

Field oriented vector AC Drive for asynchronous motors



Industrial application

ADV200

■ ■ ■ ■ ... Functions description
and parameters list

GEFRAN

Information about this manual

This manual explains the functions and the description of the parameters.

The informations about mechanical installation, electrical connection and fast start-up can be found on the ADV200 Quick start guide.

The whole set of manuals (included the expansions and field bus manuals) can be found on the CD provided with the drive.

Software version

This manual is updated according the software version V 7.X.16.

The identification number of the software version is indicated on the identification plate of the drive or can be checked with the **Firmware ver.rel** - PAR 490 parameter, menu 2.5.

The Softscope3 (Gefran's Digital Oscilloscope) Tool can be used with version V.7.X.14 and more recent of the firmware. For detailed information on use, please refer to the 1S9SF3EN manual.

General information

Note !

In industry, the terms "Inverter", "Regulator" and "Drive" are sometimes interchanged. In this document, the term "Drive" will be used.

Before using the product, read the safety instruction section carefully (ADV200 - Quick Start-up guide).

Keep the manual in a safe place and available to engineering and installation personnel during the product functioning period.

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Thank you for choosing this Gefran product.

We will be glad to receive any possible information which could help us improving this manual. The e-mail address is the following: techdoc@gefran.com.

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Symbols used in the manual



Warning

Indicates a procedure, condition, or statement that, if not strictly observed, could result in personal injury or death.
Indique le mode d'utilisation, la procédure et la condition d'exploitation. Si ces consignes ne sont pas strictement respectées, il y a des risques de blessures corporelles ou de mort.



Caution

Indicates a procedure, condition, or statement that, if not strictly observed, could result in damage to or destruction of equipment.

Indique et le mode d'utilisation, la procédure et la condition d'exploitation. Si ces consignes ne sont pas strictement respectées, il y a des risques de détérioration ou de destruction des appareils.



Indicates that the presence of electrostatic discharge could damage the appliance. When handling the boards, always wear a grounded bracelet.

Indique que la présence de décharges électrostatiques est susceptible d'endommager l'appareil. Toujours porter un bracelet de mise à la terre lors de la manipulation des cartes.



Important

Indicates a procedure, condition, or statement that should be strictly followed in order to optimize these applications.
Indique le mode d'utilisation, la procédure et la condition d'exploitation. Ces consignes doivent être rigoureusement respectées pour optimiser ces applications.

Note !

Indicates an essential or important procedure, condition, or statement.

Indique un mode d'utilisation, de procédure et de condition d'exploitation essentiels ou importants

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A – Programming

A.1 Menu display modes

The programming menu can be displayed in two modes, which can be selected using the **Access mode** parameter (04 - DRIVE CONFIG menu):

- **Easy** (default) only the main parameters are displayed.
- **Expert** all the parameters are displayed

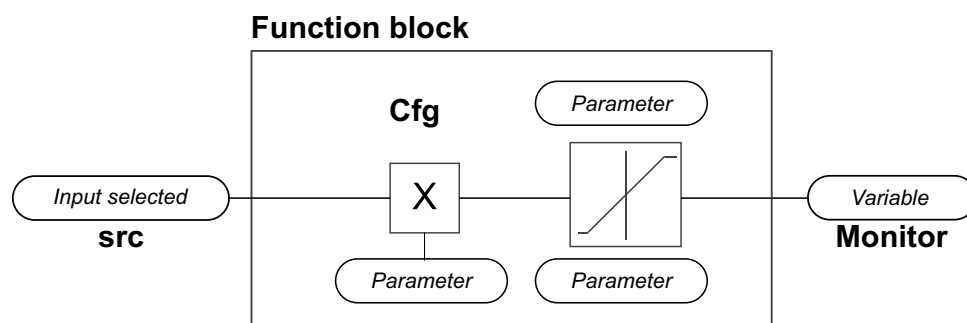
A.2 Programming of “function block” analog and digital input signals

The signals, variables and parameters of each single “function block” of the drive are interconnected in order to achieve the configurations and controls inside the control system.

These can be managed and modified using the keypad, PC configurator or fieldbus programming.

The programming mode is based on the following logic:

- Src** (source; i.e.: **Ramp ref 1 src**, PAR: 610)
This term defines **the source of the function block input**, i.e. the signal to be processed in the function block.
The different configurations are defined in the relative **selection lists**.
- cfg** (configuration; i.e.: **Mpot init cfg**, PAR: 880)
This term refers to **the parameter setting and its effect on the function block**.
For example: Ramp times, internal reference adjustment, etc...
- mon** (display; i.e.: **Ramp ref 1 mon**, PAR: 620)
This term refers to the **variable output from the function block, which is the result of the calculations performed on the actual block**.



A.3 Variable interconnections mode

The **source (src)** allows the desired control signal to be assigned to the function block input.
This operation is performed by using specific selection lists.

Possible control signal sources:

1 – Physical terminal

The analog and digital signals come from the terminal strip of the regulation card and/or from those of the expansion cards.

2 – Drive internal variables

Internal drive control system variables, from “function block” calculations, sent via keypad, PC configurator or fieldbus.

Practical example

The following examples illustrate the philosophies and methods with which more or less complex operations are performed in the single “function blocks”, the results of which represent the output of the block.

• Example: Changing the Speed Reference source

The main drive reference (in the default configuration) **Ramp ref 1 mon** (PAR: 620) is generated by the output of the function block “**Ramp setpoint Block**”.

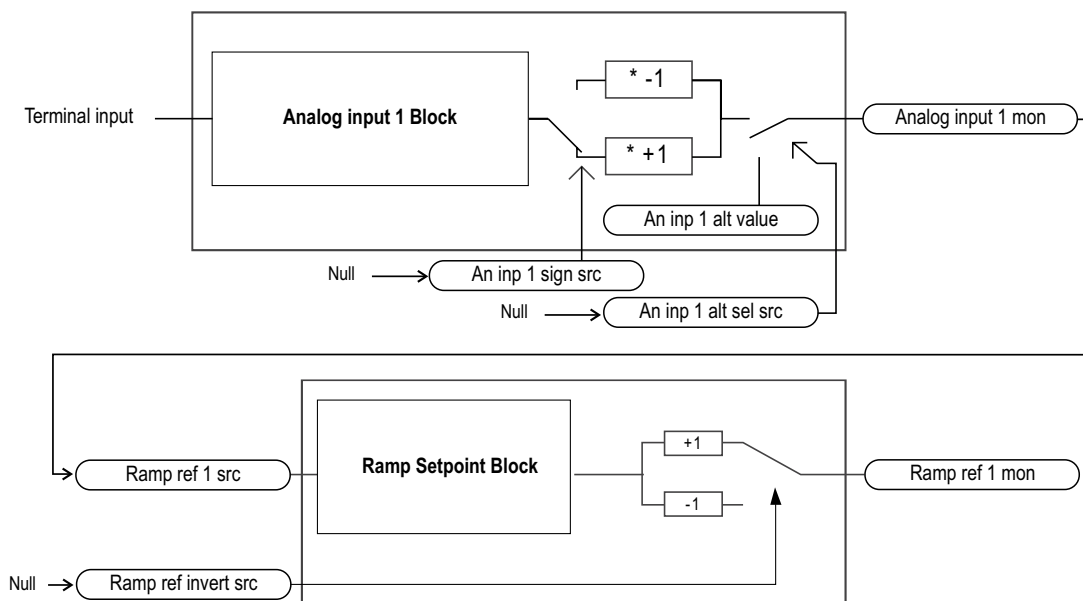
Its default source is the **Analog input 1 mon** signal (PAR: 1500), from the output of the function block “**Analog input 1 Block**”, which in this case refers to analog input 1 of the signal terminal strip.

