
P7-48 ACC_DEC24	Deceleration and Acceleration of Data Set 24 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 860 _h
P7-49 SPD_DLY24	Waiting Time and Target Velocity of Data Set 24 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 862 _h
P7-50 ACC_DEC25	Deceleration and Acceleration of Data Set 25 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 864 _h
P7-51 SPD_DLY25	Waiting Time and Target Velocity of Data Set 25 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 866 _h
P7-52 ACC_DEC26	Deceleration and Acceleration of Data Set 26 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 868 _h
P7-53 SPD_DLY26	Waiting Time and Target Velocity of Data Set 26 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 86 A _h
P7-54 ACC_DEC27	Deceleration and Acceleration of Data Set 27 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 86C _h
P7-55 SPD_DLY27	Waiting Time and Target Velocity of Data Set 27 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 86E _h
P7-56 ACC_DEC28	Deceleration and Acceleration of Data Set 28 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 870 _h
P7-57 SPD_DLY28	Waiting Time and Target Velocity of Data Set 28 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 872 _h
P7-58 ACC_DEC29	Deceleration and Acceleration of Data Set 29 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 874 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-59 SPD_DLY29	Waiting Time and Target Velocity of Data Set 29 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 876 _h
P7-60 ACC_DEC30	Deceleration and Acceleration of Data Set 30 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 878 _h
P7-61 SPD_DLY30	Waiting Time and Target Velocity of Data Set 30 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 87 A _h
P7-62 ACC_DEC31	Deceleration and Acceleration of Data Set 31 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 87C _h
P7-63 SPD_DLY31	Waiting Time and Target Velocity of Data Set 31 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 87E _h
P7-64 ACC_DEC32	Deceleration and Acceleration of Data Set 32 Applicable operating mode: PS See P7-02 for details.	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 880 _h
P7-65 SPD_DLY32	Waiting Time and Target Velocity of Data Set 32 Applicable operating mode: PS See P7-03 for details.	0.1rpm ms 0 0 200 0 60000 32767 Decimal	u32 RW per.	Modbus 882 _h

P8 - Control Loops

P8 - Control Loops

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-00 LTND	Derivative Gain Applicable operating mode: PT, PS, V This parameter is used to adjust the derivative gain. Refer to chapter Manual Tuning (see page 191).	0.1Hz 0 800 20000 Decimal	u32 RW per.	Modbus 900 _h
P8-01 LTNI	Integral Gain Applicable operating mode: PT, PS, V This parameter is used to adjust the integral gain. Refer to chapter Manual Tuning (see page 191).	0.1Hz 0 100 2000 Decimal	u32 RW per.	Modbus 902 _h
P8-02 LTNIV	Derivative-Integral Gain Applicable operating mode: PT, PS, V This parameter is used to adjust the derivative-integral gain. Refer to chapter Manual Tuning (see page 191).	0.1Hz 0 400 4000 Decimal	u32 RW per.	Modbus 904 _h
P8-03 LTNP	Proportional Gain Applicable operating mode: PT, PS, V This parameter is used to adjust the proportional gain. Refer to chapter Manual Tuning (see page 191).	0.1Hz 0 300 4000 Decimal	u32 RW per.	Modbus 906 _h
P8-04 LTNUSERGAIN	Global Gain Applicable operating mode: PT, PS, V	0.001 100 500 3000 Decimal	u32 RW per.	Modbus 908 _h
P8-05 NLAFFLPFHZ	HD Spring Filter Applicable operating mode: PT, PS, V This parameter is used to set a low-pass filter for the acceleration profile during tuning. Refer to chapter Manual Tuning (see page 191).	Hz 10 7000 7000 Decimal	u16 RW per.	Modbus 90 A _h
P8-06 NLANTIVIBGAIN	Anti-Vibration Gain Applicable operating mode: PT, PS, V	Rad*10-3/N 0 0 10000 Decimal	u32 RW per.	Modbus 90C _h
P8-07 NLANTIVIBGAIN2	Pe filter 2 Applicable operating mode: PT, PS, V This parameter is used to set the gain of the Pe filter 2.	0.001 0 0 99000 Decimal	u32 RW per.	Modbus 90E _h
P8-08 NLANTIVIBHZ	Anti-Vibration Filter Applicable operating mode: PT, PS, V This parameter is used to set the frequency to remove while using the anti-vibration filter.	0.1Hz 50 4000 4000 Decimal	u32 RW per.	Modbus 910 _h
P8-09 NLANTIVIBHZ2	Pe filter 2 Applicable operating mode: PT, PS, V This parameter is used to set the frequency to remove with the Pe filter 2.	0.1Hz 50 4000 4000 Decimal	u32 RW per.	Modbus 912 _h
P8-10 NLANTIVIBLMJR	Ratio of Load Inertia to Motor Inertia for Anti-Vibration Applicable operating mode: PT, PS, V Expert parameter for the internal control loop.	0.1 0 0 6000 Decimal	u32 RW per.	Modbus 914 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-11 NLANTIVIBN	NL Anti-Resonance Filter Divider Applicable operating mode: PT, PS, V Expert parameter for the internal control loop.	0.01 1 200 10000 Decimal	u32 RW per.	Modbus 916 _h
P8-12 NLANTIVIB-SHARP	Anti-Resonance Sharpness Applicable operating mode: PT, PS, V Expert parameter for the internal control loop.	0.001 10 500 10000 Decimal	u16 RW per.	Modbus 918 _h
P8-13 NLANTIVIB-SHARP2	Pe Sharpness Applicable operating mode: PT, PS, V This parameter is used to optimize the Pe filter action.	0.001 10 500 10000 Decimal	u16 RW per.	Modbus 91 A _h
P8-14 NLFILTDAMPING	Current Filter Damping Applicable operating mode: PT, PS, V For further details, refer to Manual Tuning (see page 191).	% 0 0 100 Decimal	u16 RW per.	Modbus 91C _h
P8-15 NLFILT1	Current Filter Low Pass Filter Rise Time Applicable operating mode: PT, PS, V For further details, refer to Manual Tuning (see page 191).	0.01ms 0 300 3000 Decimal	u16 RW per.	Modbus 91E _h
P8-16 NLNOTCH2BW	Current Filter - Second Notch Filter Bandwidth Applicable operating mode: PT, PS, V	Hz 0 0 500 Decimal	u16 RW per.	Modbus 920 _h
P8-17 NLNOTCH2CENTER	Current Filter - Second Notch Filter Center Applicable operating mode: PT, PS, V	Hz 5 100 1800 Decimal	u16 RW per.	Modbus 922 _h
P8-18 NLNOTCHBW	Current Filter - Notch Filter Bandwidth Applicable operating mode: PT, PS, V	Hz 0 0 500 Decimal	u16 RW per.	Modbus 924 _h
P8-19 NLNOTCHCENTER	Current Filter - Notch Filter Center Applicable operating mode: PT, PS, V For further details, refer to Manual Tuning (see page 191).	Hz 5 100 1800 Decimal	u16 RW per.	Modbus 926 _h
P8-20 NLPEAFF	Elasticity Compensation Applicable operating mode: PT, PS, V This parameter is used in the compensation of the elasticity of the mechanical system. For further details, refer to Manual Tuning (see page 191).	0.1Hz 0 50000 50000 Decimal	u32 RW per.	Modbus 928 _h
P8-21 NLPEDFFRATIO	Spring Deceleration Ratio Applicable operating mode: PT, PS, V This parameter is used in the compensation of the elasticity of the mechanical system. For further details, refer to Manual Tuning (see page 191).	0.001 0 1000 2000 Decimal	u16 RW per.	Modbus 92 A _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-22 NLVELLIM	Analog NCT standstill Applicable operating mode: PT, PS, V If the target value is supplied as an analog voltage signal, this parameter can be used to improve the standstill stability. If the voltage drops below the value specified via this parameter, the integral gain set via parameter P8-01 and the derivative-integral gain set via parameter P8-02 are reduced by one half.	mV -3815 0 3815 Decimal	s16 RW per.	Modbus 92C _h
P8-24 ANIN2LPFHZ	Analog Input 2 - Filter Applicable operating mode: PT, PS, V, T This parameter specifies the cut-off frequency for the first order low-pass filter of analog input 2.	Hz 10 1000 10000 Decimal	u16 RW per.	Modbus 930 _h
P8-25 GEARFILTAFF	Electronic Gear Filter - Acceleration Feedforward Applicable operating mode: PT This parameter specifies the acceleration feed-forward for the electronic gear filter. Setting can only be changed if power stage is disabled.	0.001 -2000 0 2000 Decimal	s16 RW per.	Modbus 932 _h
P8-26 GEARFILTMODE	Electronic Gear Filter - Activation Applicable operating mode: PT This parameter activates/deactivates the electronic gear filter. Value 0: Deactivate electronic gear filter Value 1: Activate electronic gear filter Setting can only be changed if power stage is disabled.	- 0 0 1 Decimal	u16 RW per.	Modbus 934 _h
P8-27 GEARFILTT1	Electronic Gear Filter - Depth Applicable operating mode: PT	0.01ms 75 200 3200 Decimal	u32 RW per.	Modbus 936 _h
P8-28 GEARFILTT2	Electronic Gear Filter - Velocity and Acceleration Depth Applicable operating mode: PT	0.01ms 0 400 6000 Decimal	u16 RW per.	Modbus 938 _h
P8-29 GEARFILTVELFF	Electronic Gear Filter - Velocity Feedforward Applicable operating mode: PT This parameter specifies the velocity feed-forward for the electronic gear filter. Setting can only be changed if power stage is disabled.	0.01ms -20000 0 20000 Decimal	s32 RW per.	Modbus 93 A _h
P8-30 GEARINMODE	Interpolation of Input Signal for Electronic Gear - Activation Applicable operating mode: PT This parameter allows for interpolation of the input signal for electronic gear and increases the resolution by a factor of 16. Value 0: Deactivate interpolation of input signal for electronic gear Value 1: Activate interpolation of input signal for electronic gear Setting can only be changed if power stage is disabled.	- 0 1 1 Decimal	u16 RW per.	Modbus 93C _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-31 GEARING_MODE	Method for Operating Mode Pulse Train (PT) Applicable operating mode: PT Value 0: Synchronization deactivated Value 1: Position synchronization without compensation movement Value 2: Position synchronization with compensation movement Value 3: Velocity synchronization The parameters for acceleration (P1-34), deceleration (P1-35) and velocity (P1-55) act as limitations for the synchronization.	- 0 1 3 Decimal	u16 RW per.	Modbus 93E _h
P8-32 MOVES-MOOTHAVG	S-Curve Setting Applicable operating mode: PT, PS	0.01ms 25 400 25600 Decimal	u32 RW per.	Modbus 940 _h
P8-33 MOVESMOOTH-LPFHZ	Low Pass Filter Setting Applicable operating mode: PT, PS	Hz 1 5000 5000 Decimal	u16 RW per.	Modbus 942 _h
P8-34 MOVESMOOTH-MODE	Smoothing Filter for Operating modes PT and PS - Type Applicable operating mode: PT, PS Value 0: No smoothing Value 1: LPF smoothing Value 2: S-curve smoothing Setting can only be changed if power stage is disabled.	- 0 2 2 Decimal	u16 RW per.	Modbus 944 _h
P8-35 CONTROLMODE	Type of Control Applicable operating mode: PT, PS, V This parameter specifies the type of velocity and position control. Value 5: Velocity control with integral gain (P8-01, P8-02) Value 6: Velocity control without integral gain Value 7: Velocity control with P8-00 = P8-01, P8-02 = 0, P8-03 = 0 Setting can only be changed if power stage is disabled.	- 5 519 519 Hexadecimal	u16 RW per.	Modbus 946 _h
P8-36 NLANTIVIBGAIN3	Pe filter 3 Applicable operating mode: PT, PS, V This parameter is used to set the gain of the Pe filter 3	0.001 0 0 6000 Decimal	u32 RW per.	Modbus 948 _h
P8-37 NLANTIVIBHZ3	Pe filter 3 Applicable operating mode: PT, PS, V This parameter is used to set the frequency to remove with the Pe filter 3.	0.1Hz 50 4000 8000 Decimal	u32 RW per.	Modbus 94 A _h
P8-38 NLANTIVIBQ3	Pe filter 3 Applicable operating mode: PT, PS, V This parameter is used to set the zero-pole alignment with the Pe filter 3.	0.001 200 1000 10000 Decimal	u32 RW per.	Modbus 94C _h
P8-39 IGRAV	Gravity Compensation Applicable operating mode: PT, PS, V, T This parameter is used to set the gravity compensation current for unbalanced systems.	0.01 A - 0 - Decimal	s16 RW per.	Modbus 94E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-40 LTNAFRC	HD AFF Applicable operating mode: PT, PS, V This parameter is used to set the feed forward term for the current command.	- 0 0 200 Decimal	u16 RW per.	Modbus 950 _h
P8-41 NLANTIVIB-SHARP3	Pe Sharpness Applicable operating mode: PT, PS, V This parameter is used to optimize the Pe filter 3 action.	- 10 200 10000 Decimal	u16 RW per.	Modbus 952 _h
P8-42 HOME_FAIL-URE_IND	Homing Error Information Applicable operating mode: PT, PS, V, T This parameter provides information in case of the homing is not successful.	- 0 - FFFFFFFF _h Hexadecimal	u32 RO -	Modbus 954 _h
P8-43 ZSPDLPFHZ	ZSPD Low Pass Filter Value Applicable operating mode: PT, PS, V, T This parameter sets the low pass filter value for ZSPD output in order to reduce jitters when the motor speed is around the Zero speed Threshold (P1-38) value.	Hz 10 1000 1000 Decimal	u16 RW per.	Modbus 956 _h
P8-45 FEEDBACKTYPE	Feedback type Applicable operating mode: PT, PS, V, T Value 0: No feedback connected or undetermined feedback connected. Value 1: single turn encoder.	- 0 - 2 Decimal	u16 RO -	Modbus 95 A _h
P8-46 SRVSNS_TEMPERATURE	Encoder temperature Applicable operating mode: PT, PS, V, T	Deg. - - - Decimal	s16 RO -	Modbus 95C _h
P8-47 SRVSNS_VER	Encoder firmware and hardware versions Applicable operating mode: PT, PS, V, T The format is: ZZaabbcc - aa.bb.cc: firmware version. - ZZ: hardware version.	- - - 4294967295 Decimal	u32 RO -	Modbus 95E _h
P8-48 SRVSNS_FLTS	Encoder errors Applicable operating mode: PT, PS, V, T - Bit 0: The returned position values are no longer considered as reliable. - Bit 1: The device temperature is too high. - Bit 2: The device temperature is too low. - Bit 3: The device is not calibrated or the calibration data is corrupted. The device is not able to decode the position. - Bit 4: The device supply voltage has dropped under operational value. - Bit 16...23: Internal Error detected. - Bit 24: The FW cannot operate on the provided HW. - Bit 25...31: Reserved.	- - - 4294967295 Hexadecimal	u32 RO -	Modbus 960 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-49 SRVSNS_WRNS	Encoder alerts Applicable operating mode: PT, PS, V, T ● Bit 0: The device temperature is too high. ● Bit 1: The device temperature is too low. ● Bit 2: Over speed. ● Bit 3: Over acceleration. ● Bit 4: Invalid checksum value detected on non-volatile memory initialization. ● Bit 5: non-volatile memory is empty. ● Bit 6: Internal Parameters area detected as invalid, default values are used. ● Bit 7: Invalid decoding sequence detected. ● Bit 8: Encoder internal flash error detected. ● Bit 9: The device has detected unusual high shaft displacement. Position error might be greater than usual. ● Bit 10...31: Reserved.	- - - 4294967295 Hexadecimal	u32 RO -	Modbus 962 _h
P8-99 LTNUSERVCM-DGAIN	Adaptive Velocity Reference Value Gain Applicable operating mode: PT, PS	0.001 0 1000 3000 Decimal	u32 RW per.	Modbus 9C6 _h

P9 - DTM Data

P9 - DTM Data

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-00 PRGNR	Lexium program number Applicable operating mode: PT, PS, V, T Reads the program number	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RO -	Modbus A00 _h
P9-01 DATE	Firmware Version Date Applicable operating mode: PT, PS, V, T This parameter contains the date of the firmware version.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RO -	Modbus A02 _h
P9-02 MTP_ID	MTP Identification Code Applicable operating mode: PT, PS, V, T	- 0 _h - FFFFFFFF _h Hexadecimal	u16 RO -	Modbus A04 _h
P9-06 UNAME1	User-Defined Application Name 1 Applicable operating mode: PT, PS, V, T This parameter is provided for a user-defined application name.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW per.	Modbus A0C _h
P9-07 UNAME2	User-Defined Application Name 2 Applicable operating mode: PT, PS, V, T This parameter is provided for a user-defined application name.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW per.	Modbus A0E _h
P9-08 UNAME3	User-Defined Application Name 3 Applicable operating mode: PT, PS, V, T This parameter is provided for a user-defined application name.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW per.	Modbus A10 _h
P9-09 UNAME4	User-Defined Application Name 4 Applicable operating mode: PT, PS, V, T This parameter is provided for a user-defined application name.	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RW per.	Modbus A12 _h
P9-10 MBWORD	Modbus Word Order Applicable operating mode: PT, PS, V, T This parameter sets the word order for Modbus. Value 0: Order of the bytes: 0 1 2 3 Value 1: Order of the bytes: 2 3 0 1	- 0 0 1 Decimal	u16 RW per.	Modbus A14 _h
P9-11 SERNUM1	Serial Number Part 1 Applicable operating mode: PT, PS, V, T	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RO -	Modbus A16 _h
P9-12 SERNUM2	Serial Number Part 2 Applicable operating mode: PT, PS, V, T	- 0 _h 0 _h FFFFFFFF _h Hexadecimal	u32 RO -	Modbus A18 _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-13 SERNUM3	Serial Number Part 3 Applicable operating mode: PT, PS, V, T	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RO -	Modbus A1A _h
P9-14 SERNUM4	Serial Number Part 4 Applicable operating mode: PT, PS, V, T	- 0 _h 0 _h FFFFFFF _h Hexadecimal	u32 RO -	Modbus A1C _h
P9-15 LTN	Autotuning Method Applicable operating mode: PT, PS, V, T	- 0 0 6 Decimal	u16 RW -	Modbus A1E _h
P9-16 LTNREFERENCE	Autotuning Motion Profile - Type Applicable operating mode: PT, PS, V	- 0 0 2 Decimal	u16 RW -	Modbus A20 _h
P9-17 LTNAVMODE	Anti-vibration tuning mode. Applicable operating mode: PT, PS, V	- 0 0 6 Decimal	u16 RW -	Modbus A22 _h
P9-18 LTNSAVEMODE	Autotuning Results - Save/Discard Applicable operating mode: PT, PS, V	- 0 0 3 Decimal	u16 RW -	Modbus A24 _h
P9-19 LTNNLPEAFF	Autotuning - Elasticity Compensation Filters Applicable operating mode: PT, PS, V	- 0 1 1 Decimal	s16 RW -	Modbus A26 _h
P9-20 LTNCYCLE	Autotuning - Direction of Movement Applicable operating mode: PT, PS, V This parameter sets the direction of movement for autotuning. Value 0: Both directions of movement Value 2: One direction of movement	- 0 0 3 Decimal	s16 RW -	Modbus A28 _h
P9-21 LTNDWELLTIME	Minimum Dwell Time for Detection of Movement Cycle Applicable operating mode: PT, PS, V	- 100 200 1000 Decimal	u16 RW -	Modbus A2A _h
P9-22 LTNLMJR	Autotuning - Automatic Estimation of Ratio of Load Inertia and Motor Inertia Applicable operating mode: PT, PS, V	- 0 0 1 Decimal	u16 RW -	Modbus A2C _h
P9-23 LTNSTIFF	Defines which values will be used for the position command filters. Applicable operating mode: PT, PS, V Value 0: Automatic smoothing via S-curve optimization of the value Value 1: Manual smoothing	- 0 0 1 Decimal	u16 RW -	Modbus A2E _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-25 LTNREFEN	Autotuning Motion Profile - Activation Applicable operating mode: PT, PS, V	- 0 0 1 Decimal	u16 RW -	Modbus A32 _h
P9-26 PTPOS	Autotuning - Movement Range in Direction 1 Applicable operating mode: PS This parameter specifies the movement range for autotuning in direction of movement 1. The sign of the value determines the direction of movement: Positive value: Positive direction of movement as set via parameter P1-01 Negative value: Negative direction of movement as set via parameter P1-01 See parameter P9-20 to select one direction of movement or both directions of movement for Comfort Tuning.	PUU -2147483647 0 2147483647 Decimal	s32 RW -	Modbus A34 _h
P9-27 PTNEG	Autotuning - Movement Range in Direction 2 Applicable operating mode: PS This parameter specifies the movement range for autotuning in direction of movement 2. The sign of the value determines the direction of movement: Positive value: Positive direction of movement as set via parameter P1-01 Negative value: Negative direction of movement as set via parameter P1-01 See parameter P9-20 for Comfort Tuning in a single or in both directions of movement. See parameter P9-20 to select one direction of movement or both directions of movement for Comfort Tuning.	PUU -2147483647 0 2147483647 Decimal	s32 RW -	Modbus A36 _h
P9-28 LTNACTIVE	Autotuning Active Applicable operating mode: PT, PS, V This parameter indicates whether autotuning is active. Value 0: Autotuning inactive Value 1: Autotuning active	- 0 - 1 Decimal	s16 RO -	Modbus A38 _h
P9-29 LTNVCRUISE	Autotuning - Velocity Applicable operating mode: PT, PS, V Bits 0 ... 15: Velocity for positive direction of movement Bits 16 ... 31: Velocity for negative direction of movement	0.1rpm 0.1rpm - - - Decimal	u32 RW -	Modbus A3A _h

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-30 LTNST	Autotuning - Status Applicable operating mode: PT, PS, V Value 0: Inactive Value 1: Active Value 2: Successfully completed Values 3 ... 9: Reserved Value 10: Impossible to set P9-15 Value 11: Impossible to set P9-16 Value 12: Impossible to set P9-17 Value 13: Impossible to set P9-18 Value 14: Impossible to set P9-19 Value 15: Impossible to set P9-21 Value 16: Impossible to set P9-22 Value 17: Impossible to set P9-23 Value 18: Impossible to set P9-24 Value 19: Impossible to set P9-25 Value 20: Impossible to set P9-32 Value 21: Impossible to enable the power stage Value 22: Hold is active Value 23: Undetermined motor Values 24 ... 26: Reserved Value 27: Impossible to activate autotuning Value 28: Autotuning did not run successfully Value 29: Reserved Value 30: Low Effort Value 31: AVG Zero Init Value Value 32: Cost factor error detected Value 33: Pos tune user gain modified Value 34: Motor Was Not Recognized Value 35: LTNP Step Updated Value 36: Movement too small Value 37: LTNIV verify Value 38: ICMD Sat	- 0 - 65535 Decimal	u32 RO -	Modbus A3C _h
P9-30 Continued	Value 39: Insufficient velocity (less than 10 % of nominal velocity) Value 40: Insufficient acceleration/deceleration (less than 33 % of nominal acc/dec) Value 41: Excessive acceleration/deceleration (more than 90 % of nominal acc/dec) Value 42: Need gravity compensation Values 43 ... 45: Reserved Value 46: Ratio of load inertia to motor inertia is too high (>30) Values 47 ... 49: Reserved Value 50: P9-15 set to 0 Value 51: Power stage disabled during autotuning Value 52: Current saturation Value 53: Reserved Value 54: Insufficient excitation for autotuning (poor motion profile: short distance, low acceleration/deceleration, etc.) Value 55: Insufficient tuning effort Value 56: Halt during autotuning Value 57: Undetermined motor Value 58: Motion profile exceeds limits Value 59: Invalid gains during autotuning Value 60: Insufficient movement Values 61 ... 69: Reserved			

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P9-31 PTACCDEC	Autotuning - Acceleration and Deceleration Applicable operating mode: PT, PS, V Bits 0 ... 15: Acceleration for Autotuning Bits 16 ... 31: Deceleration for Autotuning	ms ms 6 6 6000 6000 65500 65500 Decimal	u32 RW -	Modbus A3E _h
P9-32 LTNADVMODE	Autotune advance mode. Applicable operating mode: PT, PS, V	- 0 1 2 Decimal	u16 RW -	Modbus A40 _h
P9-33 LTNEFFORTMAX	Maximum Autotuning Optimization Value Applicable operating mode: PT, PS, V Setting can only be changed if power stage is disabled.	0.001 0 - 1000 Decimal	u32 RO -	Modbus A42 _h
P9-34 LTNBAR	Autotuning Progress Bar Applicable operating mode: PT, PS, V	- 0 0 100 Decimal	u16 RO -	Modbus A44 _h
P9-35 LTNIGRAV	Autotuning - Gravity Estimation Applicable operating mode: PT, PS, V	- 0 0 1 Decimal	u16 RW -	Modbus A46 _h
P9-36 LTNNLAFRC	Set LTNAFRC in Autotune Applicable operating mode: PT, PS, V	- 0 0 2 Decimal	s16 RW -	Modbus A48 _h
P9-37 LTNWARNING	Autotuning - Last Stored Event Applicable operating mode: PT, PS, V	- 0 0 65535 Decimal	u32 RO -	Modbus A4A _h
P9-38 LTNIMPROVE-MENT	Mode 2 AT improvement Applicable operating mode: PT, PS, V, T	- 0 0 100 Decimal	u16 RO -	Modbus A4C _h
P9-39 LTNCYCLEIDENT	Cycle Identification status Applicable operating mode: PT, PS, V, T	- 0 0 9 Decimal	u16 RO -	Modbus A4E _h
P9-40 LTNDEFAULTS	LTN Autotuning Using Defaults Applicable operating mode: PT, PS, V	- 0 0 65535 Decimal	u16 RW -	Modbus A50 _h

Part VII

Operation

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Chapter 17

Operation

What Is in This Chapter?