To change the reference source from the analog input to a digital reference inside the drive, the input signal must be changed to “**Ramp setpoint Block**”.

Enter the **Ramp ref 1 src** parameter (PAR: 610) and set a new reference, selecting it from among those listed in the L_MLTREF selection list, for example **Dig ramp ref 1** (PAR: 600).

• Example: Inverting the analog reference signal

To invert the “**Analog input 1 Block**” output signal, the value of the **An inp 1 sign src** parameter (PAR: 1526), which has a default setting of **Null** (no operation), must be changed by selecting the source of the command signal from among those listed in the L_DIGSEL 2 selection list, for example **Digital input X mon, One** (function always enabled), etc.



The diagrams above illustrate the internal processing philosophy of the single “function blocks” and the result of these changes on the other interconnected “function blocks”.

Note !

This section contains a brief description of the functions of the other parameters in the function blocks not included for the changes in the example

The **An inp 1 alt sel src** parameter (PAR: 1528) can be used to select an alternative reference for the **Analog input 1 mon** (PAR: 1500) output.

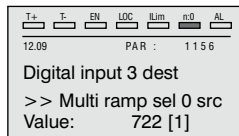
The **An inp 1 alt value** parameter (PAR: 1524) determines the alternative reference value for the **Analog input 1 mon** (PAR: 1500) output.

The **Ramp ref invert src** parameter (PAR: 616) can be used to select the source for the command to reverse the “**Ramp setpoint**” function block output.

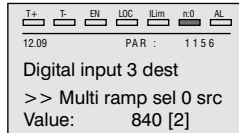
The output signal from the “**Ramp setpoint**” block is displayed in the **Ramp ref 1 mon** parameter (PAR: 620).

A.4 Multiple destination

Several functions can be assigned together to each input: to display which and how many functions have been assigned to each input, check the relative “**dest**” parameter to see whether there is a number shown in square brackets to the right of the number of the selected parameter (as shown in the figure below).



If there is a number, press the key to display the next source applied to the selected input.



B – Parameters and functions description (Expert list)

Legend

①	②	③	④	⑤	⑥	⑦	⑧	⑨	⑩
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc Mod
1 - MONITOR						(Level 1 menu)			
1.1	250	Output current	A	FLOAT	16/32	0.0	0.0	0.0	R FVS
1.2	252	Output voltage	V	FLOAT	16/32	0.0	0.0	0.0	R FVS
22.1 - FUNCTIONS/SPEED RATIO						(Level 2 menu)			
22.1.1	3000	Dig speed ratio	perc	INT16	16/32	100	CALCI	CALCI	ERW FVS
22.1.2	3002	Speed ratio src		LINK	16/32	3000	0	16384	ERW FVS
						L_VREF (Selection List) [*]			

①	Indexing of the menu and parameter
②	Parameter identifier
③	Parameter description
④	UM: unit of measure
⑤	Type of parameter
⑥	BIT Boolean, from modbus seen as 16 bits
⑦	ENUM Selection list, from modbus seen as 16 bits
⑧	FLOAT Real, from modbus seen as 32 bits
⑨	FBM2SIPA 16-bit unsigned integer. Only PAR of existing parameters accepted.
⑩	FBS2MIPA 16-bit unsigned integer. Only PAR of existing parameters accepted.
⑪	INT16 Integer with sign 16 bits, from modbus seen as 16 bits
⑫	INT32 Integer with sign 32 bits, from modbus seen as 32 bits
⑬	ILINK Selection list, from modbus seen as 16 bits
⑭	LINK Selection list, from modbus seen as 16 bits
⑮	UINT16 Integer without sign 16 bits, from modbus seen as 16 bits
⑯	UINT32 Integer without sign 32 bits, from modbus seen as 32 bits
⑰	SINT Integer 8 bits
⑱	Format of data exchanged on Fieldbus (16, 32BIT)

⑥	Default value	CALCF Value calculated as a number with floating point
⑦	Minimum value	CALCI Value calculated as a whole number (Max = 32768)
⑧	Maximum value	SIZE Value depending on the size of the drive
⑨	Accessibility : E Expert R Read S Size (set value depending on the size of the device) W Write Z parameters that can be modified ONLY with the drive disabled	
⑩	Available in regulation mode: V = V/f Control S = Vect Flux OL F = Vect Flux CL	
⑪	Selection lists: The "... src" format parameters are linked to a selection list. The source of the signal that will control the parameter can be selected from the list indicated. The lists are indicated in paragraph C of this manual.	

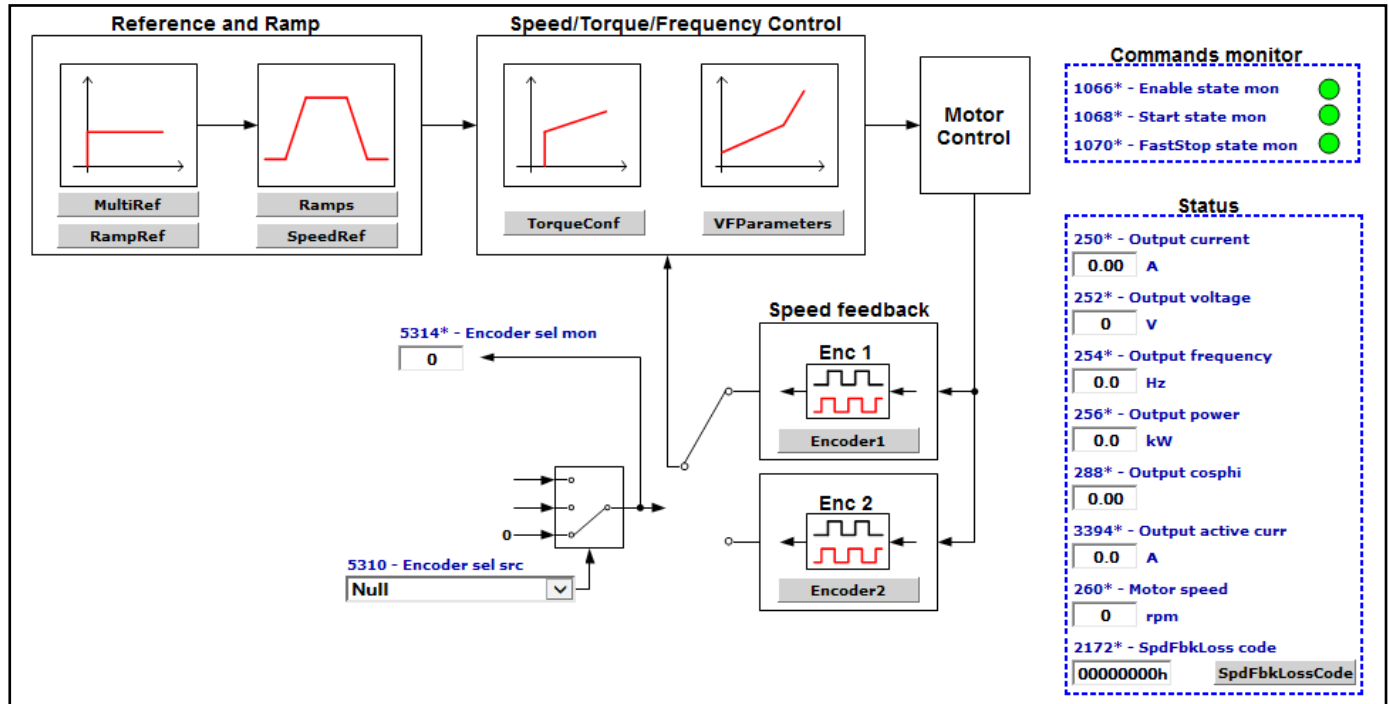
Note !

The drive is factory-set to control Asynchronous motors. To switch to Synchronous mode, send the **Load synch control** command (In menu 4 DRIVE CONFIG, first set PAR 554 **Access mode** = Expert, then again in menu 4 - DRIVE CONFIG, run parameter 6100 **Load synch control**). The drive is re-started (in this mode, reference should be made to the "ADV 200 – Field-oriented vector inverter for synchronous motors – Description of functions and list of parameters" guide on the CD supplied with the inverter or downloadable from the www.gefran.com website).

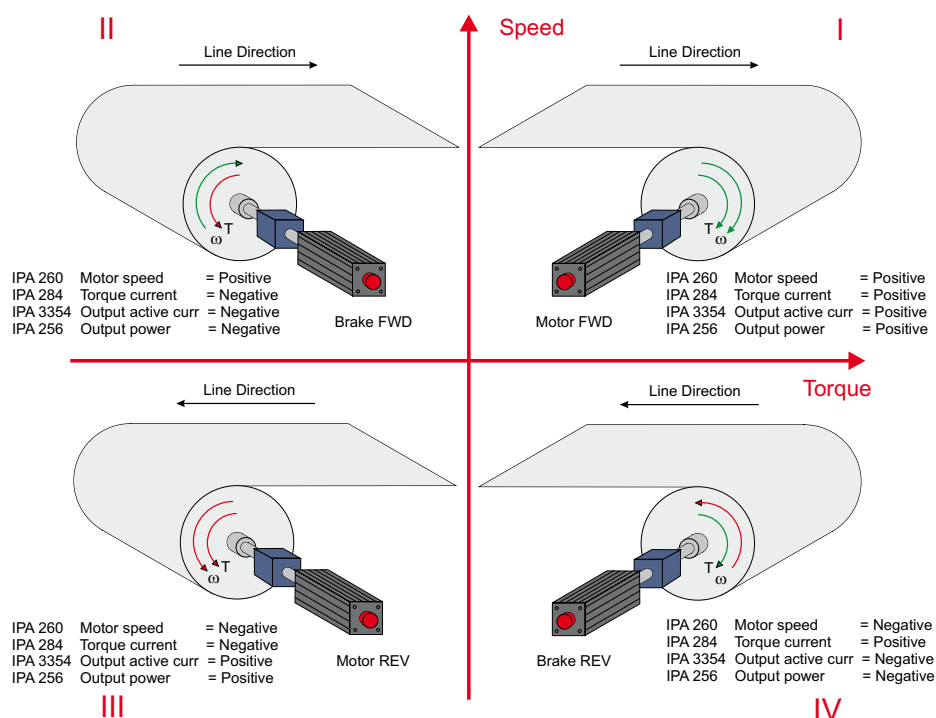
To return to Asynchronous motor control mode, send the **Load asynch control** command (PAR 6100). The drive is re-started to operate in the new mode.

1 – MONITOR

The monitor menu displays the measured values of the sizes and of the drive operating parameters.



Relationship between Speed-Torque-Power monitor parameters



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.1	250	Output current	A	FLOAT	16/32	0.0	0.0	0.0	R	FVS
The drive output current is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.2	252	Output voltage	V	FLOAT	16/32	0.0	0.0	0.0	R	FVS
The drive line voltage output is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.3	254	Output frequency	Hz	FLOAT	16/32	0	0	0	R	FVS
The drive output frequency is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.4	256	Output power	kW	FLOAT	16/32	0.0	0.0	0.0	R	FVS
Displays the drive output power.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.5	288	Output cosphi		FLOAT		0.0	0.0	0.0	ER	FVS
The cosphi value (for Asynchronous motor) is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.6	3394	Output active curr	A	FLOAT		0.0	0.0	0.0	ER	FVS
It is the active component (corresponding to the active electric power to the motor terminals) of the output current. It corresponds to the absolute value of the torque current. When the value is positive means that the motor is absorbing power from the drive (to develop motor torque). When the value is negative means that the motor is operating as a generator, that provides power to the drive (the motor is developing braking torque).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.7	628	Ramp setpoint	FF	INT16	16/32	0	0	0	R	FVS
The ramp reference is displayed. This is the speed value the drive must reach at the end of the ramp.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.8	664	Speed setpoint	FF	INT16	16/32	0	0	0	R	FVS
The speed reference is displayed. This is the value measured at the output of the speed reference circuit.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.9	260	Motor speed	FF	INT16	16/32	0	0	0	R	FVS
The actual output speed of the motor is displayed (in Flux vector CL = speed measured by the encoder, in Flux vector OL / V/f control = speed estimated by the drive).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.10	270	DC link voltage	V	FLOAT	16/32	0.0	0.0	0.0	ER	FVS
The direct voltage of the intermediate circuit capacitors is displayed (DC-Bus).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.11	272	Heatsink temperature	degC	INT16	16	0	0	0	ER	FVS
The temperature measured is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.12	290	Motor temperature	degC	FLOAT	16	0.0	0.0	0.0	ER	FVS
Displays motor temperature in °C based on type of sensor selected to manage the alarm. Equals 0 when direct conversion from count/ohm to °C is not possible, for example with PTC sensors.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.13	292	Sensor inp X mon	degC	FLOAT	16	0.0	0.0	0.0	ER	FVS
Display of temperature in degrees centigrade measured by KTY84 sensor connected to dedicated input of EXP-IO-SENS-100-ADV and EXP-IO-SENS-1000-ADV expansion cards.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.14	1544	An inp 1 temp mon	degC	FLOAT	16	0.0	0.0	0.0	ER	FVS
1.15	1594	An inp 2 temp mon	degC	FLOAT	16	0.0	0.0	0.0	ER	FVS
Display of temperature in degrees centigrade measured by KTY84 sensor connected to analog input 1 or 2 of control board.										
These parameters are on the L_TEMPCTRL selection list and can be assigned as selection to source parameter 6040 Liquid temp src .										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.16	1610	An inp 1X temp mon	degC	FLOAT	16	0.0	0.0	0.0	ER	FVS
1.17	1660	An inp 2X temp mon	degC	FLOAT	16	0.0	0.0	0.0	ER	FVS
Displays temperature in °C with PT100/PT1000/Ni1000 from input 1 (PAR 1610) or input 2 (PAR 1660) of EXP-IO-SENS-100-ADV or EXP-IO-SENS-1000-ADV card, regardless of how the motor overtemperature alarm is managed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.18	2342	Working load	perc	FLOAT		0.0	0.0	0.0	ER	F_S
Normal motor torque scaled according to setting of parameter Torque scale factor IPA 2340. This value is expressed in %.										
This parameter is obtained with the following formula:										
Scaled torque % = Torque % (IPA 2394) * 100 / Torque scale factor .										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.19	280	Torque current ref	A	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
The current reference used for torque control is displayed (in the Flux vector OL and Flux vector CL modes).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.20	282	Magnet current ref	A	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
The magnetizing current reference is displayed (in the Flux vector OL and Flux vector CL modes).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.21	284	Torque current	A	FLOAT	16/32	0.0	0.0	0.0	ER	FVS
The actual torque current value is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.22	286	Magnet current	A	FLOAT	16/32	0.0	0.0	0.0	ER	FVS
The actual magnetizing current value is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.23	3212	Motor overload accum	perc	UINT16	16/32	0	0	100	ER	FVS
The motor overload level is displayed (100% = alarm threshold).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.24	368	Drive overload accum	perc	UINT16	16/32	0	0	100	ER	FVS
The drive overload level is displayed. An instantaneous overload of 180% of the drive rated current is allowed for 3 s. The thermal image I ² t adjusts the drive output current thresholds. During normal operation, the instantaneous output current value can reach 180% of the drive rated current. After 0,5 s at 180%, the output current										