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Access Channels

The product can be accessed via different types of access channels. Simultaneous access via multiple access channels or the use of exclusive access may cause unintended equipment operation.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Verify that simultaneous access via multiple access channels cannot cause unintended triggering or blocking of commands.
- Verify that the use of exclusive access cannot cause unintended triggering or blocking of commands.
- Verify that the required access channels are available.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The product can be addressed via different access channels.

Access channels are:

- Integrated HMI
- Digital and analog input signals
- Commissioning software LXM26 DTM Library

The product allows you to work with exclusive access which limits access to the product via a single access channel.

Only one access channel can have exclusive access to the product.

Exclusive access can be provided via different access channels:

- Via the integrated HMI:
The operating mode Jog or Autotuning can be started via the HMI.
- Via the commissioning software LXM26 DTM Library:
The commissioning software receives exclusive access via the switch *Exclusive access* in position *On*.

When the product is powered on, there is no exclusive access via an access channel.

The reference values are effective at the analog inputs and at the pulse inputs when the product is powered on. If exclusive access has been assigned to an access channel, signal at the pulse inputs are ignored.

The signal input functions **HALT**, **FAULT_RESET**, **SON** (falling edge), **CWL(NL)** and **CCWL(PL)** are always effective during exclusive access.

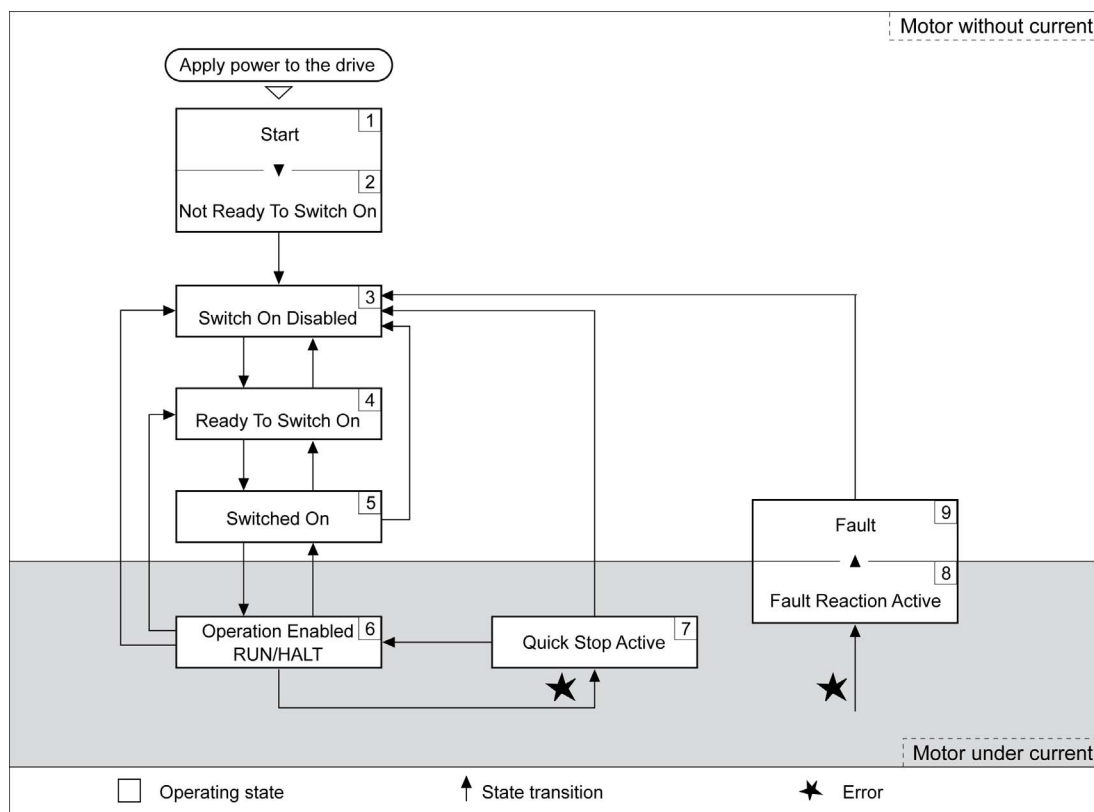
Operating States

State Diagram

When the product is powered on and when an operating mode is started (*see page 285*), the product goes through a number of operating states.

The state diagram (state machine) shows the relationships between the operating states and the state transitions.

The operating states are internally monitored and influenced by monitoring functions.



Operating States

Operating state	Description
1 Start	Electronics are initialized
2 Not Ready To Switch On	The power stage is not ready to switch on
3 Switch On Disabled	Impossible to enable the power stage
4 Ready To Switch On	The power stage is ready to switch on.
5 Switched On	Power stage is switched on
6 Operation Enabled	Power stage is enabled Selected operating mode is active
7 Quick Stop Active	Quick Stop is being executed
8 Fault Reaction Active	Error response is active
9 Fault	Error response terminated Power stage is disabled

Resetting an Error Message

After you have removed the cause of the error, you can reset the error message in one of the following ways:

- With a rising edge of the signal input function **FAULT_RESET**
- With a rising edge of the signal input function **SON**
- By setting parameter P0-01 to the value 0

Setting the Digital Signal Inputs

Various signal functions can be assigned to the digital signal inputs.

The functions of the inputs and outputs depend on the selected operating mode and the settings of the corresponding parameters.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Only start the system if there are no persons or obstructions in the zone of operation.
- Verify that the wiring is appropriate for the settings.
- Carefully run tests for all operating states and potential error situations when commissioning, upgrading or otherwise modifying the operation of the drive.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Default Presets of the Signal Inputs

The following table shows the default presets of the digital signal inputs depending on the selected operating mode:

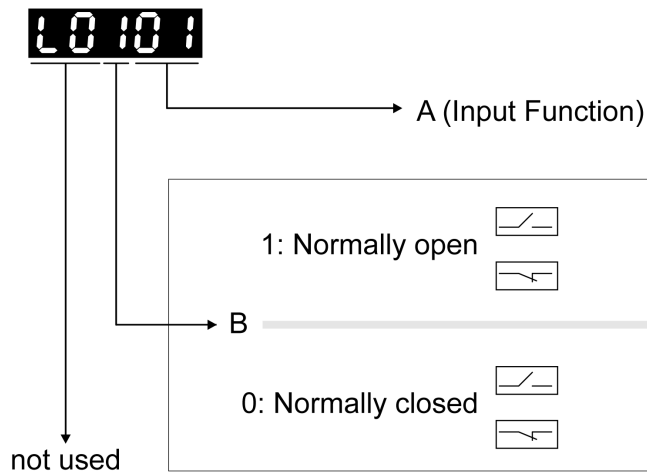
Setting A for P2-10 ... P2-17	Short name	Name	PT	PS	V	T	Vz	Tz	PT V	PT T	PS V	PS T	V T
01 _h	SON	Servo ON	DI1	DI1	DI1	DI1	DI1	DI1	DI1	DI1	DI1	DI1	DI1
02 _h	FAULT_ RESET	Fault Reset	DI5	DI5	DI5	DI5	DI5	DI5	-				
03 _h	GAINUP	Increase Gain	-										
04 _h	CLRPOS- DEV	Clear Position Deviation	DI2	-					DI2	DI2	-		
05 _h	ZCLAMP	Zero Clamp	-										
06 _h	INVDIRROT	Inverse Direction Of Rotation	-										
07 _h	HALT	Halt	-										
08 _h	CTRG	Start Data Set	-	DI2	-						DI2	DI2	-
09 _h	TRQLM	Activate Torque Limit	-		DI2	-	DI2	-					
10 _h	SPDLM	Activate Speed Limit	-			DI2	-	DI2	-				
11 _h	POS0	Data Set Bit 0	-	DI3	-						DI3	DI3	-
12 _h	POS1	Data Set Bit 1	-	DI4	-						DI4	DI4	-
13 _h	POS2	Data Set Bit 2	-										
14 _h	SPD0	Speed Reference Value Bit 0	-		DI3	-	DI3	-	DI3	-	DI5	-	DI3
15 _h	SPD1	Speed Reference Value Bit 1	-		DI4	-	DI4	-	DI4	-	DI6	-	DI4
16 _h	TCM0	Torque Reference Value Bit 0	DI3	-		DI3	-	DI3	-	DI3	-	DI5	DI5
17 _h	TCM1	Torque Reference Value Bit 1	DI4	-		DI4	-	DI4	-	DI4	-	DI6	DI6
18 _h	V-Px	Velocity - Position	-						DI7	-	DI7	-	
19 _h	V-T	Velocity - Torque	-										DI7
1 A _h	POS3	Data Set Bit 3	-										
1B _h	POS4	Data Set Bit 4	-										
1C _h	TPROB1	Touch Probe 1	-										
20 _h	T-Px	Torque - Position	-							DI7	-	DI7	-

Setting A for P2-10 ... P2-17	Short name	Name	PT	PS	V	T	Vz	Tz	PT V	PT T	PS V	PS T	V T
21 _h	OPST	Stop and Disable Power Stage	DI8	DI8	DI8	DI8	DI8	DI8	DI8	DI8	DI8	DI8	DI8
22 _h	CWL(NL)	Negative Limit Switch (NL/LIMN)	DI6	DI6	DI6	DI6	DI6	DI6	-				
23 _h	CCWL(PL)	Positive Limit Switch (PL/LIMP)	DI7	DI7	DI7	DI7	DI7	DI7	-				
24 _h	ORGP	Reference Switch	-										
27 _h	GOTO-HOME	Move To Home Position	-										
2C _h	PTCMS	Type of pulses for operating mode Pulse Train (PT) (OFF: Low-speed pulses, ON: High-Speed pulses)	-										
37 _h	JOGP	Jog Positive	-										
38 _h	JOGN	Jog Negative	-										
39 _h	STEPSU	Next Data Set	-										
40 _h	STEPD	Previous Data Set	-										
41 _h	STEPB	First Data Set	-										
42 _h	AUTOR	Automatic Position Sequence: Start with first data set, repeat sequence	-										
43 _h	GNUM0	Numerator Bit 0 Electronic Gear Ratio	-										
44 _h	GNUM1	Numerator Bit 1 Electronic Gear Ratio	-										
45 _h	INHP	Pulse Inhibit	-										
46 _h	STOP	Stop Motor (operating mode PS only)	-										

Parameterization of the Signal Input Functions

The signal input functions for the inputs DI1 ... DI8 are configured via the parameters P2-10 ... P2-17.

A signal input function can only be assigned to one of the signal inputs.



The operating modes Torque (T) and Torque (Tz) and the dual operating modes with Torque (T) and Torque (Tz) do not provide deceleration functionality in response to a power stage disable request. In these operating modes, the motor coasts down to a standstill in response to a power stage disable request. You must install additional equipment such as a dedicated service brake if your application requires faster deceleration of the load.

⚠ WARNING

UNINTENDED EQUIPMENT OPERATION

- During commissioning, trigger all signals and simulate all conditions that cause a power stage disable request in order to verify that all loads come to a secure standstill when the power stage is disabled under maximum load conditions.
- Install a dedicated service brake if removal of power to the motor does not meet the requirements of your application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

The following table provides an overview of the possible signal input functions:

Setting A for P2- 10 ... P2- 17	Short name	Name	Description	Signal inputs
01 _h	SON	Servo ON	The signal input function SON enables the power stage (operating state Operation Enabled). The signal input function SON is only available if no detected errors are present.	DI1 ... DI8
02 _h	FAULT_ RESET	Fault Reset	The signal input function FAULT_RESET performs a Fault Reset. The cause of the error must have been removed before a Fault Reset is performed.	DI1 ... DI8
03 _h	GAINUP	Increase Gain	The signal input function GAINUP increases the control gain according to the values and conditions set via parameter P2-27.	DI1 ... DI8
04 _h	CLRPOS- DEV	Clear Position Deviation	The signal input function CLRPOSDEV resets the position deviation to zero as set via parameter P2-50.	DI1 ... DI8
05 _h	ZCLAMP	Zero Clamp	In the operating mode V, the signal input function ZCLAMP can be used to stop the motor if the velocity of the motor is below the velocity value set via the parameter P1-38. The behavior of the signal input function ZCLAMP is set via the parameter P2-65, bit 10.	DI1 ... DI8

Setting A for P2- 10 ... P2- 17	Short name	Name	Description	Signal inputs
06 _h	INVDIR- ROT	Inverse Direction Of Rotation	The signal input function INVDIRROT inverts the direction of rotation of the motor. The signal input function INVDIRROT is available in the operating modes Velocity (V) and Torque (T).	DI1 ... DI8
07 _h	HALT	Halt	The signal input function HALT interrupts the movement with the deceleration ramp set via the parameter P1-68. The movement is resumed when the signal input function is no longer active.	DI1 ... DI8
08 _h	CTRG	Start Data Set	The signal input function CTRG starts the selected data set in the operating mode Position Sequence (PS). For further information, refer to Operating Mode Position Sequence (PS) (<i>see page 296</i>).	DI1 ... DI8
09 _h	TRQLM	Activate Torque Limit	The signal input function TRQLM activates the torque limitations set via parameters P1-12 ... P1-14. You can also use the parameter P1-02 to activate the torque limitations set via parameters P1-12 ... P1-14.	DI1 ... DI8
10 _h	SPDLM	Activate Speed Limit	The signal input function SPDLM activates the velocity limitations set via parameters P1-09 ... P1-11. You can also use the parameter P1-02 to activate the velocity limitations set via parameters P1-09 ... P1-11.	DI1 ... DI8
11 _h	POS0	Data Set Bit 0	The signal input functions POS0 ... POS4 represent bits 0 ... 4 required to select one of the 32 data sets available in the operating mode Position Sequence (PS). For further information, refer to Operating Mode Position Sequence (PS) (<i>see page 296</i>).	DI1 ... DI8
12 _h	POS1	Data Set Bit 1	The signal input functions POS0 ... POS4 represent bits 0 ... 4 required to select one of the 32 data sets available in the operating mode Position Sequence (PS). For further information, refer to Operating Mode Position Sequence (PS) (<i>see page 296</i>).	DI1 ... DI8
13 _h	POS2	Data Set Bit 2	The signal input functions POS0 ... POS4 represent bits 0 ... 4 required to select one of the 32 data sets available in the operating mode Position Sequence (PS). For further information, refer to Operating Mode Position Sequence (PS) (<i>see page 296</i>).	DI1 ... DI8
14 _h	SPD0	Speed Reference Value Bit 0	The signal input functions SPD0 and SPD1 represent bits 0 and 1 to select one of the three velocity reference values available in the operating mode Velocity (V). For further information, refer to Operating Modes Velocity (V) and Velocity Zero (Vz) (<i>see page 330</i>).	DI1 ... DI8
15 _h	SPD1	Speed Reference Value Bit 1	The signal input functions SPD0 and SPD1 represent bits 0 and 1 to select one of the three velocity reference values available in the operating mode Velocity (V). For further information, refer to Operating Modes Velocity (V) and Velocity Zero (Vz) (<i>see page 330</i>).	DI1 ... DI8
16 _h	TCM0	Torque Reference Value Bit 0	The signal input functions TCM0 and TCM1 represent bits 0 and 1 to select one of the three torque reference values available in the operating mode Torque (T). For further information, refer to Operating Modes Torque (T) and Torque Zero (Tz) (<i>see page 335</i>).	DI1 ... DI8
17 _h	TCM1	Torque Reference Value Bit 1	The signal input functions TCM0 and TCM1 represent bits 0 and 1 to select one of the three torque reference values available in the operating mode Torque (T). For further information, refer to Operating Modes Torque (T) and Torque Zero (Tz) (<i>see page 335</i>).	DI1 ... DI8
18 _h	V-Px	Velocity - Position	Operating mode switching between Velocity (V) and Pulse Train (PT) or between Velocity (V) and Position Sequence (PS). For further information, refer to Setting the Operating Mode (<i>see page 286</i>). (OFF: Velocity (V), ON: Pulse Train (PT) or Position Sequence (PS), depending on P1-01)	DI1 ... DI8

Setting A for P2- 10 ... P2- 17	Short name	Name	Description	Signal inputs
19 _h	V-T	Velocity - Torque	Operating mode switching between Velocity (V) and Torque (T). For further information, refer to Setting the Operating Mode (see page 286). (OFF: Velocity (V), ON: Pulse Torque (T))	DI1 ... DI8
1 A _h	POS3	Data Set Bit 3	The signal input functions POS0 ... POS4 represent bits 0 ... 4 required to select one of the 32 data sets available in the operating mode Position Sequence (PS). For further information, refer to Operating Mode Position Sequence (PS) (see page 296).	DI1 ... DI8
1B _h	POS4	Data Set Bit 4	The signal input functions POS0 ... POS4 represent bits 0 ... 4 required to select one of the 32 data sets available in the operating mode Position Sequence (PS). For further information, refer to Operating Mode Position Sequence (PS) (see page 296).	DI1 ... DI8
1C _h	TPROB1	Touch Probe 1	The signal input function TPROB1 is used to trigger the Position Capture function. See the sections on the parameters P5-37 ... P5-39 for additional information.	DI7
1D _h	TPROB2	Touch Probe 2	The signal input function TPROB2 is used to trigger the Position Capture function. See the sections on the parameters P5-37 ... P5-39 for additional information.	DI6
20 _h	T-Px	Torque - Position	Operating mode switching between Torque (T) and Pulse Train (PT) or between Torque (T) and Position Sequence (PS). For further information, refer to Setting the Operating Mode (see page 286). (OFF: Torque (T), ON: Pulse Train (PT) or Position Sequence (PS), depending on P1-01)	DI1 ... DI8
21 _h	OPST	Stop and Disable Power Stage	The signal input function OPST stops the motor with the deceleration ramp set via the parameter P1-68 and then disables the power stage.	DI1 ... DI8
22 _h	CWL(NL)	Negative Limit Switch (NL/LIMN)	Negative limit switch (NL/LIMN). When the signal input is activated, an alert is triggered. The deceleration ramp is specified via parameter P5-25.	DI1 ... DI8
23 _h	CCWL(PL)	Positive Limit Switch (PL/LIMP)	Positive limit switch (PL/LIMP). When the signal input is activated, an alert is triggered. The deceleration ramp is specified via parameter P5-26.	DI1 ... DI8
24 _h	ORGP	Reference Switch	The signal input function ORGP is used for the reference switch. For further information, refer to Operating Mode Position Sequence (PS) (see page 296).	DI1 ... DI8
27 _h	GOTO-HOME	Move To Home Position	The signal input function GOTOHOME triggers a movement to the Home position set via the parameter P5-04.	DI1 ... DI8
2C _h	PTCMS	Type of pulses for operating mode Pulse Train (PT) (OFF: Low-speed pulses, ON: High-Speed pulses)	The signal input function PTCMS selects the type of pulses for the operating mode Pulse Train PT (OFF: Low-speed pulses, ON: High-speed pulses). You can also use the parameter P1-00 to select the type of pulses.	DI1 ... DI8
37 _h	JOGP	Jog Positive	The signal input function JOGP triggers a Jog movement in positive direction if the value determining the direction of movement in the parameter P1-01 is set to the default value.	DI1 ... DI8
38 _h	JOGN	Jog Negative	The signal input function JOGN triggers a Jog movement in negative direction if the value determining the direction of movement in the parameter P1-01 is set to the default value.	DI1 ... DI8
39 _h	STEPS	Next Data Set	The signal input function STEPU starts the next data set in the operating mode Position Sequence (PS).	DI1 ... DI8
40 _h	STEPD	Previous Data Set	The signal input function STEPD starts the previous data set in the operating mode Position Sequence (PS).	DI1 ... DI8

Setting A for P2- 10 ... P2- 17	Short name	Name	Description	Signal inputs
41 _h	STEPB	First Data Set	The signal input function STEPB starts the first data set in the operating mode Position Sequence (PS).	DI1 ... DI8
42 _h	AUTOR	Automatic Position Sequence: Start with first data set, repeat sequence	The signal input function AUTOR starts a sequence of data sets from the first data set in the operating mode Position Sequence (PS). The sequence is repeated as long as the signal input function AUTOR is active.	DI1 ... DI8
43 _h	GNUM0	Numerator Bit 0 Electronic Gear Ratio	The signal input functions GNUM0 and GNUM1 represent bits 0 and 1 to select one of the four numerators set via the parameters P1-44, P2-60 ... P2-62. The denominator is set via the parameter P1-45. The ratios are used as gear factors in the operating mode Pulse Train (PT) and as scaling factors. For further information, refer to Gear Ratio (see page 293) and Scaling (see page 300).	DI1 ... DI8
44 _h	GNUM1	Numerator Bit 1 Electronic Gear Ratio	The signal input functions GNUM0 and GNUM1 represent bits 0 and 1 to select one of the four numerators set via the parameters P1-44, P2-60 ... P2-62. The denominator is set via the parameter P1-45. The ratios are used as gear factors in the operating mode Pulse Train (PT) and as scaling factors. For further information, refer to Gear Ratio (see page 293) and Scaling (see page 300).	DI1 ... DI8
45 _h	INHP	Pulse Inhibit	The signal input function INHP is used in the operating mode Pulse Train (PT) to block pulses received as reference signals. If the signal input function is active, the pulses are no longer evaluated and the motor coasts down.	DI1 ... DI8
46 _h	STOP	Stop Motor (operating mode PS only)	The signal input function STOP stops the motor with the deceleration ramp set via the parameter P5-20. The power stage remains enabled. The signal input function STOP is available in the operating mode Position Sequence (PS).	DI1 ... DI8

Setting the Digital Signal Outputs

Various signal functions can be assigned to the digital signal outputs.

The functions of the inputs and outputs depend on the selected operating mode and the settings of the corresponding parameters.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Only start the system if there are no persons or obstructions in the zone of operation.
- Verify that the wiring is appropriate for the settings.
- Carefully run tests for all operating states and potential error situations when commissioning, upgrading or otherwise modifying the operation of the drive.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Default Presets of the Signal Outputs

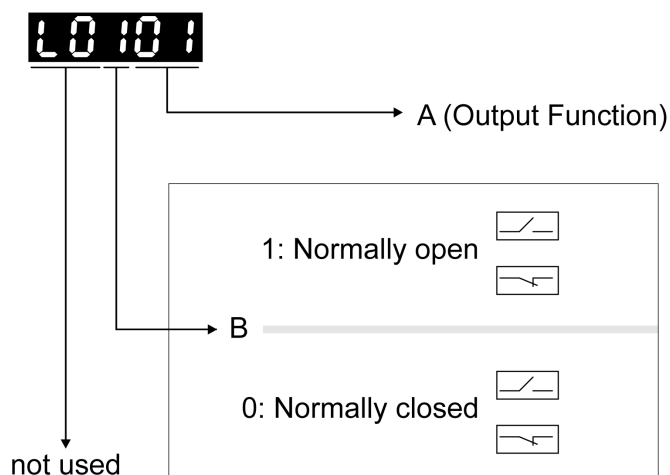
The following table shows the default presets of the digital signal outputs depending on the selected operating mode:

Setting A for P2-18 ... P2-22	Short name	Name	PT	PS	V	T	Vz	Tz	PT V	PT T	PS V	PS T	V T
01 _h	SRDY	Servo Ready	DO1	DO1	DO1	DO1	DO1	DO1	DO1	DO1	DO1	DO1	DO1
02 _h	SON	Servo On	-										
03 _h	ZSPD	Zero Speed	DO2	DO2	DO2	DO2	DO2	DO2	DO2	DO2	DO2	DO2	DO2
04 _h	TSPD	Speed Reached	-		DO3	DO3	DO3	DO3	DO3	DO3	DO3	DO3	DO3
05 _h	TPOS	Movement Completed	DO4	DO4	-				DO4	DO4	DO4	DO4	-
06 _h	TQL	Torque Limit Reached	-										
07 _h	ERROR	Error Detected	DO5	DO5	DO5	DO5	DO5	DO5	DO5	DO5	DO5	DO5	DO5
08 _h	BRKR	Holding Brake Control	-		DO4	DO4	DO4	DO4	-				
09 _h	HOMED _OK	Homing Completed	DO3	DO3	-								
10 _h	OLW	Motor Overload Alert	-										
11 _h	WARN	Alert Signal activated	-										
12 _h	OVF	Position command overflow	-										
13 _h	SCWL (SNL)	Negative Software Limit Switch Reached	-										
14 _h	SCCWL (SPL)	Positive Software Limit Switch Reached	-										
15 _h	CMD_ OK	Data set completed	-										
16 _h	CAP1_ OK	Capture 1 completed	-										
17 _h	MC_OK	Motion control completed output	-										
19 _h	SP_OK	Speed reached output	-										
30 _h	SDO_0	Output the status of bit 0 of P4-06.	-										

Setting A for P2-18 ... P2-22	Short name	Name	PT	PS	V	T	Vz	Tz	PT V	PT T	PS V	PS T	V T
31 _h	SDO_1	Output the status of bit 1 of P4-06.							-				
32 _h	SDO_2	Output the status of bit 2 of P4-06.							-				
33 _h	SDO_3	Output the status of bit 3 of P4-06.							-				
34 _h	SDO_4	Output the status of bit 4 of P4-06.							-				
35 _h	SDO_5	Output the status of bit 5 of P4-06.							-				
36 _h	SDO_6	Output the status of bit 6 of P4-06.							-				
37 _h	SDO_7	Output the status of bit 7 of P4-06.							-				
38 _h ... 3F _h	-	-							-				

Parameterization of the Signal Output Functions

The signal output functions for the outputs DO1 ... DO5 are configured via the parameters P2-18 ... P2-22.



The following table provides an overview of the possible signal output functions:

Setting A for P2-18 ... P2-22	Short name	Name	Description
01 _h	SRDY	Servo Ready	The signal output function SRDY indicates that no errors are detected, i.e., the drive is not in the operating state Fault.
02 _h	SON	Servo On	The signal output function SON indicates that the drive is in the operating state Operation Enabled .
03 _h	ZSPD	Zero Speed	The signal output function ZSPD indicates that the velocity of the motor is less than the velocity value set via parameter P1-38 .
04 _h	TSPD	Speed Reached	The signal output function TSPD indicates that the velocity of the motor is greater than the velocity value set via parameter P1-39 .
05 _h	TPOS	Movement Completed	Operating mode Pulse Train (PT): The signal output function TPOS indicates that the position deviation is within the tolerance set via the parameter P1-54 and the motor has come to a standstill. Operating mode Position Sequence (PS): The signal output function TPOS indicates that the position deviation at the target position is within the tolerance set via the parameter P1-54 and the reference velocity is below the value set via the parameter P1-38.

Setting A for P2-18 ... P2-22	Short name	Name	Description
06 _h	TQL	Torque Limit Reached	The signal output function TQL indicates that the torque of the motor has reached the value set via parameters P1-12 ... P1-14 or an analog input.
07 _h	ERROR	Error Detected	The signal output function ERROR indicates that an error has been detected and that the drive has switched to the operating state Fault. For further information, refer to Diagnostics and Troubleshooting (<i>see page 341</i>).
08 _h	BRKR	Holding Brake Control	The signal output function BRKR is used to control the holding brake with the settings made via parameters P1-42 and P1-19. The holding brake must be connected to the output to which the signal output function BRKR is assigned. For further information, refer to Holding Brake Connection (<i>see page 148</i>).
09 _h	HOME D_OK	Homing Completed	The signal output function HOMED_OK indicates that the homing procedure has been successfully completed. The settings for Homing are specified via parameters P5-04 ... P5-06. For further information, refer to Operating Mode Position Sequence (PS) (<i>see page 296</i>).
10 _h	OLW	Motor Overload Alert	The signal output function OLW indicates a motor overload condition. A threshold for the signal output function OLW can be set via parameter P1-28.
11 _h	WARN	Alert Signal activated	The signal output function indicates that one of the following conditions has been detected: Hardware limit switch triggered, undervoltage, Nodeguard alert, Operational Stop (OPST). For further information, refer to Diagnostics and Troubleshooting (<i>see page 341</i>).
12 _h	-	-	Reserved
13 _h	SCWL (SNL)	Negative Software Limit Switch Reached	The signal output function SCWL(SNL) indicates that the negative software limit switch set via parameter P5-09 has been reached. When the software limit switch is reached, an alert is triggered. The deceleration ramp is specified via parameter P5-23.
14 _h	SCCWL (SPL)	Positive Software Limit Switch Reached	The signal output function SCCWL(SPL) indicates that the positive software limit switch set via parameter P5-08 has been reached. When the software limit switch is reached, an alert is triggered. The deceleration ramp is specified via parameter P5-24.
15 _h	CM- D_OK	Data set completed	The signal output function CMD_OK indicates that the data set including the waiting time has been successfully completed.
16 _h	CAP1_ OK	Capture 1 completed	The signal output function CAP1_OK indicates that a position capture (Touch Probe) has been successfully completed. The settings for position capture (Touch Probe) are specified via parameters P5-37 ... P5-39.
17 _h	MC_OK	Motion control completed output	The signal output function MC_OK indicates that both the signal output functions CMD_OK and TPOS have been activated.
19 _h	SP_OK	Speed reached output	The signal output function SP_OK indicates that the target velocity has been reached. The velocity range for activating this signal output function is set via parameter P1-47.
30 _h	SDO_0	Output the status of bit 0 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.
31 _h	SDO_1	Output the status of bit 1 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.
32 _h	SDO_2	Output the status of bit 2 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.
33 _h	SDO_3	Output the status of bit 3 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.

Setting A for P2-18 ... P2- 22	Short name	Name	Description
34 _h	SDO_4	Output the status of bit 4 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.
35 _h	SDO_5	Output the status of bit 5 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.
36 _h	SDO_6	Output the status of bit 6 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.
37 _h	SDO_7	Output the status of bit 7 of P4-06.	The signal output functions SDO_0 ... SDO_7 provide the bit pattern (bits 0 ... 7) required to determine the setting of the parameter P4-06.

Functions for Target Value Processing

Interrupting a Movement with HALT

The HALT signal input function is available in the operating mode PT only.

With the signal input function HALT, the ongoing movement is interrupted. When the signal input function HALT is no longer active, the movement is resumed from the point where it was interrupted.

The movement is interrupted via a deceleration ramp. The deceleration ramp is specified via parameter P1-68.

In order to interrupt a movement via a signal input, you must first parameterize the signal input function HALT, refer to Setting the Digital Signal Inputs ([see page 270](#)).

NOTE: The pulses received while the HALT function is active are ignored. When the HALT is no longer active, the drive accepts any on-going pulse stream and start movement according to that stream.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Do not deactivate the HALT function prior to the deceleration of the motor.
- If the deactivation of the HALT function prior to the deceleration of the motor is unavoidable, be sure to include these circumstances in your hazard and risk analysis of your application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

If there is uncertainty of the effect of the movement generated by an ongoing pulse stream at the time of HALT deactivation, you must rehome the application.

Stopping a Movement with OPST

With the signal input function OPST (Operational Stop), the ongoing movement is stopped.

In order to stop a movement via a signal input, you must first parameterize the signal input function OPST, refer to Setting the Digital Signal Inputs ([see page 270](#)).

The movement is interrupted via a deceleration ramp to the point of the defined standstill. After that, the power stage is disabled once the drive has determined that the motor is at standstill, and if so configured, the holding brake is applied.

WARNING

UNINTENDED EQUIPMENT OPERATION

- During commissioning, trigger all signals and simulate all conditions that cause a power stage disable request in order to verify that all loads come to a secure standstill when the power stage is disabled under maximum load conditions.
- Install a dedicated service brake if removal of power to the motor does not meet the requirements of your application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

An error, AL013, is detected and presented.

The deceleration ramp is specified via parameter P1-68.

After the OPST function is enabled, you must disable it and re-enable the power stage for continued operation.

Setting a Signal Output Via Parameter

The digital signal outputs can be set via a parameter.

In order to set a digital signal output via the parameter, you must first parameterize the signal output functions SDO_0 ... SDO_7, refer to Setting the Digital Signal Outputs ([see page 276](#)).

The parameter P4-06 lets you set the digital signal outputs.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-06 FOT	Setting a signal output via parameter Applicable operating mode: PT, PS, V, T This parameter lets you set those signal outputs whose signal output functions have been defined by SDO_0 ... SDO_5. Bit 0 = 1 sets those signal outputs whose signal output function has been set to SDO_0. Bit 1 = 1 sets those signal outputs whose signal output function has been set to SDO_1. Bit 2 = 1 sets those signal outputs whose signal output function has been set to SDO_2. Bit 3 = 1 sets those signal outputs whose signal output function has been set to SDO_3. Bit 4 = 1 sets those signal outputs whose signal output function has been set to SDO_4. Bit 5 = 1 sets those signal outputs whose signal output function has been set to SDO_5. Bit 6 = 1 sets those signal outputs whose signal output function has been set to SDO_6. Bit 7 = 1 sets those signal outputs whose signal output function has been set to SDO_7. See P2-18 ... P2-22 for assigning the functions to the digital outputs.	- 0_h 0_h FF_h Hexadecimal	u16 RW -	Modbus 50C _h

Forcing the Digital Signal Inputs and Signal Outputs

Forcing of signals means that the digital inputs and outputs are set manually. Forcing input and output values can have serious consequences on the operation of a machine or process.

WARNING

UNINTENDED EQUIPMENT OPERATION CAUSED BY FORCING

- Only force I/O if there are no persons or obstructions in the zone of operation.
- Only force I/O if you are fully familiar with the effects of the signals.
- Only force I/O for test purposes, maintenance or other short-term tasks.
- Do not use forcing for regular, long-term or in-service operation.
- Always remove forcing when the task (testing, maintenance or other short-term operation) is completed.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Forcing the Digital Inputs

Forcing of the digital inputs is set via the parameters P3-06 and P4-07.

The parameter P3-06 lets you specify which digital signal inputs are allowed to be forced.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P3-06 SDI	Digital Inputs - Forcing Settings Applicable operating mode: PT, PS, V, T This parameter determines whether a digital input can be forced. Bits 0 ... 7: Digital input DI1 ... Digital input DI8 Bit settings: Value 0: Digital input cannot be forced Value 1: Digital input can be forced To start forcing, you must write P4-07. See P2-10 ... P2-17 for the assignment of signal input functions to the digital inputs.	- 0 _h 0 _h 7FF _h Hexadecimal	u16 RW -	Modbus 40C _h

Use parameter P4-07 to activate forcing of the digital signal inputs.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-07 ITST	State of Digital Inputs / Activate Forcing Applicable operating mode: PT, PS, V, T A read access to this parameter indicates the state of the digital inputs in the form of a bit pattern. Example: Read value 0x0011: Digital inputs 1 and 5 are activated By writing this parameter, you can change the state of the inputs provided that the setting for the corresponding input in P3-06 allows for forcing (value 1 for the bit corresponding to the input). Example: Write value 0x0011: Digital inputs 1 and 5 are activated Read value 0x0011: Digital inputs 1 and 5 are activated See P3-06 for permitting forcing of individual digital inputs. See P2-10 ... P2-17 for the assignment of signal input functions to the digital inputs.	- 0 _h 0 _h FF _h Hexadecimal	u16 RW -	Modbus 50E _h

Forcing the Digital Outputs

Forcing of the digital outputs is set via the parameters P4-27 and P4-28.

The parameter P4-27 lets you specify which digital signal outputs are allowed to be forced.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-27 DO_- FORCE_MASK	Digital Outputs - Forcing Settings Applicable operating mode: PT, PS, V, T This parameter determines whether a digital output can be forced. Bits 0 ... 4: Digital output DO1 ... Digital output DO5 Bit settings: Value 0: Digital output cannot be forced Value 1: Digital output can be forced To start forcing, you must write P4-28. See P2-18 ... P2-22 for the assignment of signal output functions to the digital outputs.	- 0 _h 0 _h 1F _h Hexadecimal	u16 RW -	Modbus 536 _h

Use parameter P4-28 to activate forcing of the digital signal outputs.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P4-28 DO_FORCE_VALUE	State of Digital Outputs / Activate Forcing Applicable operating mode: PT, PS, V, T A read access to this parameter indicates the state of the digital outputs in the form of a bit pattern. Example: Read value 0x0011: Digital outputs 1 and 5 are activated By writing this parameter, you can change the state of the outputs provided that the setting for the corresponding output in P4-27 allows for forcing (value 1 for the bit corresponding to the output). Example: Write value 0x0011: Digital outputs 1 and 5 are activated Read value 0x0011: Digital outputs 1 and 5 are activated See P4-27 for permitting forcing of individual digital outputs. See P2-18 ... P2-22 for the assignment of signal output functions to the digital outputs.	- 0 _h 0 _h 1F _h Hexadecimal	u16 RW -	Modbus 538 _h

Chapter 18

Operating Modes

What Is in This Chapter?

This chapter contains the following sections:

Section	Topic	Page
18.1	Setting the Operating Mode	286
18.2	Jog Operation	288
18.3	Operating Mode Pulse Train (PT)	289
18.4	Operating Mode Position Sequence (PS)	296
18.5	Operating Modes Velocity (V) and Velocity Zero (Vz)	330
18.6	Operating Modes Torque (T) and Torque Zero (Tz)	335

Section 18.1

Setting the Operating Mode

Setting the Operating Mode

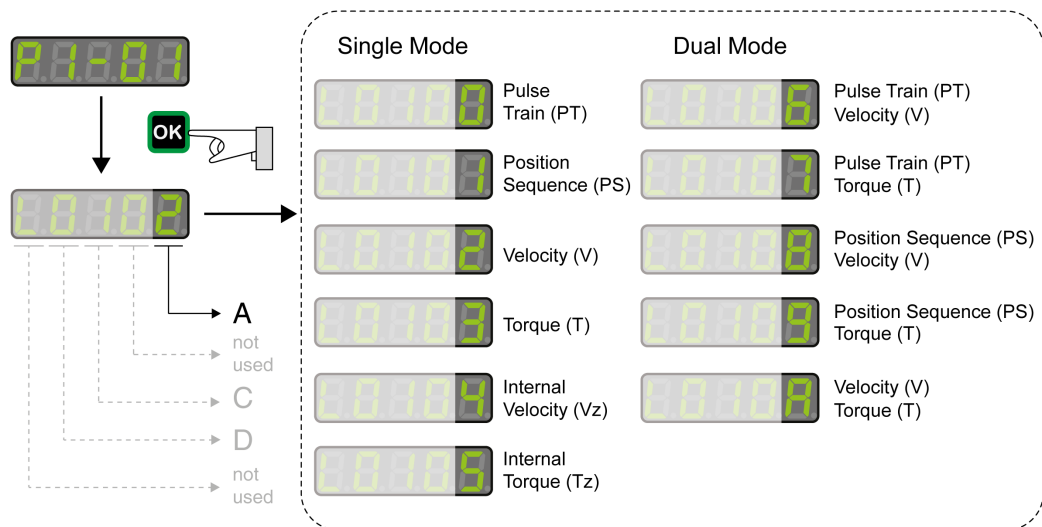
Unsuitable settings or unsuitable data may trigger unintended movements, trigger signals, damage parts and disable monitoring functions. Some parameters and other operational data do not become active until after a restart.

! WARNING

UNINTENDED EQUIPMENT OPERATION

- Only start the system if there are no persons or obstructions in the zone of operation.
- Do not operate the drive system with undetermined parameter values.
- Never modify a parameter value unless you fully understand the parameter and all effects of the modification.
- Restart the drive and verify the saved operational data and/or parameter values after modification.
- Carefully run tests for all operating states and potential error situations when commissioning, upgrading or otherwise modifying the operation of the drive.
- Verify the functions after replacing the product and also after making modifications to the parameter values and/or other operational data.

Failure to follow these instructions can result in death, serious injury, or equipment damage.



The drive has the following types of operating modes:

- **Single Mode** operating modes
 - The drive operates in a single operating mode.
- **Dual Mode** operating modes
 - The drive operates using 2 operating modes alternately. The signal input functions are used to switch between the operating modes.

The operating modes Torque (T) and Torque (Tz) and the dual operating modes with Torque (T) and Torque (Tz) do not provide deceleration functionality in response to a power stage disable request. In these operating modes, the motor coasts down to a standstill in response to a power stage disable request. You must install additional equipment such as a dedicated service brake if your application requires faster deceleration of the load.

 WARNING**UNINTENDED EQUIPMENT OPERATION**

- During commissioning, trigger all signals and simulate all conditions that cause a power stage disable request in order to verify that all loads come to a secure standstill when the power stage is disabled under maximum load conditions.
- Install a dedicated service brake if removal of power to the motor does not meet the requirements of your application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Section 18.2

Jog Operation

Jog Operation

Description

In the Jog operation, a movement is made from the actual motor position in the specified direction.

The parameter $P4-05$ is used to set the velocity for the movement in the unit rpm.

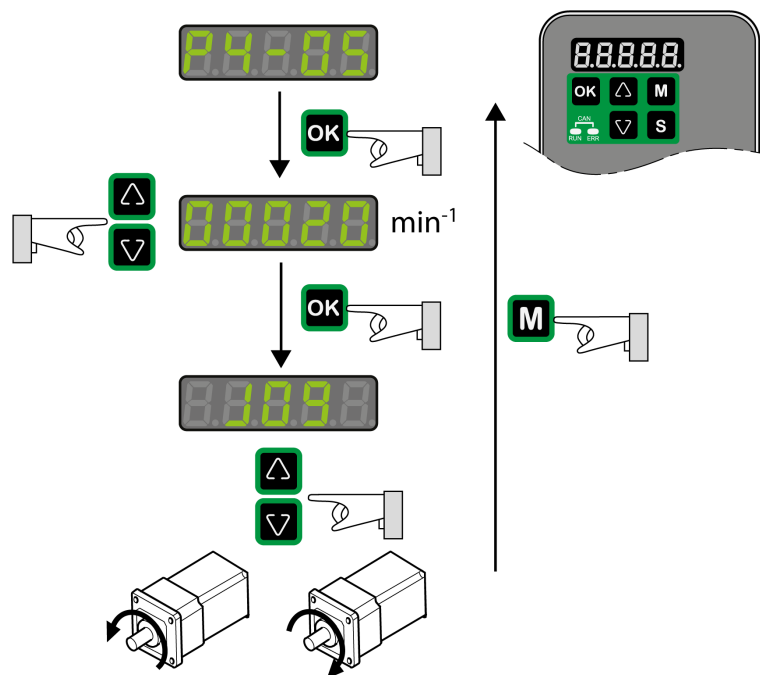
The movement can be performed via the arrow keys at the HMI or via the signal input functions JOGP and JOGN.

For further information on the parameterizable signal input functions, refer to Setting the Digital Signal Inputs ([see page 270](#)).

Jog Via HMI

If the HMI is used, the movements are performed via the arrow keys. The operating mode is terminated via the **M** key.

If the HMI is used, the movements are performed via the arrow keys. The operating mode is terminated via the **M** key.



Section 18.3

Operating Mode Pulse Train (PT)

What Is in This Section?

This section contains the following topics:

Topic	Page
Operating mode Pulse Train (PT)	290
Pulse Settings	291
Gear Ratio	293
Acceleration and Deceleration Limitation	295

Operating mode Pulse Train (PT)

Description

In the operating mode Pulse Train (PT), movements are carried out according to externally supplied reference value signals. A position reference value is calculated on the basis of these external reference values plus an adjustable gear ratio. The reference value signals can be A/B signals, P/D signals or CW/CCW signals.