threshold is reduced to 160%. When the overload level **par. 368 Drive overload accum** reaches 100%, the output current threshold is reduced to 100% of the rated current, and stays at that value until the I²t integrator cycle is complete. At this point the 180% instantaneous overload is re-enabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.25	3260	Bres overload accum	perc	UINT16	16/32	0	0	100	ER	FVS

The used braking resistor overload limit is displayed (100% = alarm threshold).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.26	1066	Enable state mon		BIT	16	0	0	1	R	FVS

The drive Enable command status is displayed. Voltage must be present on terminal 7. The FR Forwardstart command is needed to start the inverter.

- 0 Disabled drive disabled
- 1 Enabled drive enabled

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.27	1068	Start state mon		BIT	16	0	0	1	R	FVS

The drive **Start** command status is displayed.

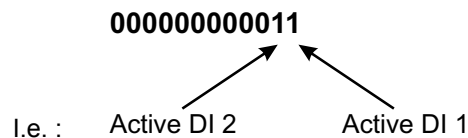
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.28	1070	FastStop state mon		BIT	16	0	0	1	R	FVS

The drive **FastStop** command status is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.29	1100	Digital input mon		UINT16	16	0	0	0	R	FVS

The status of the digital inputs on the drive is displayed. It can also be read via a serial line or fieldbus. The data are contained in a word, where each bit is 1 if voltage is supplied to the corresponding input terminal.

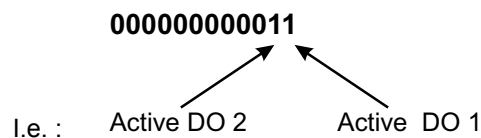
- 1 Input enabled.
- 0 Input disabled.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.30	1300	Digital output mon		UINT16		0	0	0	R	FVS

The status of the digital outputs on the drive is displayed. It can also be read via a serial line or fieldbus. The data are contained in a word, where each bit is 1 if voltage is supplied to the corresponding input terminal.

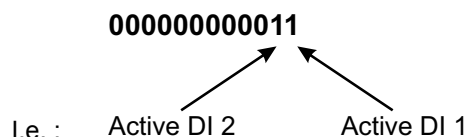
- 1 Output enabled.
- 0 Output disabled.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.31	1200	Digital input X mon		UINT16	16	0	0	0	R	FVS

The status of the digital inputs of the expansion card is displayed. It can also be read via a serial line or fieldbus. The data are contained in a word, where each bit is 1 if voltage is supplied to the corresponding input terminal. This parameter displays the state of the 16 external inputs. The 14 less significant bits are displayed from the keypad.

- 1 Input enabled.
- 0 Input disabled.

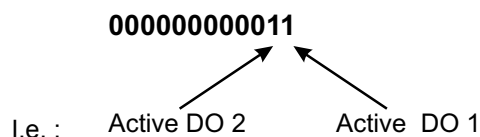


Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.32	1400	Digital output X mon		UINT16		0	0	0	R	FVS

The status of the digital outputs of the expansion card is displayed. It can also be read via a serial line or fieldbus. The data are contained in a word, where each bit is 1 if voltage is supplied to the corresponding input terminal.

1 Output enabled.

0 Output disabled.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.33	5400	Dig inp 0Ext mon		UINT16 32		0	0	4294967295	ER	FVS

This parameter displays the state of external inputs from 0 to 31 through the use of EXP-FL-XCAN-ADV optional card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.34	5402	Dig inp 1Ext mon		UINT16		0	0	4294967295	ER	FVS

This parameter displays the state of external inputs from 32 to 63 through the use of EXP-FL-XCAN-ADV optional card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.35	5450	Digital out 0Ext mon		UINT16		0	0	0	R	FVS

This parameter is used to read the state of external outputs from 0 to 31 through the use of EXP-FL-XCAN-ADV optional card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
1.36	5452	Digital out 1Ext mon		UINT16		0	0	0	R	FVS

This parameter is used to read the state of external outputs from 32 to 63 through the use of EXP-FL-XCAN-ADV optional card.

2 – DRIVE INFO

This menu displays the information for identifying and configuring the drive.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.1	480	Control type		ENUM		Asynchronous	0	0	R	FVS

The type of motor control mode is displayed.

- 1 Synchronous
- 2 Asynchronous

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.2	482	Drive size		UINT16		No Power	0	0	R	FVS

The drive size identification code is displayed.