Method

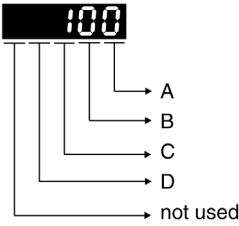
A movement can be made using one of 3 methods:

- Position synchronization without compensation movement
In the case of position synchronization without compensation movement, the movement is made synchronously (position synchronicity) with the supplied reference value signals. Reference value signals supplied during an interruption are not taken into account.
- Position synchronization with compensation movement
In the case of position synchronization with compensation movement, the movement is made synchronously (position synchronicity) with the supplied reference value signals. Reference value signals supplied during an interruption are taken into account and compensated for.
- Velocity synchronization
In the case of velocity synchronization, the movement is made synchronously (velocity synchronicity) with the supplied reference value signals.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P8-31 GEARING_MODE	Method for Operating Mode Pulse Train (PT) Applicable operating mode: PT Value 0: Synchronization deactivated Value 1: Position synchronization without compensation movement Value 2: Position synchronization with compensation movement Value 3: Velocity synchronization The parameters for acceleration (P1-34), deceleration (P1-35) and velocity (P1-55) act as limitations for the synchronization.	- 0 1 3 Decimal	u16 RW per.	Modbus 93E _n

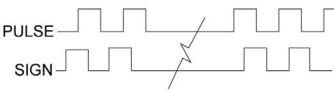
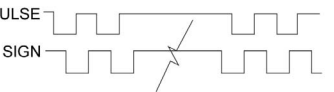
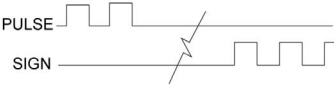
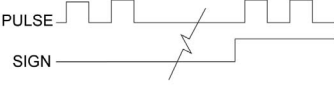
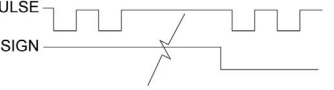
Pulse Settings

The parameter P1-00 lets you specify the type of reference value signals, the input polarity, the maximum signal frequency and the source of the pulses.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-00 PTT	Reference Value Signal - Pulse Settings Applicable operating mode: PT  This parameter is used to configure the reference value signals for the operating mode PT. A: Type of reference value signals B: Signal frequency C: Input polarity D: Source of reference value signals Setting can only be changed if power stage is disabled.	- 0 _h 2 _h 1132 _h Hexadecimal	u16 RW per.	Modbus 200 _h

Settings A and C

Type of reference value signals and input polarity

-	C = 0 Positive input polarity		C = 1 Negative input polarity	
	Positive direction of movement	Negative direction of movement	Positive direction of movement	Negative direction of movement
A = 0 A/B signals				
A = 1 CW/CCW signals				
A = 2 P/D signals				

Setting B

Maximum signal frequency:

–	Low-speed pulses PULSE, SIGN	High-speed pulses HPULSE, HSIGN
B = 0	500 Kpps ⁽¹⁾	4 Mpps
B = 1	200 Kpps	2 Mpps
B = 2	100 Kpps	1 Mpps
B = 3	50 Kpps	500 Kpps
(1) Only possible with RS422.		

Parameter **P2-65** bit 6 allows you to set an error response for frequencies exceeding the maximum signal frequency by more than 10 %.

Setting D

Source of the pulses:

D = 0	Low-speed pulses	CN1 Terminal: PULSE, SIGN
D = 1	High-speed pulses	CN1 Terminal: HPULSE, HSIGN

The source of the pulses can also be set via the signal input function PTCMS. The settings of the signal input function take priority over the settings of the parameter **P1-00**.

Gear Ratio

The gear ratio is the ratio of the number of motor increments and the number of reference increments. The reference increments are supplied as reference value signals via the signal inputs.

$$\text{Gear factor} = \frac{\text{Motor increments}}{\text{Reference increments}} = \frac{\text{Gear factor numerator}}{\text{Gear factor denominator}}$$

With the factory setting for the gear ratio, 100000 reference increments correspond to one revolution. There are 1280000 motor increments per revolution.

Parameterization

You can set up 4 gear ratios. It is possible to switch between these gear ratios via the signal inputs.

The gear ratios are set via parameters P1-44, P1-45, P2-60, P2-61, and P2-62.

You can switch between the gear ratios with the signal input functions GNUM0 and GNUM1.

GNUM1	GNUM0	=
0	0	$\frac{P1-44}{P1-45}$
0	1	$\frac{P2-60}{P1-45}$
1	0	$\frac{P2-61}{P1-45}$
1	1	$\frac{P2-62}{P1-45}$

In order to switch between the gear ratios via the signal inputs, you must first parameterize the signal input functions GNUM0 and GNUM1, refer to Setting the Digital Signal Inputs ([see page 270](#)).

Example 1

Calculation of number of motor revolutions corresponding to 30000 PUU:

$$30000 \text{ PUU} \times \frac{P1-44 = 128}{P1-45 = 10} = 384000 \rightarrow \frac{384000}{1280000} = 0,3 \quad \text{(M)}$$

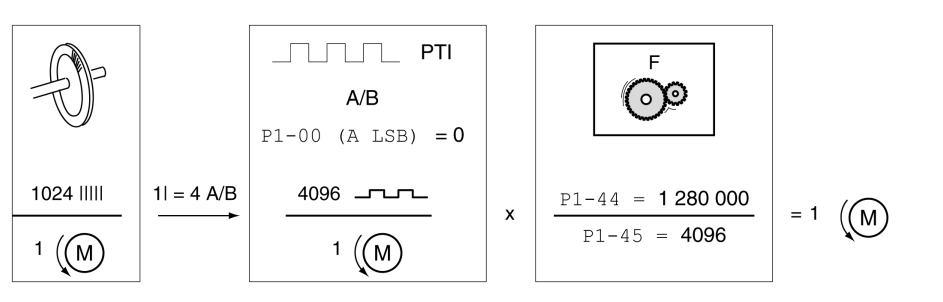
Example 2

Calculation of gear ratio if 10000 PUU are to effect 500 revolutions of the motor shaft:

$$\begin{aligned}
 10000 \text{ PUU} &= 500 \quad \text{(M)} \rightarrow \frac{P1-44 = ?}{P1-45 = ?} \\
 \frac{1280000}{1 \quad \text{(M)}} &\rightarrow \frac{\cancel{1280000} \times 500}{1 \quad \text{(M)} \times \cancel{10000}} = \frac{128 \times 500}{\text{(M)} \times 1} \\
 &\rightarrow \frac{P1-44 = 128 \times 500}{P1-45 = 1}
 \end{aligned}$$

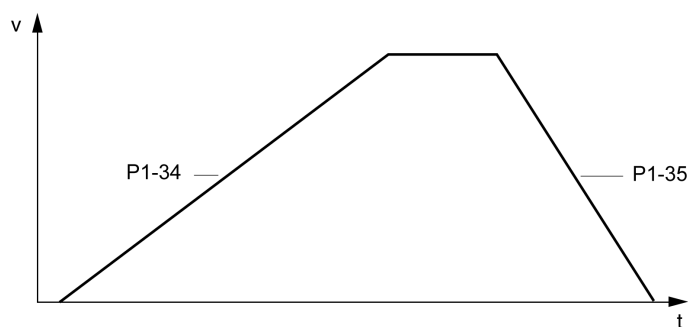
Example 3

A machine encoder with 1024 lines per revolution is to effect one revolution of the motor shaft with one revolution.



Acceleration and Deceleration Limitation

The parameters P1-34 and P1-35 allow you to set a limitation for the acceleration and deceleration.



Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-34 TACC	Acceleration Period Applicable operating mode: PT, V The acceleration period is the time in milliseconds required to accelerate from motor standstill to 6000 rpm. For operating mode V, this parameter specifies the acceleration. For operating mode PT, this parameter specifies an acceleration limitation for the pulses at the PTI interface.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 244 _h
P1-35 TDEC	Deceleration Period Applicable operating mode: PT, V The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. For operating mode V, this parameter specifies the deceleration. For operating mode PT, this parameter specifies a deceleration limitation for the pulses at the PTI interface.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 246 _h

Section 18.4

Operating Mode Position Sequence (PS)

What Is in This Section?

This section contains the following topics:

Topic	Page
Operating mode Position Sequence (PS)	297
Structure of a Data Set	298
Scaling	300
Homing Data Set for Absolute Movements	301

Operating mode Position Sequence (PS)

Description

The operating mode Position Sequence (PS) allows you to set and execute 32 motion profiles in any sequence. The motion profiles are defined via 32 data sets.

The following values can be set for each data set:

- Target position
- Type of movement: Absolute or relative
- Type of transition between data sets
- Acceleration
- Target velocity
- Deceleration
- Waiting time after completion of the data set

In addition, a Homing data set is provided. This Homing data set is used to set a reference point for absolute movements.

Configuration

The data sets are configured by means of the commissioning software LXM26 DTM Library.

Structure of a Data Set

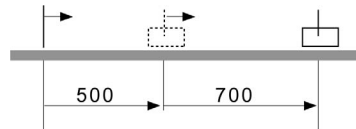
Target Position

The target position is set in the user-defined unit. With the factory scaling, the resolution is 100000 user-defined units per revolution.

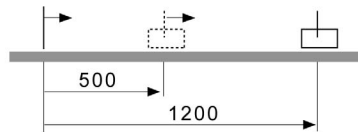
For further information on scaling, refer to chapter Scaling (*see page 300*).

Type of Movement

In the case of a relative movement, the movement is relative with reference to the previous target position or the current motor position.



In the case of an absolute movement, the movement is absolute with reference to the zero point.



Homing or position setting is required before the first absolute movement can be performed.

Transition Between Data Sets

There are two types of transitions:

- The subsequent data set is only started after the preceding data set has been completed.
- The subsequent data set is started as soon as it is triggered via the signal input function CTRG or the parameter P5-07.

Acceleration Period

The acceleration period is the time in milliseconds required to accelerate from motor standstill to 6000 rpm. It is used to set the acceleration ramp.

Target Velocity

The target velocity is reached after the time required for acceleration has passed.

Deceleration Period

The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. It is used to set the deceleration ramp.

Waiting Time

The waiting time is the period of time that must pass after the target position has been reached for the data set to be considered completed.

Parameters for the Data Sets

The data set are configured via parameters P6-02 ... P6-65 and P7-02 ... P7-65. The following table provides an overview:

Data set	Target position	Type / transition	Acceleration / deceleration	Waiting time / target velocity
1	P6-02	P6-03	P7-02	P7-03
2	P6-04	P6-05	P7-04	P7-05
3	P6-06	P6-07	P7-06	P7-07
4	P6-08	P6-09	P7-08	P7-09
5	P6-10	P6-11	P7-10	P7-11
6	P6-12	P6-13	P7-12	P7-13
7	P6-14	P6-15	P7-14	P7-15
8	P6-16	P6-17	P7-16	P7-17
9	P6-18	P6-19	P7-18	P7-19
10	P6-20	P6-21	P7-20	P7-21
11	P6-22	P6-23	P7-22	P7-23
12	P6-24	P6-25	P7-24	P7-25
13	P6-26	P6-27	P7-26	P7-27
14	P6-28	P6-29	P7-28	P7-29
15	P6-30	P6-31	P7-30	P7-31
16	P6-32	P6-33	P7-32	P7-33
17	P6-34	P6-35	P7-34	P7-35
18	P6-36	P6-37	P7-36	P7-37
19	P6-38	P6-39	P7-38	P7-39
20	P6-40	P6-41	P7-40	P7-41
21	P6-42	P6-43	P7-42	P7-43
22	P6-44	P6-45	P7-44	P7-45
23	P6-46	P6-47	P7-46	P7-47
24	P6-48	P6-49	P7-48	P7-49
25	P6-50	P6-51	P7-50	P7-51
26	P6-52	P6-53	P7-52	P7-53
27	P6-54	P6-55	P7-54	P7-55
28	P6-56	P6-57	P7-56	P7-57
29	P6-58	P6-59	P7-58	P7-59
30	P6-60	P6-61	P7-60	P7-61
31	P6-62	P6-63	P7-62	P7-63
32	P6-64	P6-65	P7-64	P7-65

Scaling

Scaling is the ratio of the number of user-defined units and the number of internal units.

The user-defined units are supplied as parameter values in the unit PUU.

$$\text{Scaling factor} = \frac{\text{Internal units}}{\text{User-defined units}} = \frac{\text{Gear factor numerator}}{\text{Gear factor denominator}}$$

With the factory setting for the scaling factor, 100000 user-defined units correspond to one revolution.

The internal units are 1280000 increments per revolution.

Parameterization

The scaling factor is set using the parameters P1-44 and P1-45.

$$\frac{P1-44}{P1-45}$$

Example 1

Calculation of number of motor revolutions corresponding to 30000 PUU:

$$30000 \text{ PUU} \times \frac{P1-44 = 128}{P1-45 = 10} = 384000 \rightarrow \frac{384000}{1280000} = 0,3 \text{ (M)}$$

Example 2

Calculation of the scaling factor if 10000 PUU are to effect 500 revolutions of the motor shaft:

$$\begin{aligned} 10000 \text{ PUU} &= 500 \text{ (M)} \rightarrow \frac{P1-44 = ?}{P1-45 = ?} \\ \frac{1280000}{1 \text{ (M)}} &\rightarrow \frac{\cancel{1280000} \times 500}{1 \text{ (M)} \times \cancel{10000}} = \frac{128 \times 500}{\text{(M)} \times 1} \\ &\rightarrow \frac{P1-44 = 128 \times 500}{P1-45 = 1} \end{aligned}$$

Homing Data Set for Absolute Movements

The Homing data set is used to establish a reference between a mechanical position and the actual position of the motor.

A reference between a mechanical position and the actual position of the motor is generated by means of a reference movement or by means of position setting.

A successful reference movement, or position setting, homes the motor.

Homing establishes the zero point for absolute movements.

Methods

The following methods are available:

- Reference movement to a limit switch

In the case of a reference movement to a limit switch, a movement to the negative limit switch or the positive limit switch is performed.

When the limit switch is reached, the motor is stopped and a movement is made back to the switching point of the limit switch.

From the switching point of the limit switch, an additional movement can be made to the next index pulse of the motor.

The switching point of the limit switch or the position of the index pulse point is the reference point.
- Reference movement to the reference switch

In the case of a reference movement to the reference switch, a movement to the reference switch is performed.

When the reference switch is reached, the motor is stopped and a movement is made back to the switching point of the reference switch.

From the switching point of the reference switch, an additional movement can be made to the next index pulse of the motor.

The switching point of the reference switch or the position of the index pulse point is the reference point.
- Reference movement to the index pulse

In the case of a reference movement to the index pulse, a movement is made from the actual position to the next index pulse. The position of the index pulse is the reference point.
- Position setting

In the case of position setting, the current motor position is set to a desired position value.

A reference movement must be terminated without interruption for the new zero point to be valid. If the reference movement is interrupted, it must be started again.

Starting the Homing Data Set

The Homing data set can be started in the following ways:

- Automatic start when the power stage is enabled for the first time

The automatic start can be set with the parameter P6-01.
- Start via the signal input function GOTOHOME

The signal input function must have been parameterized, refer to Setting the Digital Signal Inputs (*see page 270*).

Setting Automatic Start and the Subsequent Data Set

The parameter P6-01 is used to set the automatic start and select a data set to be executed after completion of the Homing data set.

The parameter P7-01 is used to set a waiting time for the subsequent data set. The subsequent data set is started after the waiting time has elapsed.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-01 ODEF	Subsequent Data Set and Auto-start of Homing Data Set Applicable operating mode: PS Bit 0: 0 = Do not start Homing after first power stage enable 1 = Start Homing after first power stage enable Bits 1 ... 7: Reserved Bits 8 ... 15: Subsequent data set	- 0 _h 0 _h 2001 _h Hexadecimal	u32 RW per.	Modbus 702 _h
P7-01 HOME_DLY	Waiting Time of Homing Data Set Applicable operating mode: PS Bits 0 ... 15: Waiting time until next dataset is started Bits 16 ... 31: Reserved	ms 0 0 32767 Decimal	u32 RW per.	Modbus 802 _h

Setting Acceleration and Deceleration

The acceleration and deceleration for the Homing data set are set via the parameter P7-00.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P7-00 HOME_ACC_DEC	Deceleration and Acceleration of Homing Data Set Applicable operating mode: PS Bits 0 ... 15: Deceleration Bits 16 ... 31: Acceleration	ms ms 6 6 200 200 65500 65500 Decimal	u32 RW per.	Modbus 800 _h

Setting Velocities

The parameters P5-05 and P5-06 are used to set the velocities for searching the switch and for moving away from the switch.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P5-05 HOMESPEED1	Homing - Fast Velocity for Reference Movement Applicable operating mode: PS	0.1rpm 10 1000 60000 Decimal	u32 RW per.	Modbus 60 A _h
P5-06 HOMESPEED2	Homing - Slow Velocity for Reference Movement Applicable operating mode: PS	0.1rpm 10 200 60000 Decimal	u32 RW per.	Modbus 60 C _h

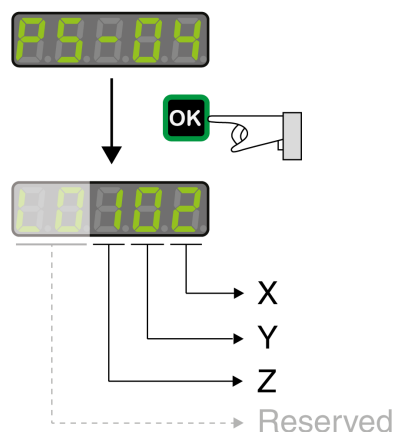
Defining the Zero Point

The parameter P6-00 is used to specify a position value, which is set at the reference point after a successful reference movement or after position setting. This position value defines the zero point.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-00 ODAT	Position of Homing Data Set Applicable operating mode: PS After a successful reference movement, this position is automatically set at the reference point. Bits 0 ... 31: Position	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 700 _h

Selecting the Homing Method

The parameter P5-04 is used to set the Homing method.



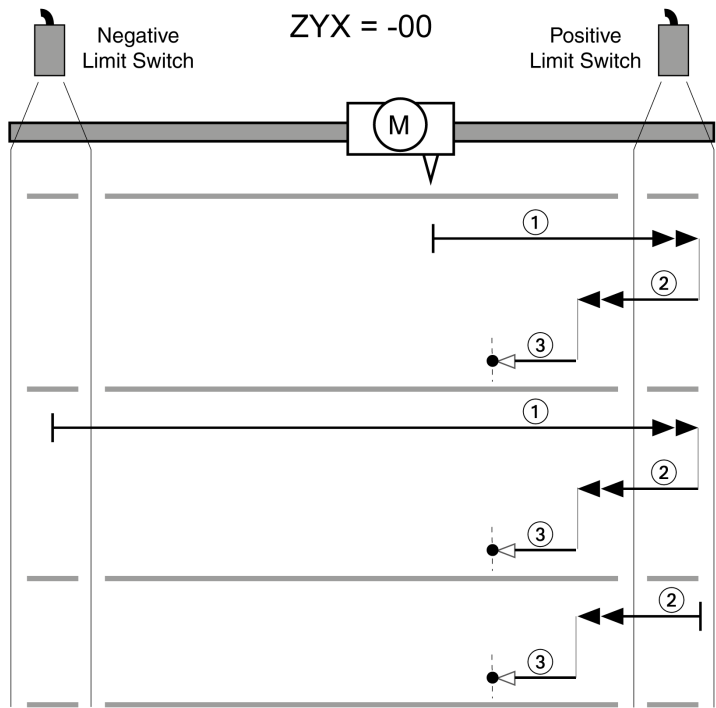
Setting Z - limit switch	Setting Y - index pulse	Settings X - Homing method	
-	Y=0: Movement back to the last index pulse	0	Movement in positive direction to the positive limit switch
-	Y=2: No movement to the index pulse	1	Movement in negative direction to the negative limit switch
Z=0: Stop after limit switch is reached and trigger alert AL014 or AL015 Z=1: Move in opposite direction after having reached the limit switch, no alert	Y=0: Movement back to the last index pulse	2	Movement in positive direction to the rising edge of the reference switch
	Y=1: Movement to the next index pulse	3	Movement in negative direction to the rising edge of the reference switch
	Y=2: No movement to the index pulse		
	-	4	Movement in positive direction to the next index pulse
	-	5	Movement in negative direction to the next index pulse
	Y=0: Movement back to the last index pulse	6	Movement in positive direction to the falling edge of the reference switch
	Y=1: Movement to the next index pulse	7	Movement in negative direction to the falling edge of the reference switch
	Y=2: No movement to the index pulse		
-	-	8	Position setting

The illustrations below show the Homing methods.

Reference Movement to the Positive Limit Switch

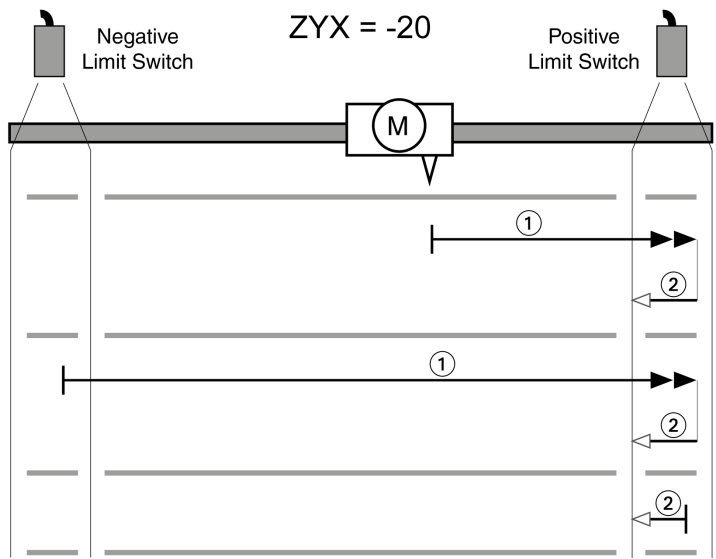
The following illustrations show reference movements to the positive limit switch from different starting positions.

Reference movement (ZYX = -00)



Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06

Reference movement (ZYX = -20)

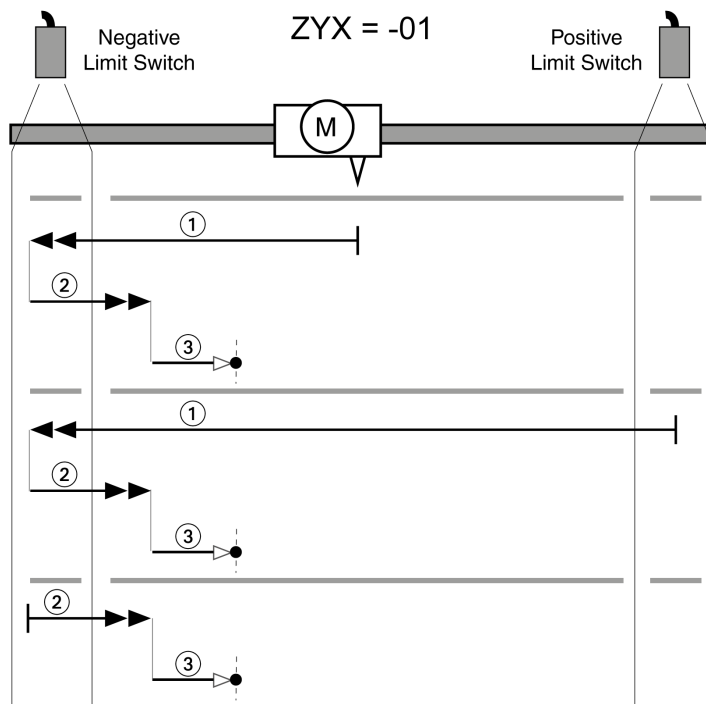


Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06

Reference Movement to the Negative Limit Switch

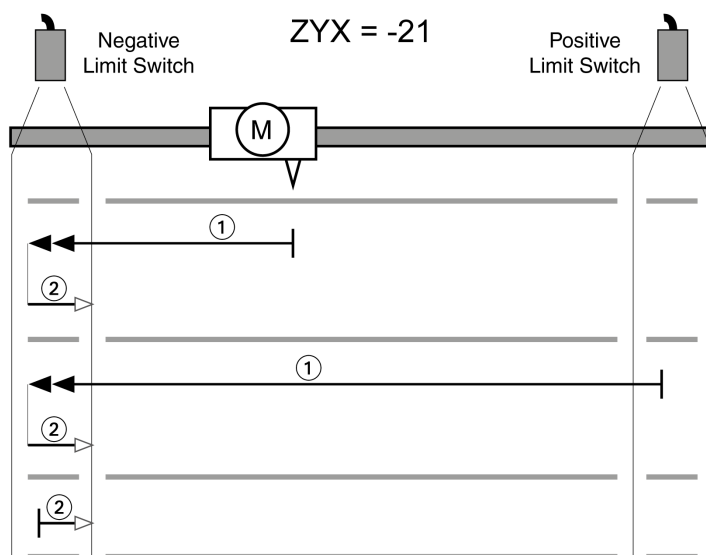
The following illustrations show reference movements to the negative limit switch from different starting positions.

Reference movement (ZYX = -01)



Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06

Reference movement (ZYX = -21)

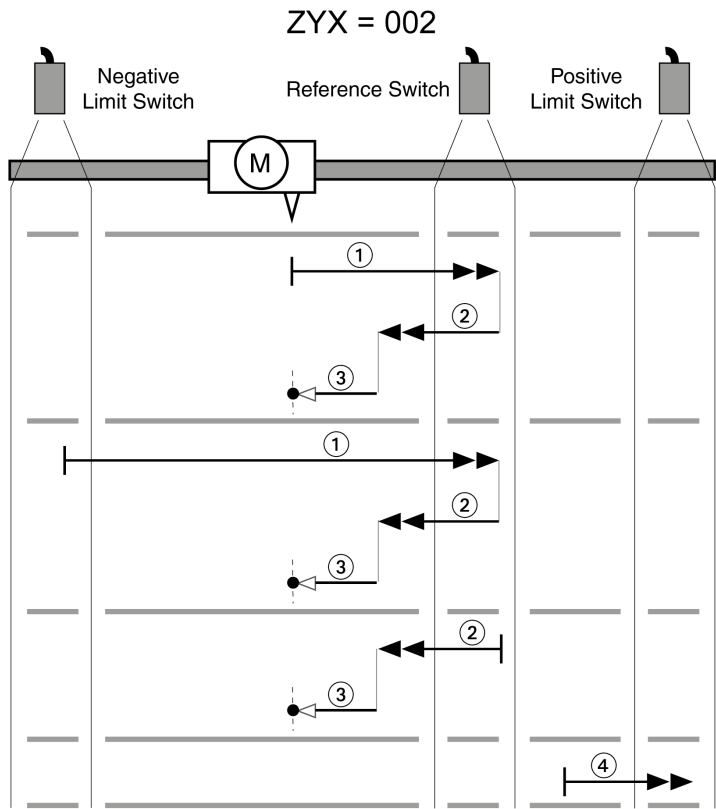


Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06

Reference Movement in Positive Direction to the Rising Edge of the Reference Switch

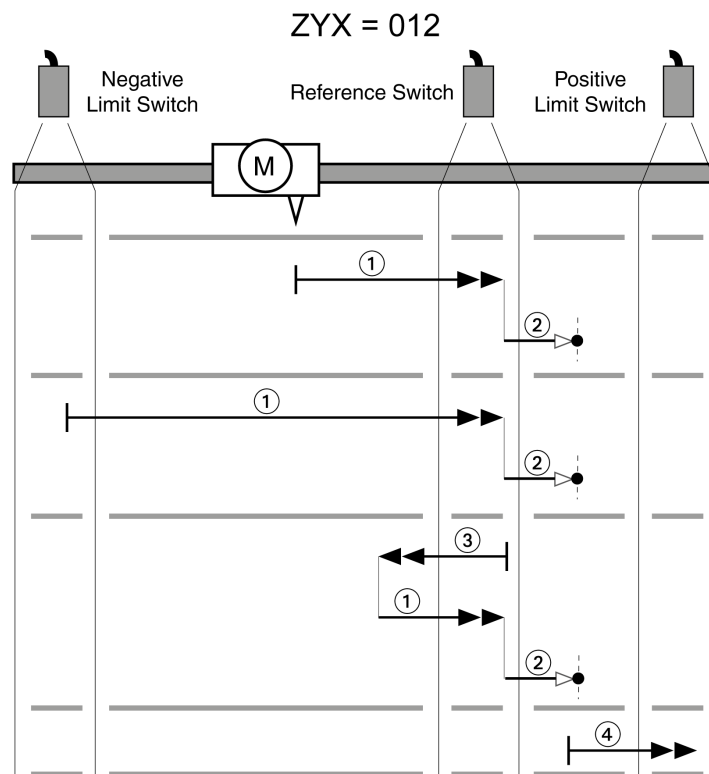
The following illustrations show reference movements to the rising edge of the reference switch in positive direction from different starting positions.

Reference movement (ZYX = 002)



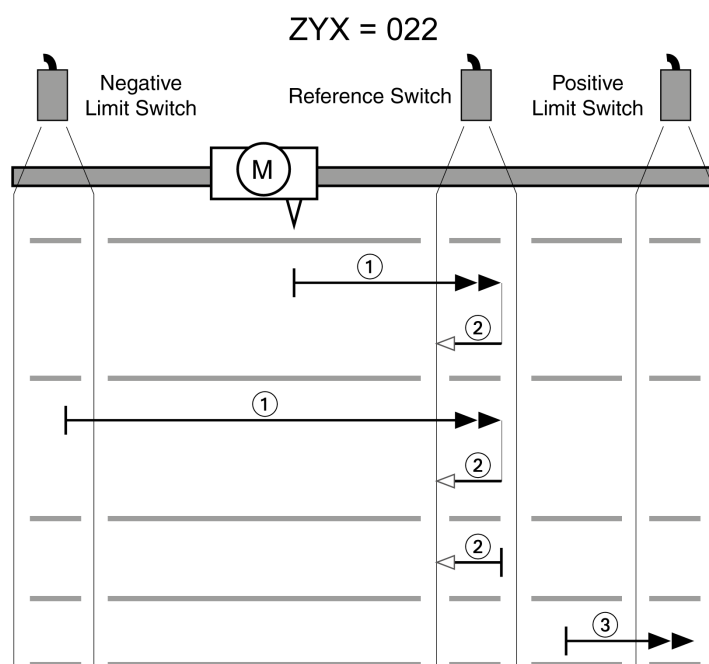
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 012)



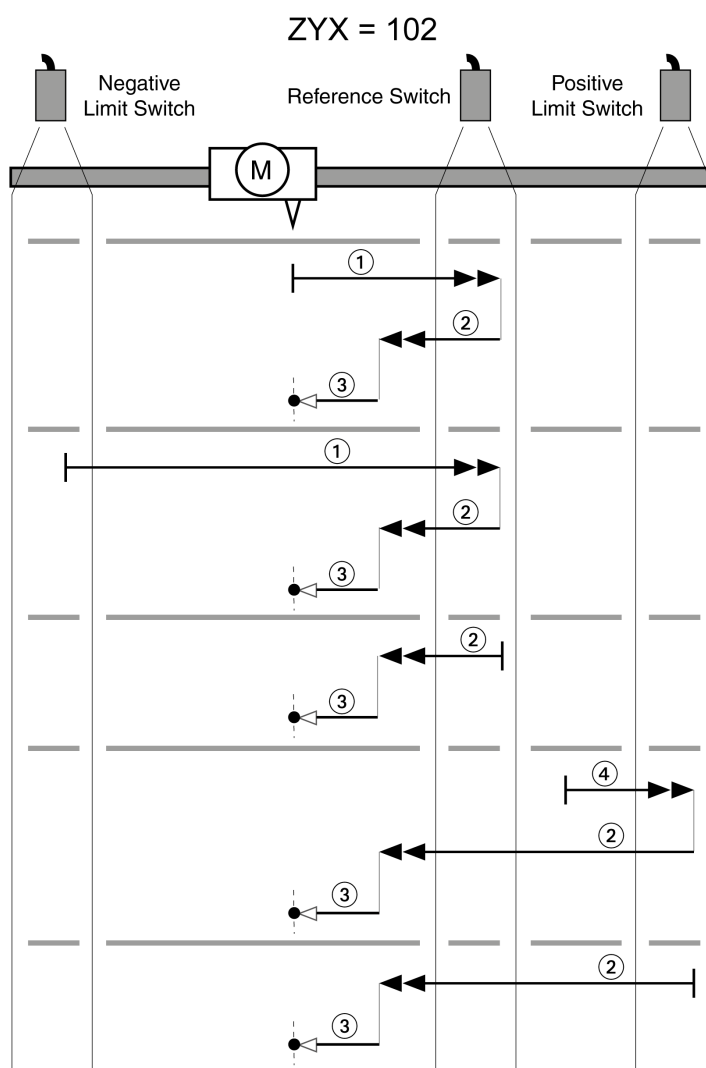
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to falling edge at velocity P5-05
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 022)



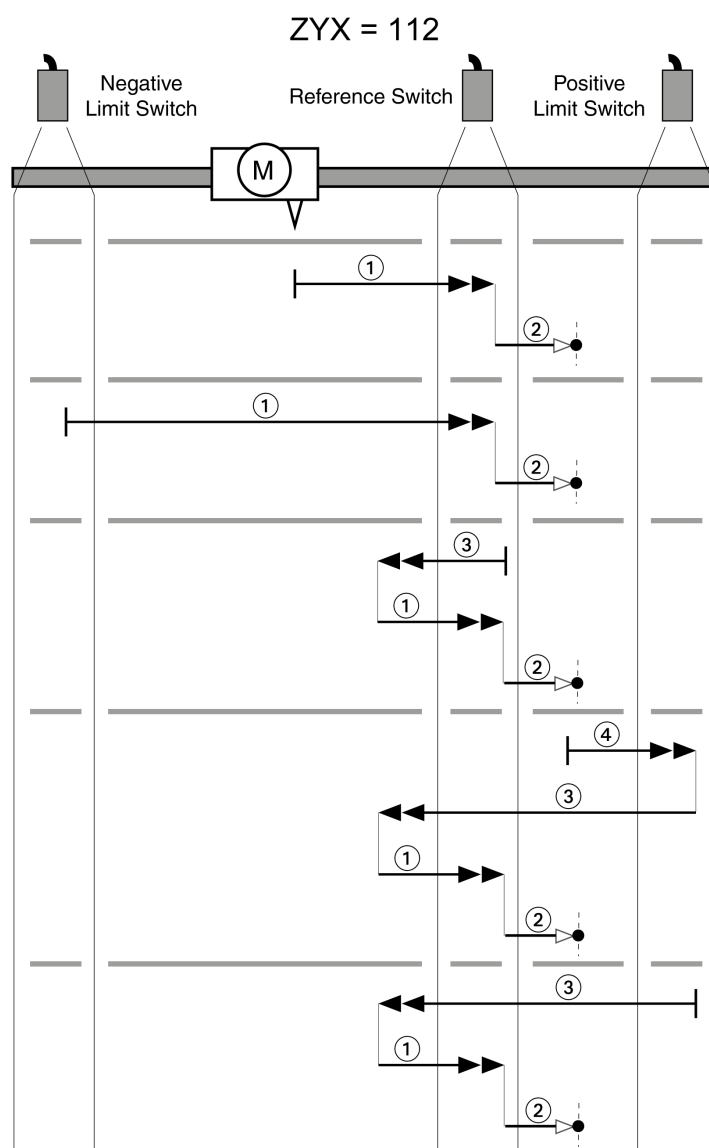
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 102)



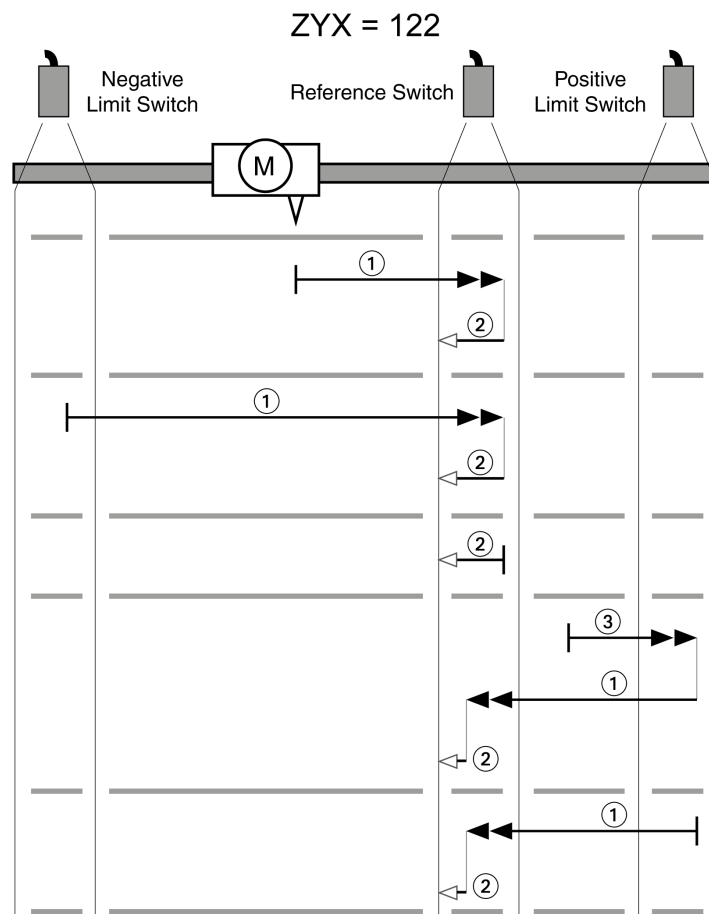
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 112)



Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to falling edge at velocity P5-05
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 122)

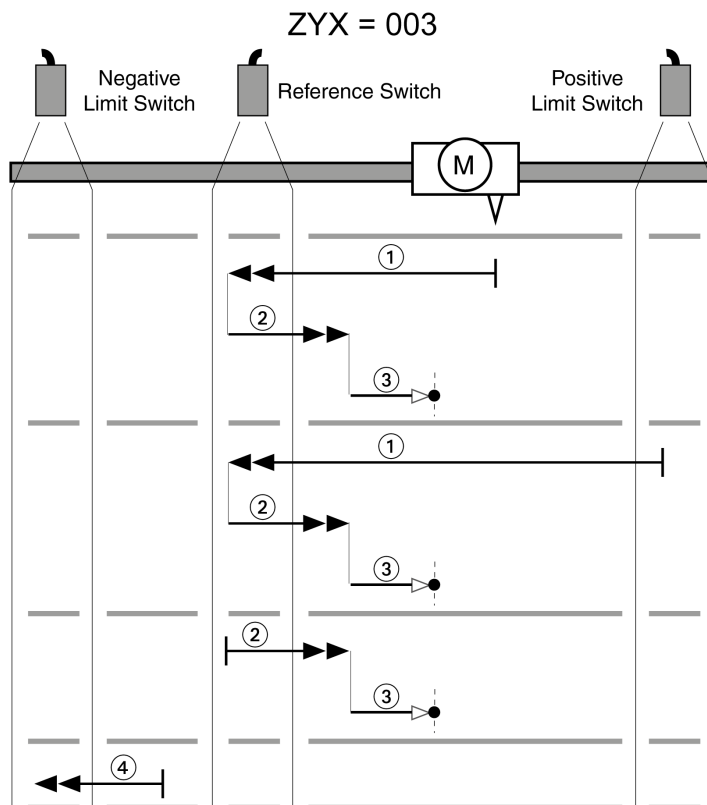


Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference Movement in Negative Direction to the Rising Edge of the Reference Switch

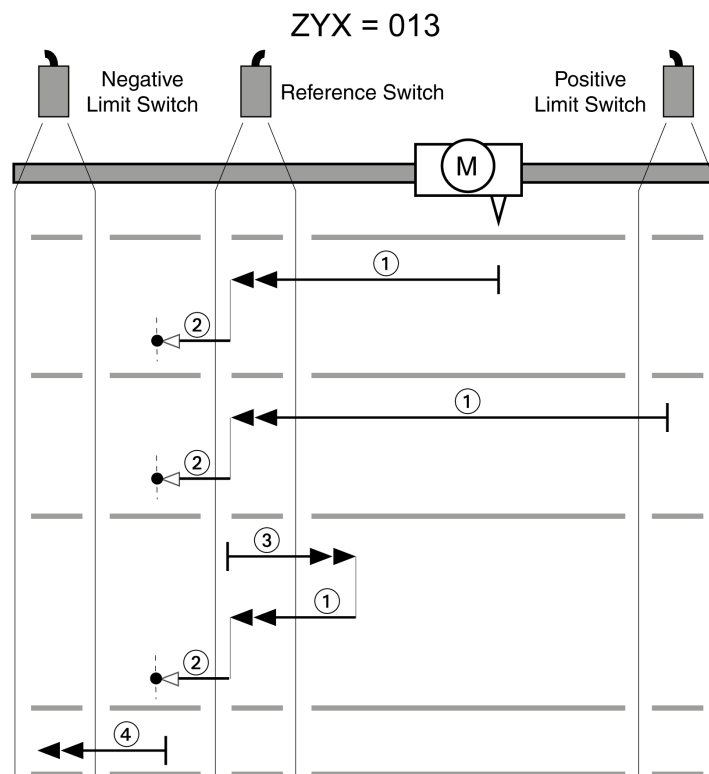
The following illustrations show reference movements to the rising edge of the reference switch in negative direction from different starting positions.

Reference movement (ZYX = 003)



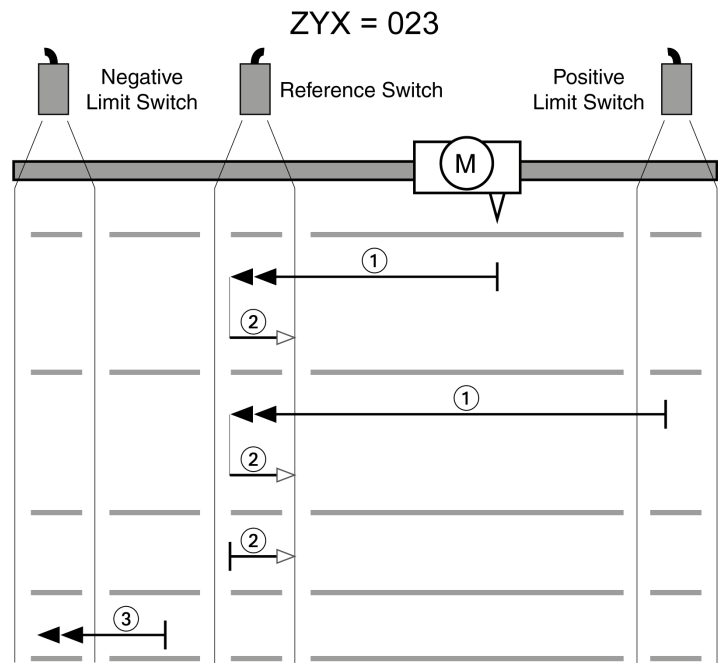
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 013)



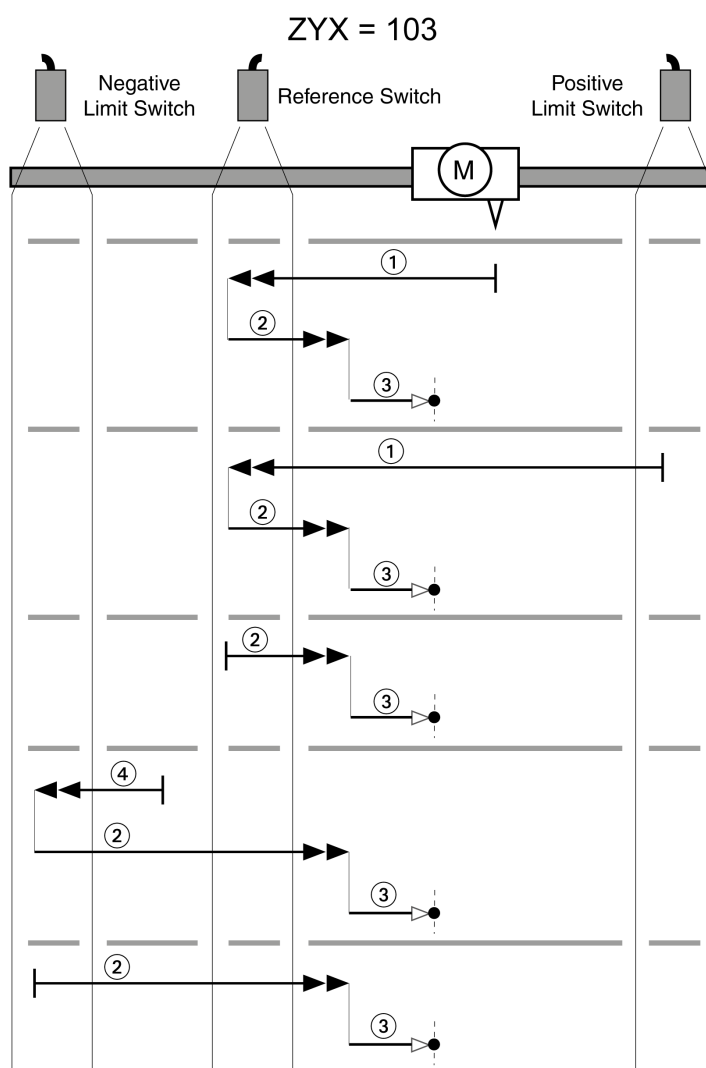
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to falling edge at velocity P5-05
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 023)



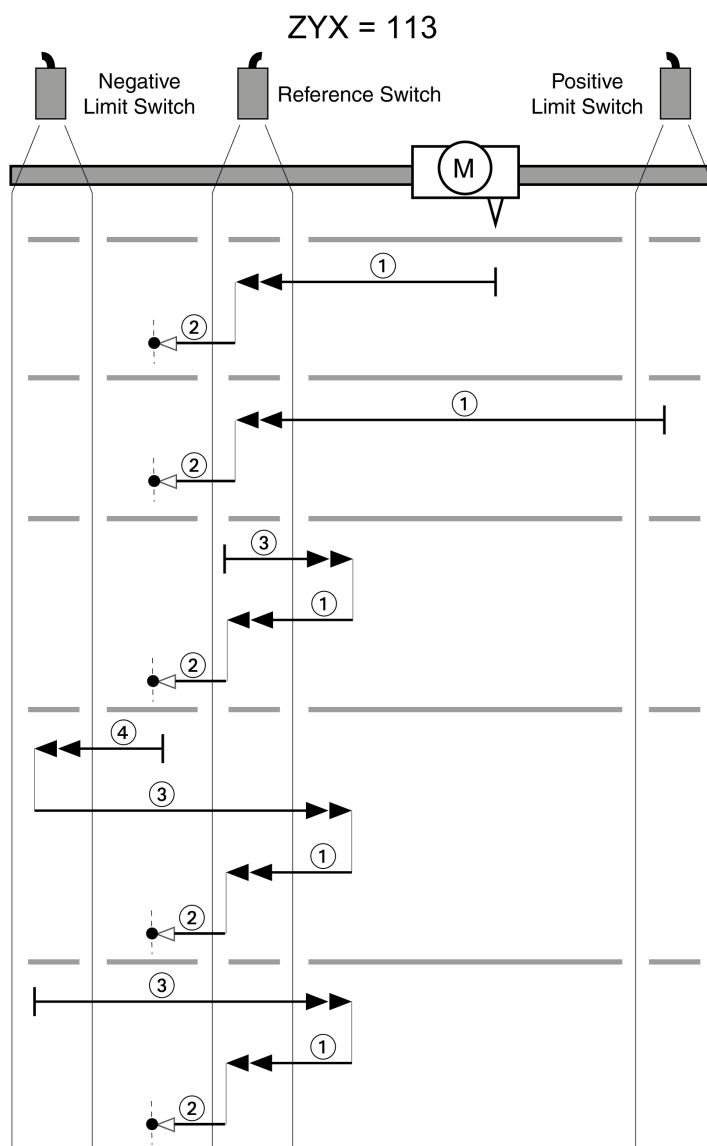
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 103)