Size code	Size text	Family code	Family text
1	0.75/1.5 kW	1	380V..480V
2	1.5/2.2 kW	1	380V..480V
3	2.2/3.0 kW	1	380V..480V
4	3.0/4.0 kW	1	380V..480V
5	4.0/5.5 kW	1	380V..480V
6	5.5/7.5 kW	1	380V..480V
7	7.5/11.0 kW	1	380V..480V
8	11.0/15.0 kW	1	380V..480V
9	15.0/18.5 kW	1	380V..480V
10	18.5/22.0 kW	1	380V..480V
11	22.0/30.0 kW	1	380V..480V
12	30.0/37.0 kW	1	380V..480V
12	30.0/37.0 kW	1	380V..480V
13	37.0/45.0 kW	1	380V..480V
13	37.0/45.0 kW	1	380V..480V
14	45.0/55.0 kW	1	380V..480V
14	45.0/55.0 kW	1	380V..480V
15	55.0/75.0 kW	1	380V..480V
15	55.0/75.0 kW	1	380V..480V
16	75.0/90.0 kW	1	380V..480V
16	75.0/90.0 kW	1	380V..480V
17	90.0/110.0 kW	1	380V..480V
17	90.0/110.0 kW	1	380V..480V
18	110.0/132.0 kW	1	380V..480V
18	110.0/132.0 kW	1	380V..480V
19	132.0/160.0 kW	1	380V..480V
19	132.0/160.0 kW	1	380V..480V
20	160.0/200.0 kW	1	380V..480V
20	160.0/200.0 kW	1	380V..480V
21	200.0/250.0 kW	1	380V..480V
21	200.0/250.0 kW	1	380V..480V
22	250.0/315.0 kW	1	380V..480V
22	250.0/315.0 kW	1	380V..480V
23	315.0/355.0 kW	1	380V..480V
23	315.0/355.0 kW	1	380V..480V
24	355.0/400.0 kW	1	380V..480V
25	400.0/500.0 kW	1	380V..480V
26	500.0/630.0 kW	1	380V..480V
27	630.0/710.0 kW	1	380V..480V
28	710.0/800.0 kW	1	380V..480V
29	0.9/1.0 MW	1	380V..480V
30	1.0/1.2 MW	1	380V..480V
1	75.0/90.0 kW	3	690V

2	90.0/110.0 kW	3	690V
3	110.0/132.0 kW	3	690V
4	132.0/160.0 kW	3	690V
5	160.0 kW	3	690V
6	200.0 kW	3	690V
7	250.0 kW	3	690V
8	315.0 kW	3	690V
9	355.0 kW	3	690V
10	400.0 kW	3	690V
11	500.0 kW	3	690V
12	630.0 kW	3	690V
13	710.0 kW	3	690V
14	800.0 kW	3	690V
15	1000.0 kW	3	690V
16	1200.0 kW	3	690V
17	160.0/200.0 kW	3	690V
18	200.0/250.0 kW	3	690V
19	250.0/315.0 kW	3	690V
20	315.0/355.0 kW	3	690V
21	355.0/400.0 kW	3	690V
22	400.0/500.0 kW	3	690V
23	500.0/630.0 kW	3	690V
24	630.0/710.0 kW	3	690V
25	710.0/800.0 kW	3	690V
26	0.9/1.0 MW	3	690V
27	1.0/1.2 MW	3	690V
28	1.35/1.5 MW	3	690V
29	1.65/1.8 MW	3	690V

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.3	484	Drive family		ENUM		No Power	0	0	RS	FVS

The available mains voltage is displayed (e.g. 380V...480V for mains 400V). The undervoltage alarm refers to this voltage value.

The condition **No power** occurs when the regulation board does not recognize the power board because not set up properly. The configuration adjustment of a new regulation board is achieved by linking it to a power board and running a **Save parameters**.

- 0 No Power
- 1 380V...480V
- 2 500V...575V
- 3 690V
- 4 230V
- 5 380V..480V LC (ADV200-LC)

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.4	486	Drive region		ENUM		EU	0	1	R	FVS

The geographical area (Europe or USA) is displayed. The factory settings for the power supply voltage and frequency used by the drive are defined accordingly.

	ADV200-4	ADV200-6
0	EU (400V / 50Hz)	EU (690V / 50Hz)
1	USA (460V / 60Hz)	USA (690V or 575V / 60Hz)

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.5	488	Drive cont current	A	FLOAT		CALCF	0.0	0.0	RZS	FVS

The current that the drive can deliver continuously according to size, supply voltage and programmed switching frequency is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.6	490	Firmware ver.rel		UINT16		0	0	0	R	FVS
The version and release number of the firmware used in the drive are displayed. On the keypad they are displayed in the format version.release. When the parameter is read via serial line or fieldbus the version is returned in the high byte and the release in the low byte.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.7	496	Firmware type		UINT16		0	0	0	R	FVS
The type of firmware installed in the drive is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.8	504	Application ver.rel		UINT16		0	0	0	ER	FVS
The version and release number of the MDPIc application used in the drive are displayed. On the keypad these are displayed in version.release format. When the parameter is read via serial line or fieldbus the version is returned in the high byte and the release in the low byte.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.9	506	Application type		UINT16		0	0	0	ER	FVS
The type of application currently used by the drive is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.10	508	Application subver		UINT16		0	0	0	ER	
The Revision Index of the application currently used by the drive is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.11	510	Time drive power on	h.min	UINT32		0	0.0	0.0	ER	FVS
The total time for which the drive has been powered is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.12	512	Time drive enable	h.min	UINT32		0	0.0	0.0	ER	FVS
The time for which the enable hardware contact on the drive has been connected is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.13	514	Number power up		UINT16		0	0	0	ER	FVS
The number of times the drive has been powered on is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.14	516	Time fan on	h.min	UINT32		0	0	0	ER	FVS
The total operating time of the drive fan is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.15	526	Power file ver.rel		UINT16		0	0	0	ER	FVS
The version number and release number of the drive power card are displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.16	530	Slot 1 card type		ENUM		None	0	0	R	FVS
2.17	532	Slot 2 card type		ENUM		None	0	0	R	FVS
2.18	534	Slot 3 card type		ENUM		None	0	0	R	FVS
The type of expansion card installed in the relative slot of the drive is displayed.										
0 None										

1	I/O 0	
769	I/O 1	(EXP-IO-D6A4R1-ADV)
1793	I/O 2	
2305	I/O 3	
3329	I/O 4	
1544	Enc 1	(EXP-DE-I1R1F2-ADV)
1800	Enc 2	(EXP-SE-I1R1F2-ADV)
520	Enc 3	(EXP-SESC-I1R1F2-ADV)
776	Enc 4	(EXP-EN/SSI-I1R1F2-ADV)
1032	Enc 5	(EXP-HIP-I1R1F2-ADV)
2056	Enc 7	(EXP-DE-I2R1F2-ADV)
4	Can/Dnet	(EXP-CAN-ADV)
260	Profibus	(EXP-PDP-ADV)
516	RTE	(EXP-ETH-...)
576	FastLink	
320	I/O Ext	
832	I/O FastLink	(EXP-FL-XCAN-ADV)
255	Unknown	
2312	Enc 8	(EXP-ASC-I1-ADV)
1288	Enc 6	(EXP-RES-I1R1-ADV)
5633	I/O 6	(EXP-IO-SENS-1000-ADV)
6401	I/O 7	(EXP-IO-D5R8-ADV)
7681	I/O 8	(EXP-IO-SENS-100-ADV)