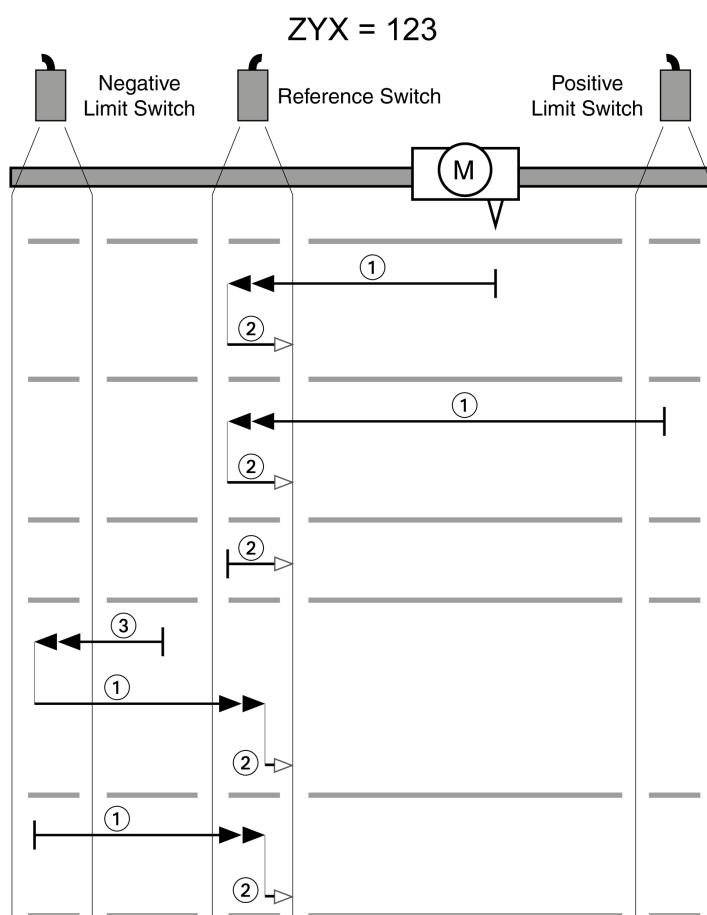
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 113)



Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to falling edge at velocity P5-05
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 123)

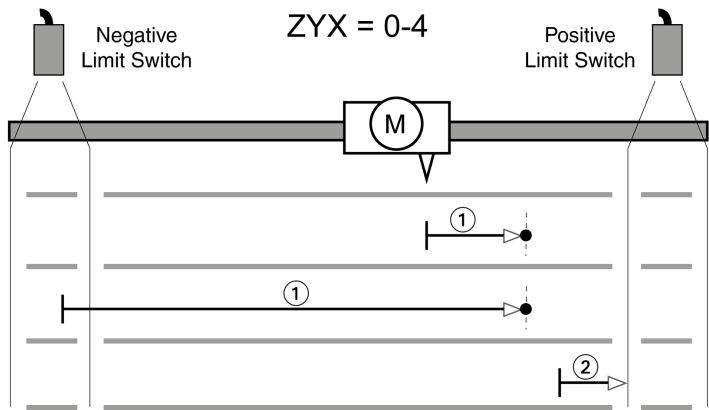


Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference Movement to the Index Pulse in Positive Direction

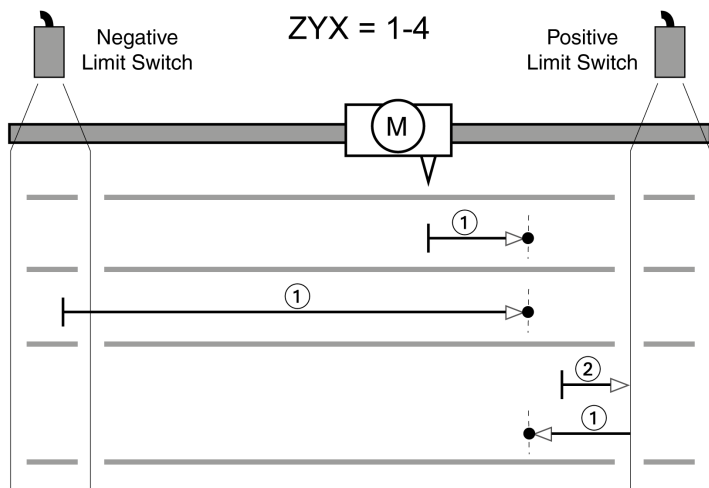
The following illustrations show reference movements to the index pulse in positive direction from different starting positions.

Reference movement (ZYX = 0-4)



Item	Description
1	Movement to the next index pulse at velocity P5-06
2	Movement to the limit switch at velocity P5-06

Reference movement (ZYX = 1-4)

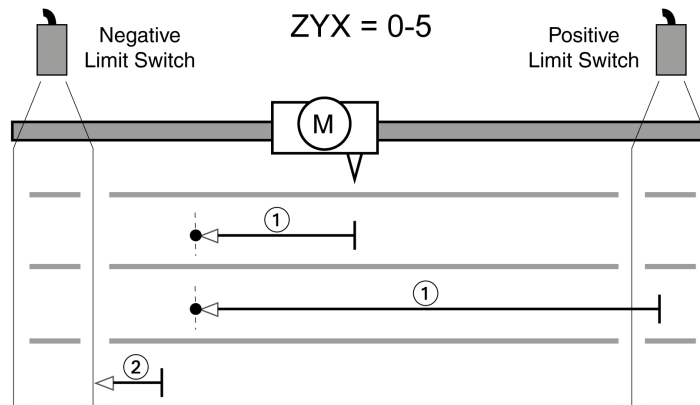


Item	Description
1	Movement to the next index pulse at velocity P5-06
2	Movement to the limit switch at velocity P5-06

Reference Movement to the Index Pulse in Negative Direction

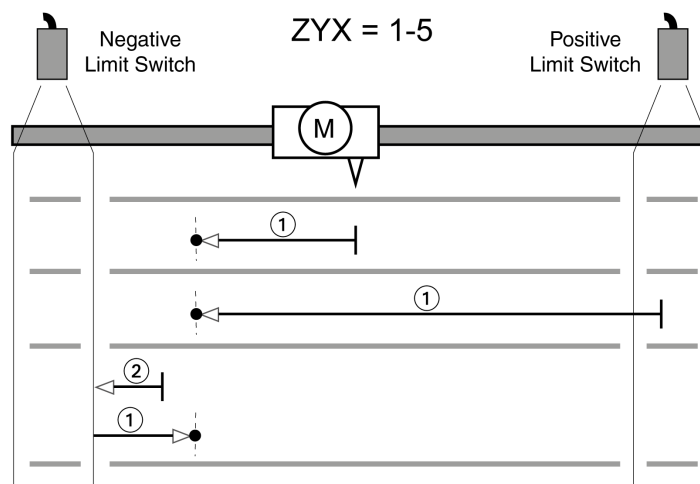
The following illustrations show reference movements to the index pulse in negative direction from different starting positions.

Reference movement (ZYX = 0-5)



Item	Description
1	Movement to the next index pulse at velocity P5-06
2	Movement to the limit switch at velocity P5-06

Reference movement (ZYX = 1-5)

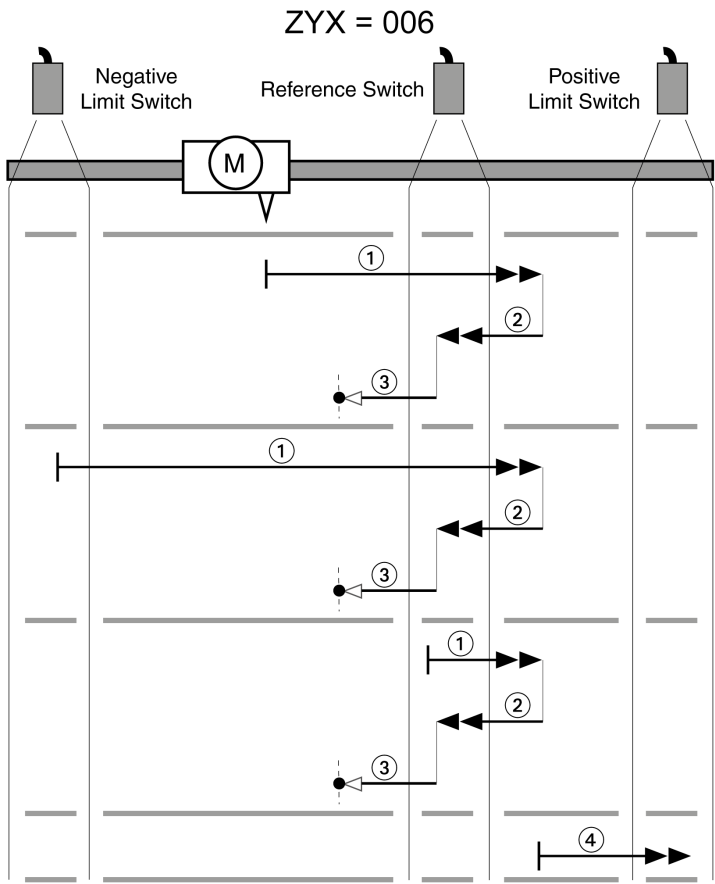


Item	Description
1	Movement to the next index pulse at velocity P5-06
2	Movement to the limit switch at velocity P5-06

Reference Movement in Positive Direction to the Falling Edge of the Reference Switch

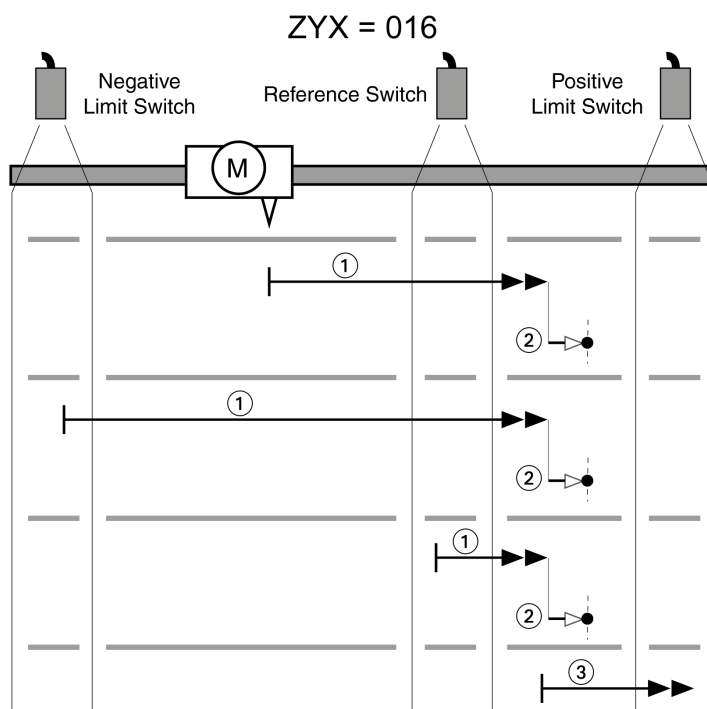
The following illustrations show reference movements to the falling edge of the reference switch in positive direction from different starting positions.

Reference movement (ZYX = 006)



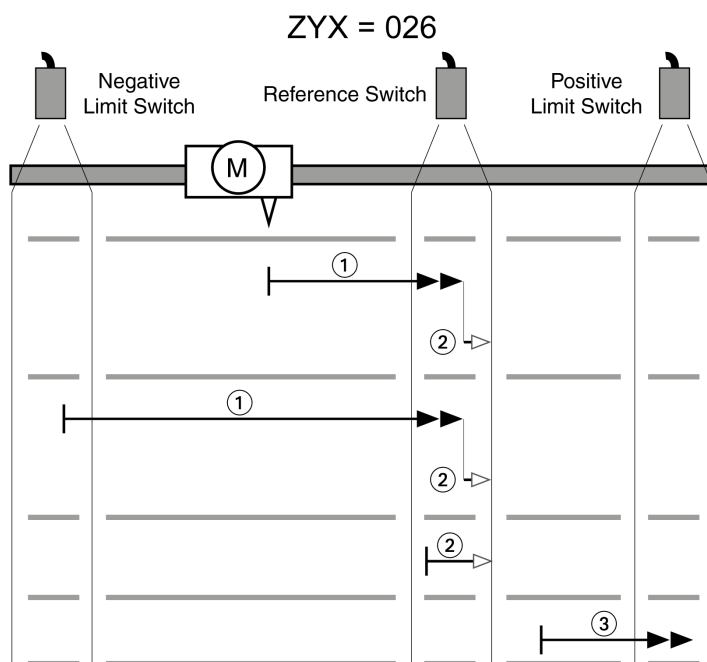
Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to rising edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 016)



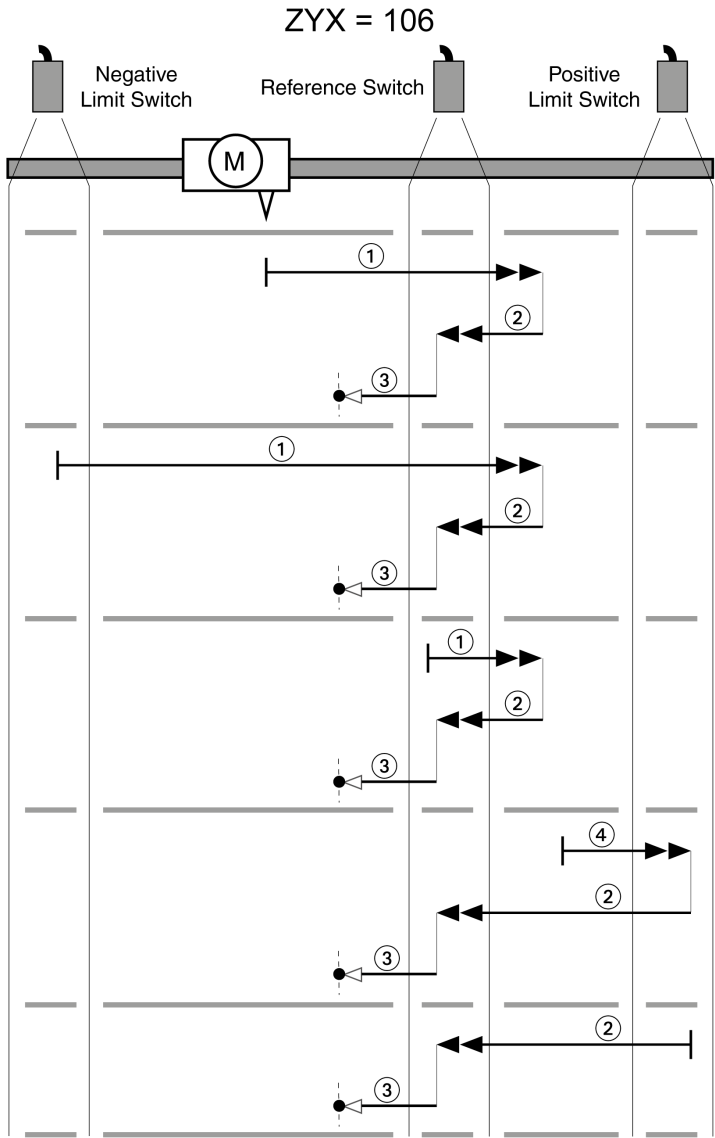
Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 026)



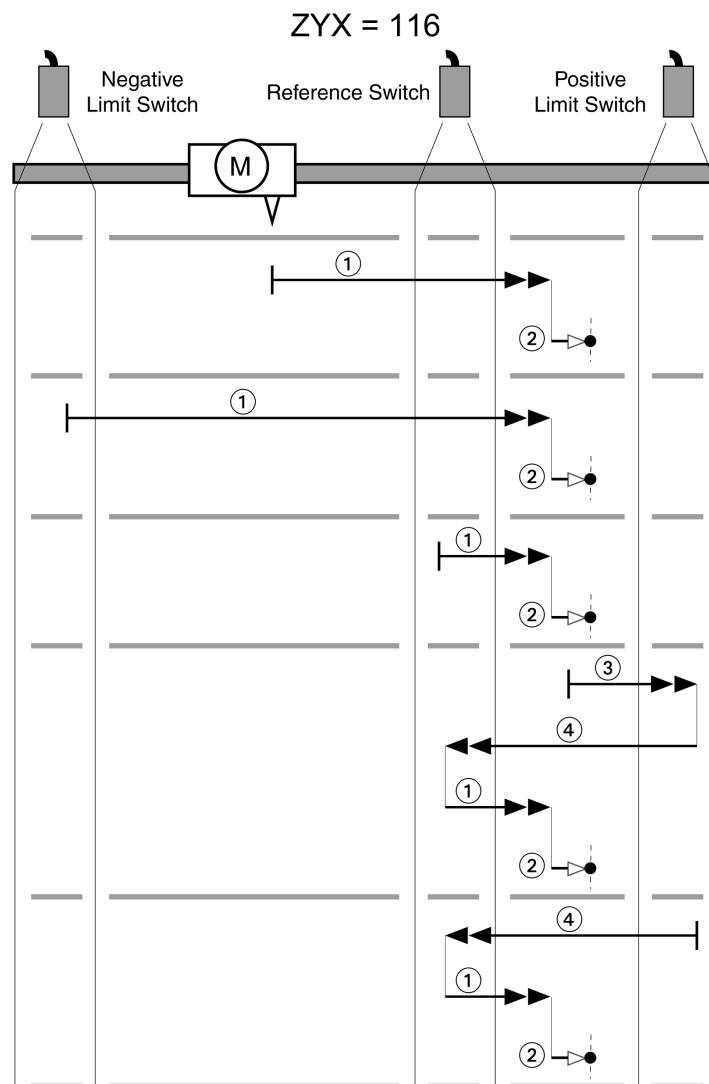
Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 106)



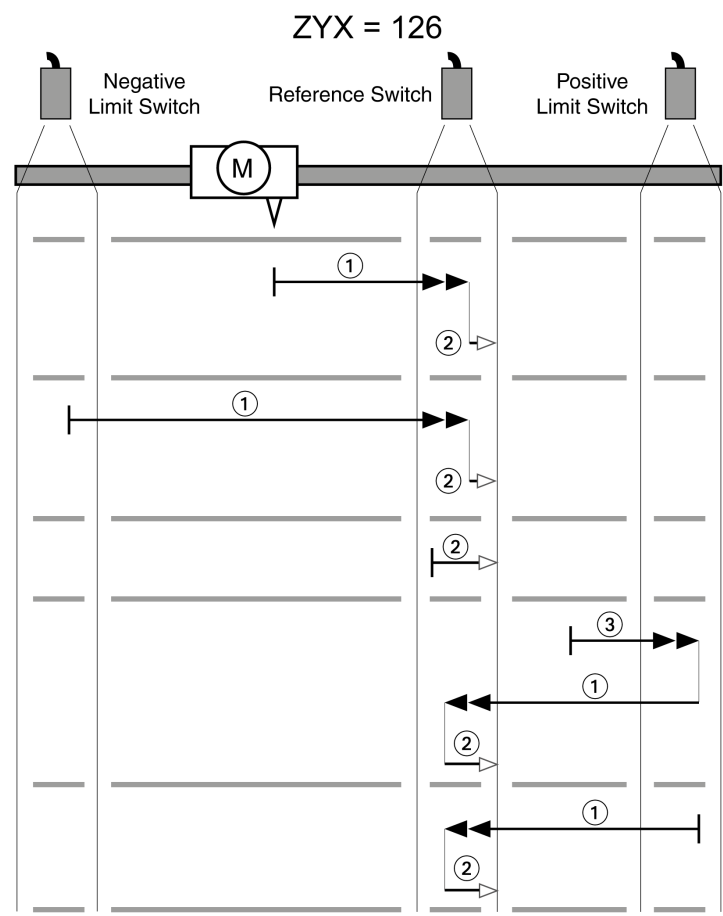
Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to rising edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 116)



Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to the limit switch at velocity P5-05
4	Movement to rising edge at velocity P5-05

Reference movement (ZYX = 126)

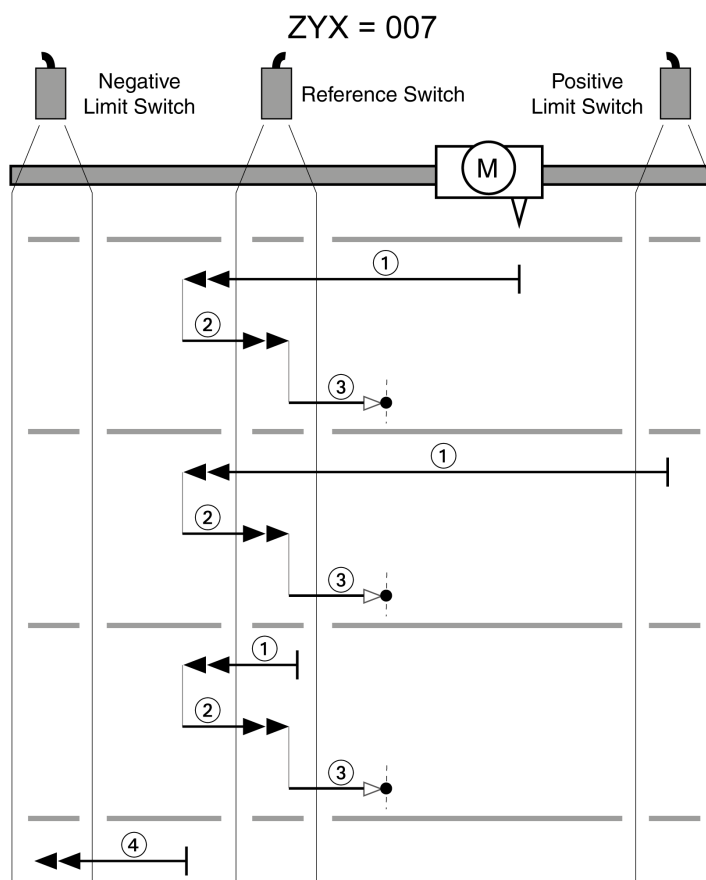


Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference Movement in Negative Direction to the Falling Edge of the Reference Switch

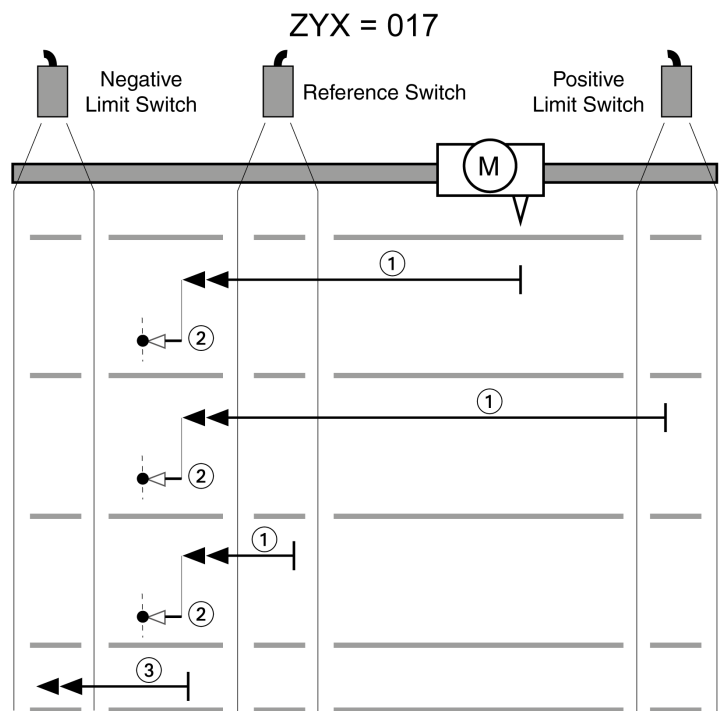
The following illustrations show reference movements to the falling edge of the reference switch in negative direction from different starting positions.

Reference movement (ZYX = 007)



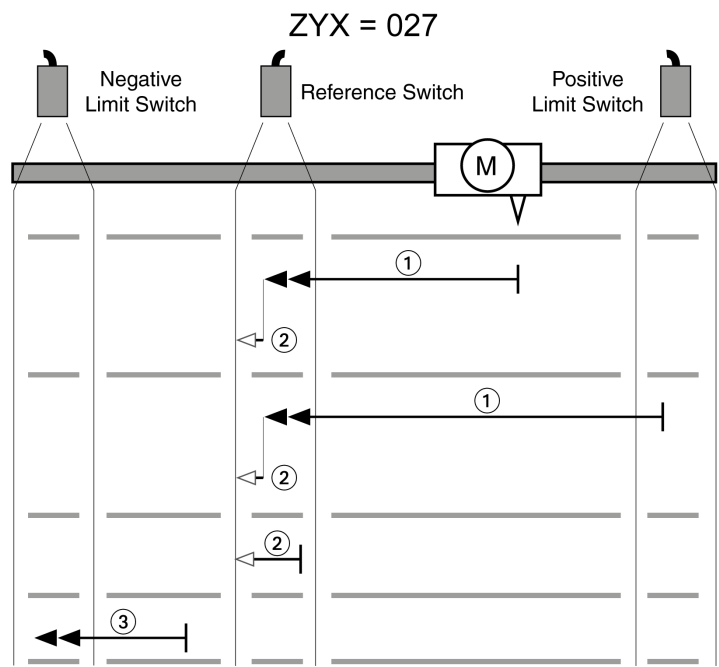
Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to rising edge at velocity P5-05
3	Movement to the index pulse at velocity P5-06
4	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 017)



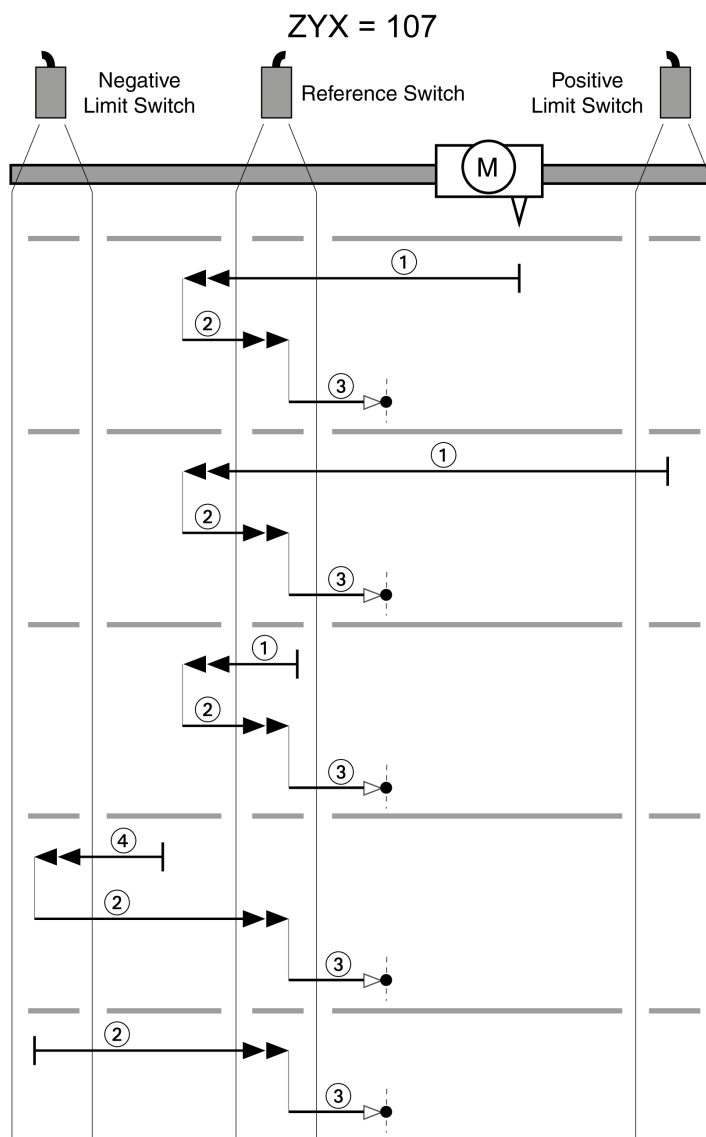
Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Reference movement (ZYX = 027)



Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

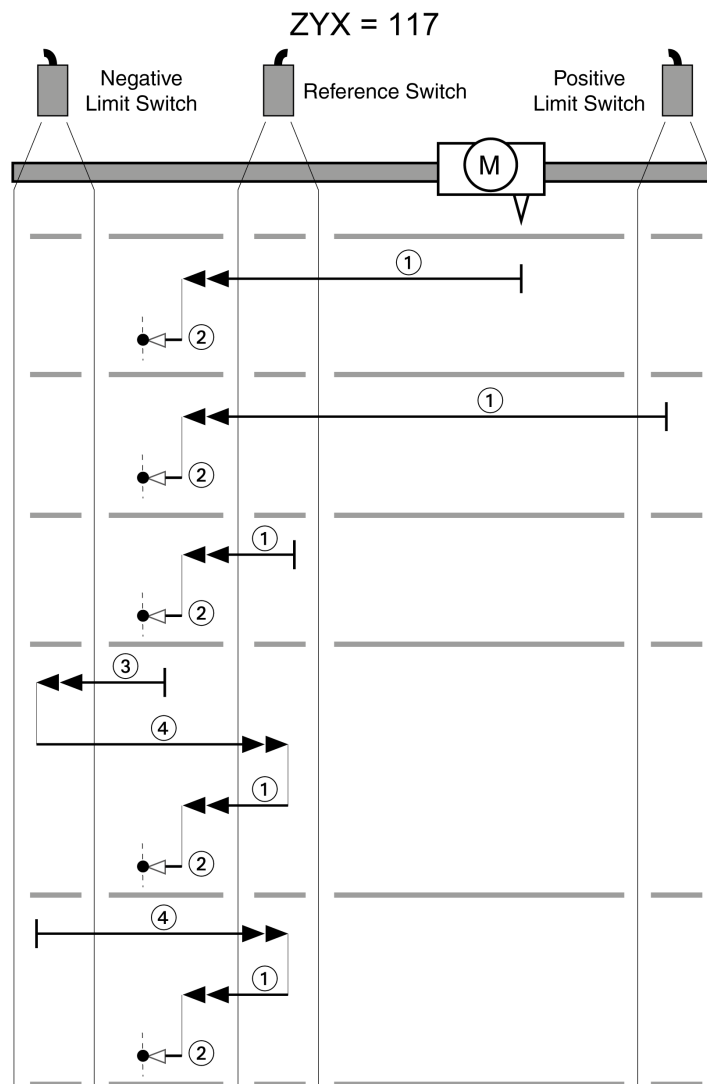
Reference movement (ZYX = 107)



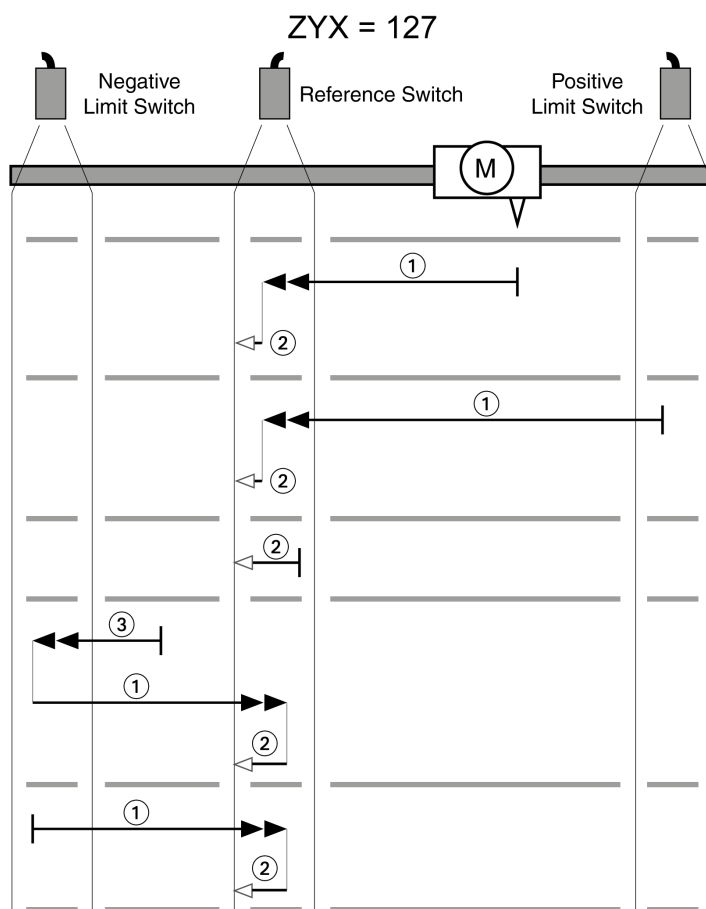
Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to rising edge at velocity P5-05
3	Movement to the limit switch at velocity P5-06

Item	Description
1	Movement to falling edge at velocity P5-05
2	Movement to the index pulse at velocity P5-06
3	Movement to the limit switch at velocity P5-05
4	Movement to rising edge at velocity P5-05

Reference movement (ZYX = 117)



Reference movement (ZYX = 127)



Item	Description
1	Movement to rising edge at velocity P5-05
2	Movement to falling edge at velocity P5-06
3	Movement to the limit switch at velocity P5-05

Position Setting

By means of position setting, the current motor position is set to the position value in parameter P6-00. This also defines the zero point.

Position setting is only possible when the motor is at a standstill. Any active position deviation remains active and can still be compensated for by the position controller after position setting.

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P6-00 ODAT	Position of Homing Data Set Applicable operating mode: PS After a successful reference movement, this position is automatically set at the reference point. Bits 0 ... 31: Position	PUU -2147483647 0 2147483647 Decimal	s32 RW per.	Modbus 700 _h

Section 18.5

Operating Modes Velocity (V) and Velocity Zero (Vz)

What Is in This Section?

This section contains the following topics:

Topic	Page
Operating Modes Velocity (V) and Velocity Zero (Vz)	331
Acceleration and Deceleration	334

Operating Modes Velocity (V) and Velocity Zero (Vz)

Description

In the operating mode Velocity (V), a movement is made with a specified target velocity.

Source of Reference Value Signals

In the operating mode Velocity (V), the source of the reference value signals is one of the three values set via the parameters P1-09 to P1-11.

In the operating mode Velocity Zero (Vz), the source of the reference value signals is either one of the three values set via the parameters P1-09 to P1-11 or the fixed target velocity 0.

The values of the parameters P1-09 to P1-11 can be selected via the signal input functions SPD0 and SPD1.

The signal input functions SPD0 and SPD1 take priority over the reference value signal at the analog input V_REF.

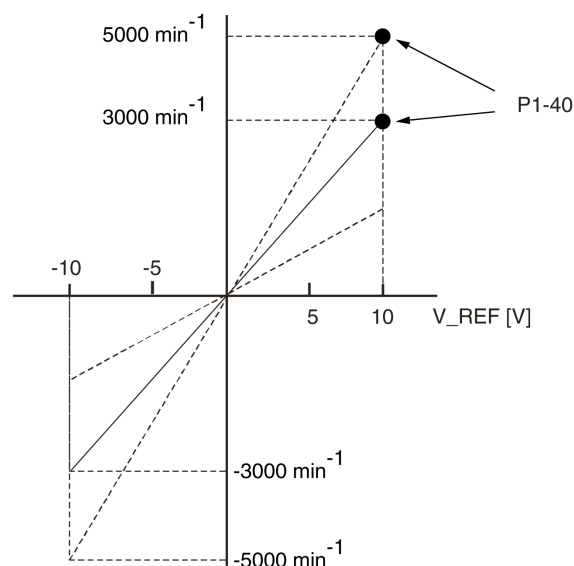
The target velocity is selected via the signal input functions SPD0 (LSB) and SPD1 (MSB) (bit-coded):

For additional information on the parameterizable signal input functions, refer to Setting the Digital Signal Inputs ([see page 270](#)).

-	Signal state of the digital signal inputs		Target velocity via:		Range
	SPD1	SPD0			
S1	0	0	Operating mode Velocity (Vz)	Voltage between V_REF (Pin42) and GND (pin 44)	-10V ... 10V
			Operating mode Velocity Zero (Vz)	0 rpm	
S2	0	1	Internal parameters	P1-09	-
S3	1	0		P1-10	
S4	1	1		P1-11	

Scaling of the Analog Input V_REF

The parameter P1-40 lets you set the velocity corresponding to 10 V. This results in a linear scaling for the analog input V_REF.

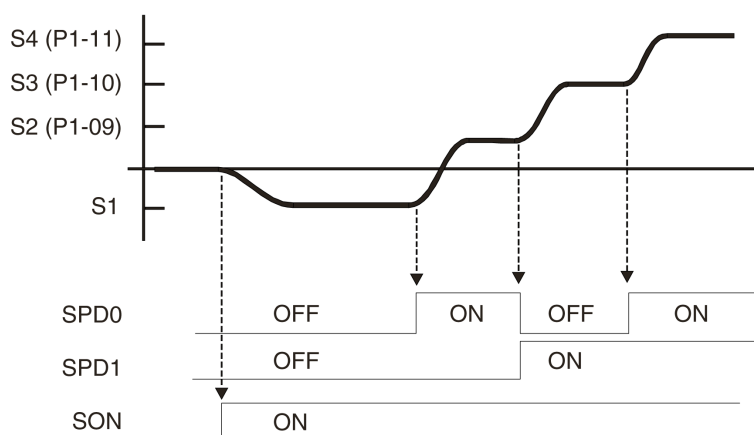


Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-40 VCM	Velocity Target Value and Velocity Limitation 10 V Applicable operating mode: PT, PS, V, T In the operating mode V, this parameter specifies the target velocity that corresponds to the maximum input voltage of 10 V. In the operating mode T, this parameter specifies the velocity limitation that corresponds to the maximum input voltage of 10 V. Example: If the value of this parameter is 3000 in the operating mode V and if the input voltage is 10 V, the target velocity is 3000 rpm.	rpm 0 - 10001 Decimal	s32 RW per.	Modbus 250 _h

Example

The illustration below shows how the target velocities are switched by means of the signal input functions SPD0, SPD1 and SON.

Operating modes Velocity (V) and Velocity Zero (Vz)



For further information, refer to Setting the Digital Signal Inputs ([see page 270](#)).

Stopping the Movement via Signal Input Function ZCLAMP

The movement can be stopped via the digital signal input function ZCLAMP.

Conditions for stopping the movement:

- The reference velocity must be below the velocity value defined in parameter P1-38.
- The signal input function ZCLAMP must be assigned and the signal input must be triggered.

For assigning the signal input function, refer to Setting the Digital Signal Inputs ([see page 270](#)).

Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-38 ZSPD	Signal Output Function ZSPD / Signal Input Function ZCLAMP - Velocity Applicable operating mode: PT, PS, V, T This parameter specifies the velocity for the signal output function ZSPD. The signal output function ZSPD indicates that the velocity of the motor is less than the velocity value set via this parameter. This parameter specifies the velocity for the signal input function ZCLAMP. The signal input function ZCLAMP stops the motor. The velocity of the motor must be below the velocity value set via this parameter.	0.1rpm 0 100 2000 Decimal	s32 RW per.	Modbus 24C _n

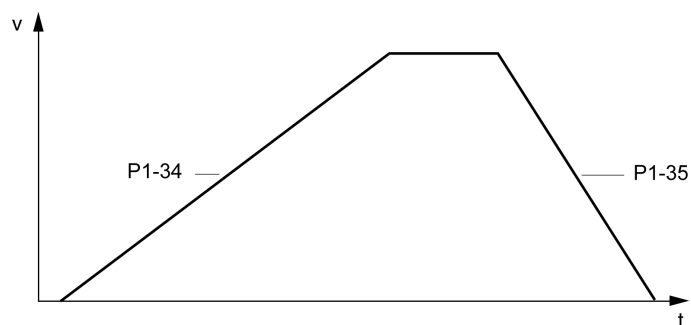
Additionally the behavior for ZCLAMP can be set via parameter P2-65 bit 10.

Setting of parameter P2-65 bit 10:

- Bit 10 = 0: Immediate stop. Motor is locked at the position where it was when ZCLAMP became active.
- Bit 10 = 1: Motor is decelerated with deceleration ramp setting. Motor is locked at the position where standstill is reached.

Acceleration and Deceleration

The parameters P1-34 and P1-35 allow you to set the acceleration and deceleration.



Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-34 TACC	Acceleration Period Applicable operating mode: PT, V The acceleration period is the time in milliseconds required to accelerate from motor standstill to 6000 rpm. For operating mode V, this parameter specifies the acceleration. For operating mode PT, this parameter specifies an acceleration limitation for the pulses at the PTI interface.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 244 _h
P1-35 TDEC	Deceleration Period Applicable operating mode: PT, V The deceleration period is the time in milliseconds required to decelerate from 6000 rpm to motor standstill. For operating mode V, this parameter specifies the deceleration. For operating mode PT, this parameter specifies a deceleration limitation for the pulses at the PTI interface.	ms 6 30 65500 Decimal	u16 RW per.	Modbus 246 _h

Section 18.6

Operating Modes Torque (T) and Torque Zero (Tz)

Operating Modes Torque (T) and Torque Zero (Tz)

Description

In the operating mode Torque (T), a movement is made with a specified target torque. The target torque is specified in percent of the nominal torque of the motor.

The operating modes Torque (T) and Torque (Tz) and the dual operating modes with Torque (T) and Torque (Tz) do not provide deceleration functionality in response to a power stage disable request. In these operating modes, the motor coasts down to a standstill in response to a power stage disable request. You must install additional equipment such as a dedicated service brake if your application requires faster deceleration of the load.

WARNING

UNINTENDED EQUIPMENT OPERATION

- During commissioning, trigger all signals and simulate all conditions that cause a power stage disable request in order to verify that all loads come to a secure standstill when the power stage is disabled under maximum load conditions.
- Install a dedicated service brake if removal of power to the motor does not meet the requirements of your application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Source of Reference Value Signals

In the operating mode Torque (T), the source of the reference value signals is either the analog input `T_REF` or one of the three values set via the parameters `P1-12` to `P1-14`.

In the operating mode Torque Zero (Tz), the source of the reference value signals is either one of the three values set via the parameters `P1-12` to `P1-14` or the fixed target torque 0 %.

The values of the parameters `P1-12` to `P1-14` can be selected via the signal input functions `TCM0` and `TCM1`.

The signal input functions `TCM0` and `TCM1` take priority over the reference value signal of the analog input `T_REF`.

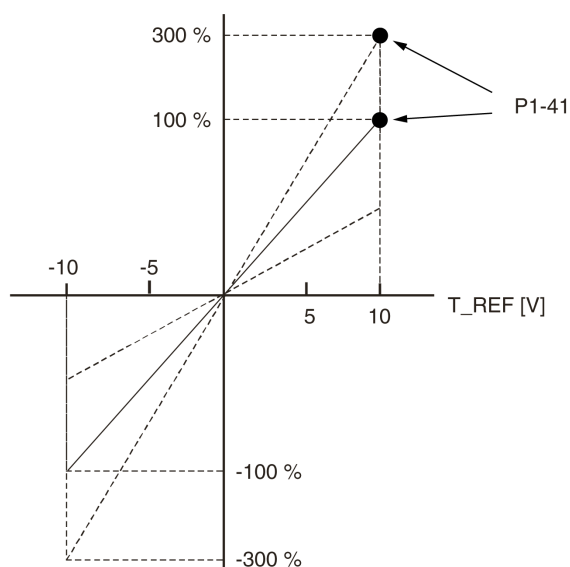
The target torque is selected via the signal input functions `TCM0` (LSB) and `TCM1` (MSB) (bit-coded):

For further information on the parameterizable signal input functions, refer to Setting the Digital Signal Inputs ([see page 270](#)).

-	Signal state of the digital signal inputs		Target torque is provided via:		Range
	TCM1	TCM0			
T1	0	0	Operating mode Torque (T)	Voltage between <code>T_REF</code> (pin 18) and GND (pin 19)	-10V ... 10V
			Operating mode Torque Zero (Tz)	0 %	-
T2	0	1	Internal parameters	<code>P1-12</code>	-300 ... 300%
T3	1	0		<code>P1-13</code>	
T4	1	1		<code>P1-14</code>	

Scaling of the Analog Input T_REF

The parameter P1-41 lets you set the torque corresponding to 10 V. This results in a linear scaling for the analog input T_REF.

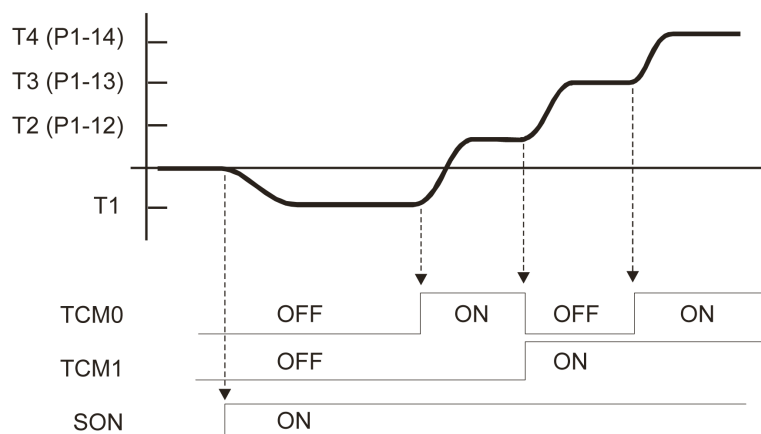


Parameter name	Description	Unit Minimum value Factory setting Maximum value HMI Format	Data type R/W Persistent	Parameter address via fieldbus
P1-41 TCM	Torque Target Value and Torque Limitation 10 V Applicable operating mode: PT, PS, V, T In the operating mode T, this parameter specifies the target torque that corresponds to the maximum input voltage of 10 V. In the operating modes PT, PS and V, this parameter specifies the torque limitation that corresponds to the maximum input voltage of 10 V. Example: If the value of this parameter is 100 in the operating mode T and if the input voltage is 10 V, the target torque is 100 % of the nominal torque. Setting can only be changed if power stage is disabled.	% 0 100 1000 Decimal	u16 RW per.	Modbus 252 _n

Example

The illustration below shows how the target torque is switched by means of the signal input functions TCM0, TCM1 and SON.

Operating modes Torque (T) and Torque Zero (Tz)



For further information, refer to Setting the Digital Signal Inputs ([see page 270](#)).