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.19	546	Fw enc sl2 ver.rel		UINT16		0	0	0	R	FVS

The version and release number of the firmware installed on the encoder (mounted in slot 2) used in the drive are displayed. When the parameter is read via serial line or fieldbus the version is returned in the high byte and the release in the low byte.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.20	548	Fw enc sl2 type		UINT16		0	0	0	R	FVS

The version of firmware on the encoder card mounted in slot 2 is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.21	5300	Fw enc sl1-3 ver.rel		UINT16		0	0	0	R	FVS

The version and release number of the firmware on the encoder card (mounted in slot 1 or 3) used in the drive are displayed. When the parameter is read via serial line or fieldbus the version is returned in the high byte and the release in the low byte.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.22	5302	Fw enc sl1-3 type		UINT16		0	0	0	R	FVS

The version of firmware on the encoder card mounted in slot 1 or 3 is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.23	5724	Fw FastLink ver.rel		UINT16		0	0	0	ER	FVS

The version and release number of the FastLink card firmware installed in the drive are displayed.

When the parameter is read via serial line or fieldbus the version is returned in the high byte and the release in the low byte.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
2.24	5726	Fw FastLink type		UINT16		0	0	0	ER	FVS

The type of FastLink card firmware installed in the drive is displayed.

3 – STARTUP WIZARD

The startup wizard menu suggests a procedure for commissioning the drive quickly with a reduced number of settings. Advanced customization requires the use of the single parameters relating to the specific performance levels. See the procedure described in the chapter 7.1 **Startup wizard** on ADV200 QS manual.

4 – DRIVE CONFIG

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.1	550	Save parameters		BIT		0	0	1	RW	FVS

Any changes to parameter values immediately affect drive operations, but are not automatically saved in the permanent memory.

The “Save Parameters” command is used to save current parameter values in the permanent memory.

Any changes that are not saved will be lost when the drive is switched off.

To save parameters follow the procedure described in **STEP 6** of the **Startup wizard**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.2	552	Regulation mode		ENUM		V/f control	0	3	RWZ	FVS

The ADV200 is capable of operating with different control modes:

- 0 V/f control
- 1 Flux vector OL
- 2 Flux vector CL
- 3 Autotune

The open loop **V/f (V/f control)** mode is the simplest type of asynchronous motor control, as the only parameters required are the rated voltage, current and frequency of the motor.

The open loop V/f control mode is factory-set and does not require any speed feedback. The natural variation in speed generated by machine load induction (slippage) can be compensated using **Slip comp** and **Slip comp filter**.

In V/f mode a single drive can be used to control several asynchronous motors, even of different sizes, connected in parallel, provided the sum of the currents of the single motors is less than the drive rated current. If using several motors connected in parallel, be sure to provide adequate thermal protection for each single motor.

Closed loop control is also possible in the V/f mode. It requires a speed reading by a digital encoder on the motor shaft; to enable encoder feedback, you must set parameter **2444 Slip comp mode =1**. The optional EXP-ENC card is necessary in order to acquire the encoder signals. The speed feedback supplied by the encoder is used to compensate motor slippage in the different load conditions, to achieve accurate control and greater precision of the actual motor speed.

With the **sensorless vector control (Flux vector OL)** mode, fine precision can be achieved at low motor rpm. The drive has a algorithm that uses a self-tuning procedure to obtain all the electric measurements of the motor. This allows the speed and position of the motor shaft to be estimated, enabling operation similar to that of a drive with feedback, both in terms of the response in torque to load variations, and of the regularity of rotation even at low rpm.

In the **field oriented vector mode (Flux vector CL)** an encoder is required for closed loop feedback. With this mode it is possible to achieve extremely high dynamic responses thanks to the regulation bandwidth, maximum torque even with the rotor blocked, speed and torque control. Numerous regulation parameters can be used to adjust the drive to each specific application, for instance adaptive gains, system inertia compensation, etc..

Autotune mode enables self-tuning of motor parameters when the **STARTUP WIZARD** is not used. This command can only be executed after enabling the drive by opening the hardware contact between terminals 7 and S3. Then set the **Regulation mode** parameter to **Autotune**. Next, if the drive is not already in Local mode, press the **Local** key (the **LOC** LED will light up) and re-close the hardware enabling contact (terminals 7 and S3). Self-tuning can now be enabled (see parameters 2022 or 2224). When self-tuning is complete, open the hardware contact between terminals 7 and S3 and restore any parameters that have been changed.

This procedure must be used for both self-tuning with the engine standing still and with the motor turning with **Flux vector CL** mode. Motor parameter self-tuning is possible with **Flux vector OL** mode.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.3	554	Access mode		ENUM		Easy	0	1	RW	FVS

With this parameter you can restrict access to advanced configuration.

- 0 Easy
- 1 Expert

The **Easy** mode gives access to a list of parameters that can be used for rapid drive commissioning. This type of configuration is suitable for the majority of applications.

Setting the parameter to **Expert** gives access to all the parameters in the firmware. This mode allows an extremely high level of customization to be achieved in order to exploit the potential of the ADV200 to the full.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.4	558	Application select		ENUM		None	0	2	ERWZ	FVS

Selection of which IEC 61131-3-compliant MDPIc application.

For Drive Size 7 and parallel units, "S1" Switch mounted on R-PSM board define the **Undervoltage** threshold level. It must be set as the configuration in PAR 560.

- 0 None
- 1 Application 1
- 2 Application 2

The drive is supplied already incorporating a number of applications developed in the IEC 61331-3 environment. To use these, set the desired application, run save parameter, switch the drive off and then on again.

NOTE! The **Load Default** command (par. 580) does not modify this parameter

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.5	560	Mains voltage		ENUM		400 V	SIZE	SIZE	ERWZS	FVS

Setting of the available mains voltage value in Volts. Detection of the undervoltage alarm refers to this value.

- 0 None
- 1 230 V
- 2 380 V
- 3 400 V
- 4 415 V
- 5 440 V
- 6 460 V
- 7 480 V
- 8 500 V
- 9 575 V
- 10 690 V

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.6	586	DC supply		ENUM		None	0	3	ERWZS	FVS

Selection of the voltage applied to the DC link if the drive is powered by an AC/DC power supply unit, whether standard or regenerative (e.g. AFE200). If a value of other than "**None**" is selected, all parameters that depend on **Mains voltage** (PAR 560) are calculated on the basis of the voltage shown in the table below, while the value of PAR 560 **Mains voltage** is set automatically.

If "None" is selected, these parameters are calculated according to the value of parameter 560 **Mains voltage**.