Part VIII

Diagnostics and Troubleshooting

Chapter 19

Diagnostics and Troubleshooting

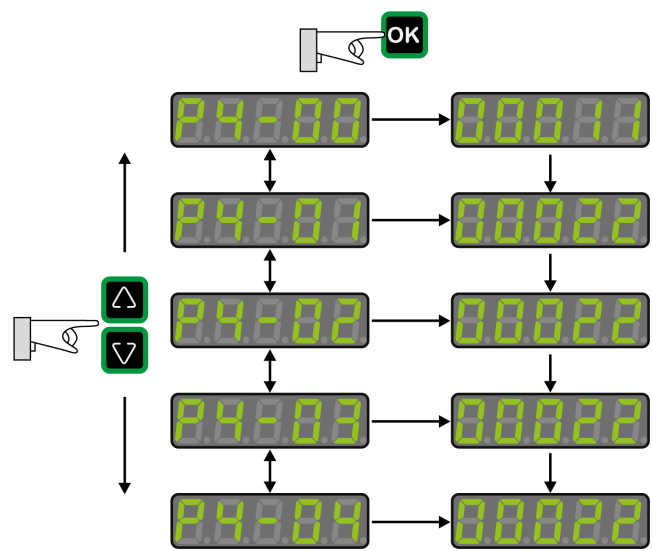
What Is in This Chapter?

This chapter contains the following topics:

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Diagnostics Via the Commissioning Software	343
Alert Codes and Error Codes	344

Diagnostics Via the Integrated HMI

Parameters P4-00 to P4-04 allow you to read the error memory.
The error memory also contains a history of the last 5 detected errors.



Parameter	Description
P4-00	Error number of the most recently detected error
...	...
P4-04	Error number of the oldest detected error

The parameter P0-47 allows you to read the last detected alert.

Diagnostics Via the Signal Outputs

The signal outputs allow you to indicate, among other things, operating states and detected errors. The following list is an excerpt of the parameterizable signal output functions. For additional signal output functions, refer to Setting the Digital Signal Outputs (*see page 276*).

Setting A for P2-18 ... P2-22	Short name	Name of the output function	Description
1	SRDY	Servo Ready	The signal output function SRDY indicates that no errors are presently detected, i.e. the drive is not in the operating state Fault.
2	SON	Servo On	The signal output function SON indicates that the drive is in the operating state Operation Enabled.
7	ERROR	Error Detected	The signal output function ERROR indicates that an error has been detected and that the drive has switched to the operating state Fault. For further information, refer to Diagnostics and Troubleshooting (<i>see page 341</i>).
11	WARN	Advisory or Alert Signal activated	The signal output function indicates that one of the following conditions has been detected: Hardware limit switch triggered, undervoltage, Nodeguard alert, Operational Stop (OPST).

Diagnostics Via the Commissioning Software

See the information provided with the commissioning software for details on how to display the device state via the commissioning software LXM26 DTM Library.

Alert Codes and Error Codes

Meaning of an Alert

An alert indicates a potential issue that was detected by a monitoring function. An alert does not trigger a transition of the operating state.

Number	Description	Cause	Remedy
AL014	Negative hardware limit switch triggered	-	-
AL015	Positive hardware limit switch triggered	-	-
AL283	Positive software limit switch triggered	-	-
AL285	Negative software limit switch triggered	-	-
Wn023	Alert threshold reached: Motor overload (foldback)	The foldback current of the motor has dropped below the alert threshold specified via the parameter P1-28.	Verify correct settings of the parameter P1-28 for the foldback current of the motor.
Wn283	Target value will cause movement to positive software limit switch	-	Verify correct target positions.
Wn285	Target value will cause movement to negative software limit switch	-	Verify correct target positions.
Wn701	Alert threshold reached: Drive overload (foldback)	The foldback current of the drive has dropped below the alert threshold specified via the parameter P1-24.	Verify correct settings of the parameter P1-24 for the foldback current of the drive.
Wn702	The DC bus voltage has dropped below the alert threshold.	Power supply loss, poor power supply.	Verify correct mains supply. Verify that the undervoltage limit is set correctly via the parameter P4-24.
Wn703	Alert threshold reached: Power stage overtemperature	Ambient temperature is too high, fan is inoperative, dust.	Verify correct operation of the fan. Improve the heat dissipation in the control cabinet. Remove pollution and verify that dust cannot get into the control cabinet or into the drive.
Wn704	Alert threshold reached: Motor overtemperature	The motor temperature is excessively high.	Verify correct settings of the parameters for temperature monitoring. Verify proper ventilation and heat dissipation of the motor. Clean off pollutants such as dust. Verify that the motor is evenly mounted to the flange plate. Increase the size of the flange plate to which the motor is mounted to improve heat dissipation. Verify that the motor is properly sized for the application.
Wn707	Alert threshold reached: Drive overtemperature (controller)	Ambient temperature is too high, fan is inoperative, dust.	Verify correct operation of the fan. Improve the heat dissipation in the control cabinet. Remove pollution and verify that dust cannot get into the control cabinet or into the drive.
Wn713	Positive hardware limit switch and negative hardware limit triggered	-	-
Wn716	Positive software limit switch and negative software limit triggered	-	-
Wn728	Alert: Missing mains supply, undervoltage mains supply	At least one mains phase is missing. Mains voltage is out of range. Mains frequency is out of range.	Verify correct connection of mains supply. Verify that the values of the mains power supply network comply with the technical data.

Number	Description	Cause	Remedy
Wn729	Modbus: Node Guarding error detected	Incorrect Modbus connection, incorrect data from Modbus master.	Verify correct Modbus connection. Verify correct operation of Modbus master.
Wn730	Alert threshold reached: Braking resistor overload	The permissible braking resistor power has been exceeded.	Verify correct rating of the braking resistor used. Verify your application.
Wn731	Encoder error detected	Refer to parameter P8-49 for details.	-
Wn732	Alert threshold reached: Processing time too long	-	-
Wn734	Alert threshold reached: Drive overtemperature (IPM)	Ambient temperature is too high, fan is inoperative, dust.	Verify correct operation of the fan. Improve the heat dissipation in the control cabinet. Remove pollution and verify that dust cannot get into the control cabinet or into the drive.
Wn737	Parameters have been reset to the factory settings, but are not yet saved to the non-volatile memory.	-	Use parameter P2-08 = 11 to save parameters reset to the factory settings to the non-volatile memory and restart the drive.
Wn739	Temperature value for monitoring function not available	-	-
Wn740	Target value will cause movement to positive software limit switch	-	-
Wn741	Target value will cause movement to negative software limit switch	-	-
Wn742	Motor type has changed.	The type of motor connected is different from the previously connected type of motor.	Reset the drive to the factory settings.
Wn744	Excessive electronic noise	-	-

Meaning of an Error

An error is a discrepancy between a computed, measured, or signaled value or condition and the specified or theoretically correct value or condition detected by a monitoring function. An error triggers a transition of the operating state.

Number	Short description	Cause	Remedy
AL001	Power stage overcurrent	An overcurrent has been detected at the power stage which may be caused by a short circuit or by incorrect settings of the current loop parameters. This condition may occur up to three times in succession. After the third time, a time delay of one minute must pass before the power stage can be enabled again.	Verify correct connection of the motor. Verify correct settings of the parameters for the current loop.
AL002	DC bus overvoltage	The DC bus voltage exceeded the maximum value.	Verify your application. Reduce the external load, the motor velocity, or the deceleration. Use an appropriately rated braking resistor, if necessary.
AL003	DC bus undervoltage	Power supply loss, poor power supply.	Verify correct mains supply. Verify that the undervoltage limitation is set correctly via the parameter P4-24.
AL005	Braking resistor overload	The braking resistor has been on for such a long period of time that its overload capability has been exceeded.	Verify your application. Reduce the external load, the motor velocity, or the deceleration. Use a braking resistor with a greater rating, if necessary.

Number	Short description	Cause	Remedy
AL006	Motor overload (foldback)	The foldback current of the motor has dropped below the value specified via the parameter P1-27.	Verify correct settings for the parameter P1-27.
AL007	Actual motor velocity too high.	The actual motor velocity exceeded the velocity limitation by more than 20% (P1-55). The analog input signal is not stable.	Verify that the velocity limitation set via the parameter P1-55 matches the requirements of the application. Verify that the values for the tuning parameters are suitable. Verify that the frequency of the analog input signal is stable using a signal detector. Use a filter function.
AL008	Frequency of reference value signal is too high	The frequency of the pulse signal (A/B, Pulse/Direction, CW/CCW) exceeds the specified range. Received pulses may be lost.	Adapt the output pulse frequency of the external source to fit the input specification of the drive. Adapt the gear ratios to the application requirements (parameters P1-44, P1-45, P2-60, P2-61 and P2-62).
AL009	Position deviation too high (following error)	The position deviation has exceeded the maximum permissible position deviation specified via the parameter P2-35 and the drive has detected a following error.	Verify your application. Reduce the external load. Increase the permissible position deviation via the parameter P2-35. Reduce the motor velocity via the parameters P1-09 ... P1-11 or the analog input V_REF. Increase the torque limitation via the parameters P1-12 ... P1-14 or the analog input T_REF.
AL013	The input to which the signal input function OPST is assigned has been activated.	-	Identify the cause which has triggered the signal input function OPST. Remove the cause. If your application does not require the signal input function OPST, disable this signal input function.
AL016	Power stage overtemperature	Ambient temperature is too high, fan is inoperative, dust.	Verify correct operation of the fan. Improve the heat dissipation in the control cabinet. Remove pollution and verify that dust cannot get into the control cabinet or into the drive.
AL017	Error detected in non-volatile memory	The drive was reset to the factory settings via parameter P2-08.	Use parameter P2-08 = 11 to save parameters reset to the factory settings to the non-volatile memory and restart the drive. Contact technical support.
AL018	Encoder simulation frequency exceeded 4 MHz	The computed equivalent encoder output frequency exceeds the maximum limit of 4 MHz for this signal.	Reduce the resolution of the encoder simulation via the parameter P1-46 or reduce the maximum velocity.
AL020	Modbus: Node Guarding error detected	Incorrect Modbus connection, incorrect data from Modbus master.	Verify correct Modbus connection. Verify correct operation of Modbus master.
AL022	Missing mains supply, undervoltage mains supply	At least one mains phase is missing. Mains voltage is out of range. Mains frequency is out of range.	Verify correct connection of mains supply. Verify that the values of the mains power supply network comply with the technical data.
AL025	Not possible to read data of electronic motor nameplate	Incorrect or missing motor data. Motor without electronic motor nameplate has been connected.	Verify that the drive and the connected motor are a permissible product combination. Verify correct connection of the encoder. Contact Technical Support or replace the motor.
AL026	Error detected in communication with motor encoder	Communication with the encoder was not initialized correctly.	Verify correct connection of the encoder. Contact Technical Support or replace the motor.

Number	Short description	Cause	Remedy
AL030	Motor torque too high for an excessive period of time	The motor torque has exceeded the value specified via the parameter P1-57 for a period of time exceeding the value specified via the parameter P1-58.	Verify your application. Verify that no movements are made up to a mechanical stop (for example, use limit switches). Verify that the values for the parameters P1-57 and P1-58 are suitable.
AL502	System error detected (FPGA)	-	Contact technical support.
AL503	System error detected (non-volatile memory)	-	Contact technical support.
AL504	System error detected (non-volatile memory)	-	Contact technical support.
AL505	DC bus voltage measurement	An error was detected in the circuit that measures the DC bus voltage.	Perform a Fault Reset. Restart the drive. If the error persists, contact Technical Support.
AL507	System error detected (NV access)	-	Contact technical support.
AL508	Drive overload (foldback)	The foldback current of the drive has dropped below the value specified via the parameter P1-23.	Verify correct settings for the parameter P1-23.
AL514	Motor overtemperature	The motor temperature is excessively high.	Verify correct settings of the parameters P1-62 and P1-63 for temperature monitoring. Verify proper ventilation and heat dissipation of the motor. Clean off pollutants such as dust. Verify that the motor is evenly mounted to the flange plate. Increase the size of the flange plate to which the motor is mounted to improve heat dissipation. Verify that the motor is properly sized for the application.
AL517	Encoder overvoltage or overcurrent	The current supplied by the drive for the 5 V encoder supply has exceeded the limit. This condition may occur up to three times in succession. After the third time, a time delay of one second must pass before the power stage can be enabled again.	Verify correct connection of the encoder (short circuits). Verify the current consumption of the encoder.
AL523	System error detected (self-test)	The self-test has detected an error.	Contact technical support.
AL525	Reserved	–	–
AL526	Reserved	–	–
AL527	System error detected (Watchdog)	The Watchdog function has detected a system error.	Restart the drive. If the error persists, contact Technical Support.
AL528	Drive overtemperature (IPM)	Ambient temperature is too high, fan is inoperative, dust.	Verify correct operation of the fan. Improve the heat dissipation in the control cabinet. Remove pollution and verify that dust cannot get into the control cabinet or into the drive.
AL529	Drive overtemperature (controller)	Ambient temperature is too high, fan is inoperative, dust.	Verify correct operation of the fan. Improve the heat dissipation in the control cabinet. Remove pollution and verify that dust cannot get into the control cabinet or into the drive.
AL532	Calculated offsets for current sensors out of range	The calculated offsets for the current sensors are out of range.	Perform a Fault Reset. Restart the drive. If the error persists, contact Technical Support.
AL533	Reserved	–	–
AL534	Pulse signal missing	One of the pulse signals is not connected.	Verify correct connection of the pulse inputs.

Number	Short description	Cause	Remedy
AL535	System error detected (FPGA does not match firmware)	The firmware version is not suitable for the drive.	Update the firmware of the drive. Contact technical support.
AL539	Motor phase missing	One of the motor phases is not connected.	Verify correct connection of the motor phases. Contact technical support.
AL547	Motor blocked	The motor was blocked mechanically, for example, by a mechanical stop or by the load.	Remove condition causing the mechanical blocking. Verify your application.
AL555	Velocity deviation too high	The deviation between actual velocity and reference velocity has exceeded the maximum velocity deviation specified via the parameter P2-34.	Verify your application. Verify that the values for the tuning parameters are suitable. Increase the value for the maximum velocity deviation in the parameter P2-34.
AL558	System error detected	-	Contact technical support.
AL560	Power stage supply off	-	Power on the power stage supply.
AL561	Temperature sensor inoperative	-	Restart the drive. If the error persists, contact Technical Support.
AL563	Commutation error detected	Motor phases have been interchanged.	Verify correct connection of the motor phases.
AL567	System error detected (encoder)	Refer to parameter P8-48 for details.	Contact technical support.
AL568	Braking resistor overload	The permissible braking resistor power has been exceeded.	Verify correct rating of the braking resistor used. Verify your application.
AL569	Configuration not correctly transferred via Modbus	-	Verify correct connection. Verify that configuration file and drive are compatible.
AL570	Overcurrent detected at one of the digital outputs	-	Verify correct wiring of the digital outputs. Verify that there are no short circuits.
AL572	Position deviation too high (following error)	The position deviation has exceeded the maximum permissible position deviation specified via the parameter P2-35 and the drive has detected a following error.	Verify your application. Reduce the external load. Increase the permissible position deviation via the parameter P2-35. Reduce the motor velocity via the parameters P1-09 ... P1-11 or the analog input V_REF. Increase the torque limitation via the parameters P1-12 ... P1-14 or the analog input T_REF.
AL588	Reserved	—	—
AL595	Impermissible combination of drive and motor	-	Use an approved drive/motor combination.
AL596	Unstable current loop	Excessive overshoot in current loop.	Verify correct settings of the parameters for the current loop.

Part IX

Service, Maintenance and Disposal

Chapter 20

Service, Maintenance, and Disposal

What Is in This Chapter?

This chapter contains the following topics:

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General

The product may only be repaired by a Schneider Electric customer service center.

The use and application of the information contained herein require expertise in the design and programming of automated control systems.

Only you, the user, machine builder or integrator, can be aware of all the conditions and factors present during installation and setup, operation, repair and maintenance of the machine or process.

You must also consider any applicable standards and/or regulations with respect to grounding of all equipment. Verify compliance with any safety information, different electrical requirements, and normative standards that apply to your machine or process in the use of this equipment.

Many components of the equipment, including the printed circuit board, operate with mains voltage, or present transformed high currents, and/or high voltages.

The motor itself generates voltage when the motor shaft is rotated.

DANGER

ELECTRIC SHOCK, EXPLOSION, OR ARC FLASH

- Disconnect all power from all equipment including connected devices prior to removing any covers or doors, or installing or removing any accessories, hardware, cables, or wires.
- Place a "Do Not Turn On" or equivalent hazard label on all power switches and lock them in the non-energized position.
- Wait 15 minutes to allow the residual energy of the DC bus capacitors to discharge.
- Do not assume that the DC bus is voltage-free when the DC bus LED is off.
- Block the motor shaft to prevent rotation prior to performing any type of work on the drive system.
- Do not create a short-circuit across the DC bus terminals or the DC bus capacitors.
- Replace and secure all covers, accessories, hardware, cables, and wires and confirm that a proper ground connection exists before applying power to the unit.
- Use only the specified voltage when operating this equipment and any associated products.

Failure to follow these instructions will result in death or serious injury.

Service Address

If you cannot resolve an error yourself, contact your sales office.

Have the following data available:

- Nameplate (type, identification number, serial number, DOM, ...)
- Type of error (with LED flash code or error code)
- Previous and concomitant circumstances
- Your own assumptions concerning the cause of the error

Also include this information if you return the product for inspection or repair.

If you have any questions, contact your sales office. Your sales office staff will provide you the name of a customer service office in your area.

<http://www.schneider-electric.com>

Maintenance of the Drive

Prior to any type of work on the drive system, consult the chapters on Installation and Commissioning for information to be observed.

Repairs cannot be made with the device installed.

Include the following points in the maintenance plan of your machine.

Connections and Fastening

- Check all connection cables and connectors regularly for damage. Replace damaged cables immediately.
- Tighten all mechanical and electrical threaded connections to the specified torque.

Cleaning

Clean dust and dirt off the product at regular intervals. Insufficient heat dissipation to the ambient air may excessively increase the temperature.

Replacement of Drive

Unsuitable settings or unsuitable data may trigger unintended movements, trigger signals, damage parts and disable monitoring functions. Some parameters and other operational data do not become active until after a restart.

WARNING

UNINTENDED EQUIPMENT OPERATION

- Only start the system if there are no persons or obstructions in the zone of operation.
- Do not operate the drive system with undetermined parameter values.
- Never modify a parameter value unless you fully understand the parameter and all effects of the modification.
- Restart the drive and verify the saved operational data and/or parameter values after modification.
- Carefully run tests for all operating states and potential error situations when commissioning, upgrading or otherwise modifying the operation of the drive.
- Verify the functions after replacing the product and also after making modifications to the parameter values and/or other operational data.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Prepare a list with the parameters required for the functions used.

Observe the following procedure when replacing devices:

Step	Action
1	Save all parameter settings. Save the data to your PC using the commissioning software, refer to chapter Commissioning Software (<i>see page 176</i>).
2	Power off all supply voltages. Verify that no voltages are present.
3	Label all connections and remove all connection cables (unlock connector locks).
4	Uninstall the product.
5	Note the identification number and the serial number shown on the product nameplate for later identification.
6	Install the new product as per chapter Installation (<i>see page 119</i>).
7	If the product to be installed has previously been used in a different system or application, you must restore the factory settings before commissioning the product.
8	Commission the product as per chapter Commissioning (<i>see page 161</i>).

Maintenance of the Motor

Prior to any type of work on the drive system, consult the chapters on Installation and Commissioning for information to be observed.

Repairs cannot be made with the device installed.

Include the following points in the maintenance plan of your machine.

Connections and Fastening

- Inspect all connection cables and connectors regularly for damage. Replace damaged cables immediately.
- Verify that all output elements are firmly seated.
- Tighten all mechanical and electrical threaded connections to the specified torque.

Lubricating the Shaft Sealing Ring

In the case of motors with shaft sealing ring, lubricant must be applied to the space between the sealing lip of the shaft sealing ring and the shaft with a suitable non-metallic tool. If the shaft sealing rings are allowed to run dry, the service life of the shaft sealing rings will be significantly reduced.

Cleaning

If the permissible ambient conditions are not respected, external substances from the environment may penetrate the product and cause unintended movement or equipment damage.

WARNING

UNINTENDED MOVEMENT

- Verify that the ambient conditions are respected.
- Do not allow seals to run dry.
- Keep liquids from getting to the shaft bushing (for example, in mounting position IM V3).
- Do not expose the shaft sealing rings and cable entries of the motor to the direct spray of a pressure washer.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Clean dust and dirt off the product at regular intervals. Insufficient heat dissipation to the ambient air may excessively increase the temperature.

Motors are not suitable for cleaning with a pressure washer. The high pressure may force water into the motor.

When using solvents or cleaning agents, verify that the cables, cable entry seals, O-rings, and motor paint are not damaged.

Replacing the Rolling Bearing

When the rolling bearing is replaced, the motor is partially demagnetized and loses power.

NOTICE

INOPERABLE EQUIPMENT

Do not replace the rolling bearing.

Failure to follow these instructions can result in equipment damage.

Changing the Motor

Drive systems may perform unintended movements if unapproved combinations of drive and motor are used. Even if motors are similar, different adjustment of the encoder system may be a source of hazards. Even if the connectors for motor connection and encoder connection match mechanically, this does not imply that the motor is approved for use.

WARNING

UNINTENDED MOVEMENT

Only use approved combinations of drive and motor.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Compatibility between Drive and Motor is defined in the Drive / Motor combinations table ([see page 18](#)).

Observe the following procedure when changing motors:

Step	Action
1	Switch off all supply voltages. Verify that no voltages are present.
2	Label all connections and uninstall the product.
3	Note the identification number and the serial number shown on the product nameplate for later identification.
4	Install the new product as per chapter Installation (see page 149).
5	Commission the product as per chapter Commissioning (see page 161).

If the connected motor is replaced by another approved motor, the new motor is automatically recognized by the drive.

Shipping, Storage, Disposal

Shipping

The product must be protected against shocks during transportation. If possible, use the original packaging for shipping.

Storage

The product may only be stored in spaces where the specified permissible ambient conditions are met. Protect the product from dust and dirt.

Disposal

The product consists of various materials that can be recycled. Dispose of the product in accordance with local regulations.

Visit <http://www.schneider-electric.com/green-premium> for information and documents on environmental protection as per ISO 14025 such as:

- EoLi (Product End-of-Life Instructions)
- PEP (Product Environmental Profile)



D

DTM

(*device type manager*) Classified into 2 categories:

- Device DTMs connect to the field device configuration components.
- CommDTMs connect to the software communication components.

The DTM provides a unified structure for accessing device parameters and configuring, operating, and diagnosing the devices. DTMs can range from a simple graphical user interface for setting device parameters to a highly sophisticated application capable of performing complex real-time calculations for diagnosis and maintenance purposes.

H

HMI

(*human machine interface*) An operator interface (usually graphical) for human control over industrial equipment.

I

IT Mains

Mains in which all active components are isolated from ground or are grounded by a high impedance. IT: isol   terre (French), isolated ground. Opposite: Grounded mains, see TT/TN mains

T

TN Mains

Grounded mains, differ in terms of the ground connection (PE conductor connection). Opposite: Ungrounded mains, see IT mains.

TT Mains

Grounded mains, differ in terms of the ground connection (PE conductor connection). Opposite: Ungrounded mains, see IT mains.



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