	DC power supply	Drive family 380V..480V Mains voltage	Drive family 690V Mains voltage
0	None	Use P560	Use P560
1	540 V (380-480V)	400 V	N/A
2	650 V (380-480V)	460 V	N/A

	DC power supply	Drive family 380V..480V Mains voltage	Drive family 690V Mains voltage
3	750 V (380-480V)	460 V	N/A
10	675 V (690V)	N/A	500 V (if compatible with the size, otherwise N/A)
11	810 V (690V)	N/A	575 V (if compatible with the size, otherwise N/A)
12	935 V (690V)	N/A	690 V
13	1120 V (690V)	N/A	690 V

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.7	450	Undervoltage	V	FLOAT		CALCF	CALCF	CALCF	ERWZS	FVS

Setting of the drive minimum operating voltage. The maximum and minimum default values are calculated automatically by the drive according to the value set in parameter 560 **Mains voltage**, as shown in the table below.

Table of undervoltage limits

	Mains voltage	Def	Min	Max
0	None	(Vdc)	(Vdc)	(Vdc)
1	230 V	225	200	282
2	380 V	372	330	466
3	400 V	392	330	490
4	415 V	407	360	509
5	440 V	431	382	539
6	460 V	451	400	564
7	480 V	470	417	588
8	500 V	490	434	613
9	575 V	563	500	705
10	690 V	676	600	846

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.8	562	Switching frequency		ENUM		SIZE	SIZE	SIZE	ERWS	FVS

Setting of the switching frequency value in kHz. The maximum value that can be set depends on the size of the drive.

- 0 1 kHz
- 1 2 kHz
- 2 4 kHz
- 3 6 kHz
- 4 8 kHz
- 5 10 kHz
- 6 12 kHz
- 7 16 kHz

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.9	564	Ambient temperature		ENUM		40 degC	0	1	ERWZ	FVS

Setting of the ambient temperature value. This parameter is used to set the output current derating factor (1% for every °C above 40°C).

- 0 40 degC The inverter is capable of delivering direct current continuously with ambient temperatures of up to 40°C.
- 1 50 degC The inverter is capable of delivering direct current continuously with ambient temperatures of up to 50°C.

If the value is set to 1 the drive output current will be 10% less than the rated current at 40°C.

Installation altitude above sea level	Output Current derating factor at Ambient Temperature of:						
	20°C	25°C	30°C	35°C	40°C	45°C	50°C
0 ... 1000 m	100%					85%	90%

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.10	566	Drive overload mode		ENUM		Heavy duty	1	2	ERWZ	FVS

Setting of the current overload that can be supplied by the drive, depending on the application.

- 1 Heavy duty
- 2 Light duty

Set **Heavy duty** when a large overload is requested:

- (asynchronous motor control) the drive can supply 180% of the rated current for 0,5 seconds and 150% for 1 minute every 5 minutes.
- (synchronous motor control) the drive can supply 200% of the rated current for 3 seconds and 160% for 1 minute every 5 minutes,

Select **Light duty** to enable the drive to deliver a current of 110% of the rated current for 1 minute every 5 minutes.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.11	568	Switching freq mode		ENUM		Costant	0	1	ERWZS	FVS

Setting of the switching frequency operating mode.

The factory switching frequency setting is 4 kHz for motors between 2.2 kW and 37 kW (the factory switching frequency setting for smaller drives is 8kHz); this value may result in increased noise. Setting a higher switching frequency will increase drive losses and thus increase the heatsink temperature, but it will also reduce noise. To combine the advantages of both settings, with the ADV drive the heatsink temperature can be controlled by reducing the switching frequency if it increases.

- 0 Costant
- 1 Variable

If set to **Constant**, the switching frequency is fixed and set with the **Switching freq mode** parameter according to the size of the drive. If the selected switching frequency is higher than the default value, the drive output current is derated.

If set to **Variable**, the switching frequency is set to 8 kHz (for sizes between 2.2 kW and 37 kW / lower values are defined for more powerful drives) and the drive heat sink temperature and output frequency values are also controlled. If the heat sink temperature exceeds a given threshold (which depends on the size of the drive) or the output frequency falls to less than 5 Hz, the switching frequency is automatically reduced to 4 kHz (again considering sizes of between 2.2 kW and 37 kW), to avoid any derating of the output current value. (When the output frequency exceeds 7 Hz the switching frequency is brought back to 8 kHz). The switching frequency is reduced in a single step.

With this setting the switching frequency value selected in the Switching frequency parameter is ineffective.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.12	454	Chopper ON	V	FLOAT		CALCF	CALCF	CALCF	ERWZS	FVS

Corresponding to the threshold of activation of the braking resistor. It is so possible to increase this value just below the **Overvoltage** threshold level (ADV200 -4: 820 Vdc, ADV200 -6: 1192 Vdc).

Parameter's range are defined thru IPA 560 **Mains voltage** setting

Note!

If **Mains voltage** is set at the maximum possible value, the activation threshold of the braking resistor can only assume the max value and can not be changed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.13	570	Password		UINT32		0	0	99999	ERW	FVS

You can enter a **password** to protect the parameters from unauthorized tampering: the password can consist of a combination of a maximum of any 5 figures that can be selected by the user. All parameters are locked, except this one and **Save parameters**.

After entering the password, press the E key once to enter it into the memory and again to enable it (= Enabled is displayed to indicate that the password is enabled).

So that the password remains valid even after switching the unit off and then switching it back on, save it using the **Save parameters** command.

When the password is enabled any attempts to modify a parameter are blocked and the **Password enabled** message is displayed.

To disable the password, enter the **Password** parameter (572) in the **DRIVE CONFIG** menu.

Check that the password is enabled (**Enabled**), press **E** and enter the combination of figures that make up the password.

Press E again. A message is displayed telling you the password is no longer enabled (**Disabled**).

To make sure the password continues to be disabled even after switching the unit off and then switching it back on, save this configuration using the **Save parameters** command.

When an incorrect password is entered, the Password wrong message is displayed

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.14	572	Application key	UINT32		0	0	4294967295	ERW	FVS	

This parameter can be used to enter the key for enabling the MDPIc application.

You may need to enter a key to definitively enable some applications. Please contact Gefran for details about which applications require the key.

If executing an application that envisages a key verification and the key is incorrect, enabling is forced for 200 hours (time drive enabled).

In this phase a message is displayed informing you that the period of forced enabling time is about to expire.

At the first power-on after the 200 hours an alarm is generated and the application does not start.

Please contact Gefran for the numerical value of the key.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.15	574	Startup display		INT16		-1	-1	20000	ERW	FVS

This is used to set the parameter that will be displayed automatically at drive power-on. Entering the value -1 (default),

-1 the function is disabled and the main menu is displayed at power-on.

0 Displays "DISP" menu parameters (monitor of inverter output variables: voltage, current, frequency, speed, etc.). This menu can also be displayed by pressing the DISP key on the keypad.

1 Displays RECIPE menu parameters.

X Any existing PAR (IPA).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.16	576	Display backlight		BIT		0	0	1	ERW	FVS

Enabling of the backlight on the drive display.

If set to 0 the display backlight will go off when the drive has been on for three minutes.

If set to 1 the backlight will stay on for as long as the drive is powered.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.17	578	Language select		ENUM		English	0	9	RWZ	FVS

Setting of the drive programming language.

0 English

1 Italian

2 French

3 German

4 Spanish

5 Polish

6 Romanian

7 Russian

8 Turkish

9 Portuguese

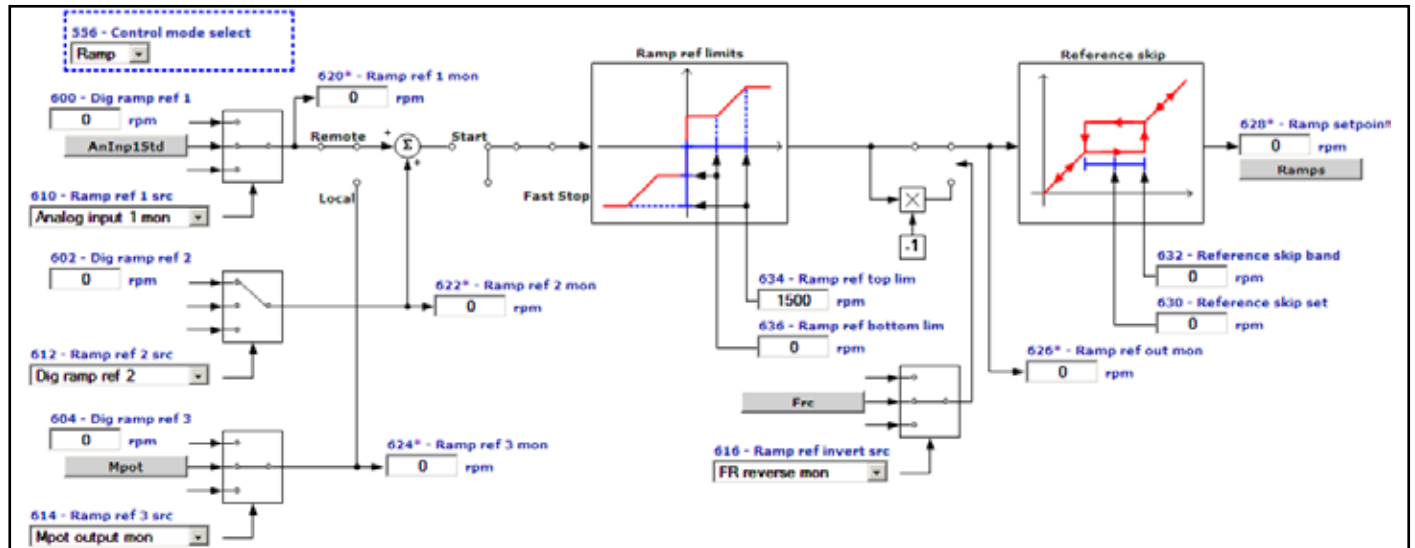
Note ! The **Load Default** command (par. 580) does not modify this parameter.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.18	580	Load default		BIT		0	0	1	RWZ	FVS
Transfers the standard factory settings to the drive memory ("Def" column in the parameters table).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.19	590	Save par to keypad		BIT		0	0	1	RW	FVS
Transfers the parameters currently stored in the drive and saves them in the keypad memory (See ADV200 Quick Start manual, chapter 6.8).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.20	592	Load par from keypad		BIT		0	0	1	RWZ	FVS
Transfers the parameters from the keypad memory to the drive (See ADV200 Quick Start manual, chapter 6.9).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.21	594	Keypad memory select		UINT16		1	1	5	ERW	FVS
Selection of the area of the keypad memory to which to transfer and save the parameters stored in the drive.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.22	6100	Load synch control		BIT		0	0	1	ERW	F_S
This command is sent to switch to Synchronous motor control mode. A message prompting you to confirm the command is displayed on the keypad, as the drive must be re-started to enable the new mode.										

5 – REFERENCES

ADV drives are provided with a speed regulation circuit, which can be adapted to suit the various applications. In the standard version, the regulator has PI behaviour and the regulator parameters are the same for the entire field of regulation.

Different sources can be used for the speed and torque references, depending on how the **554 Control mode select** parameter is set.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.1	600	Dig ramp ref 1	FF	INT16	16/32	0	CALCI	CALCI	RW	FVS

Setting of the digital ramp reference. The speed that the drive must reach after completing the acceleration phase is set with the ramp reference. Variations in the ramp reference are made with the selected ramp times. The size of the ramp reference determines the motor speed value. The sign determines the direction of rotation. The **Ramp ref** parameter also refers to a minimum speed, if set. When the “**Motor potentiometer**” or “**Multispeed**” functions are selected the relative references are used. This reference can only be used in the **Remote** mode.

The overall ramp reference is the result of the sum of the values with the **Ramp ref 1** and **Ramp ref 2** sign.

Example 1: **Ramp ref 1** = + 500 rpm **Ramp ref 2** = + 300 rpm
Ramp ref = 500 rpm + 300 rpm = 800 rpm

Example 2: **Ramp ref 1** = + 400 rpm **Ramp ref 2** = - 600 rpm
Ramp ref = 400 rpm – 600 rpm = - 200 rpm

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.2	602	Dig ramp ref 2	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS

Setting of the digital ramp reference. The speed that the drive must reach after completing the acceleration phase is set with the ramp reference. Variations in the ramp reference are made with the selected ramp times. The size of the ramp reference determines the motor speed value. The sign determines the direction of rotation. The **Ramp ref** parameter also refers to a minimum speed, if set. When the “**Motor potentiometer**” or “**Multispeed**” functions are selected the relative references are used.

In **Remote** mode the overall ramp reference is the result of the sum of the values with the Ramp ref 1 and Ramp ref 2 sign.

Example 1: **Ramp ref 1** = + 500 rpm **Ramp ref 2** = + 300 rpm
Ramp ref = 500 rpm + 300 rpm = 800 rpm

Example 2: **Ramp ref 1** = + 400 rpm **Ramp ref 2** = - 600 rpm
Ramp ref = 400 rpm – 600 rpm = - 200 rpm

In **Local** mode the overall ramp reference is the result of the sum of the values with the **Ramp ref 3** and **Ramp ref 2** sign.

Example 1: **Ramp ref 3** = + 500 rpm **Ramp ref 2** = + 300 rpm
Ramp ref = 500 rpm + 300 rpm = 800 rpm

Example 2: **Ramp ref 3** = + 400 rpm **Ramp ref 2** = - 600 rpm
Ramp ref = 400 rpm – 600 rpm = - 200 rpm

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.3	604	Dig ramp ref 3	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS

Setting of the digital ramp reference. The speed that the drive must reach after completing the acceleration phase is set with the ramp reference. Variations in the ramp reference are made with the selected ramp times. The size of the ramp reference determines the motor speed value. The sign determines the direction of rotation. The **Ramp ref** parameter also refers to a minimum speed, if set. When the “**Motor potentiometer**” or “**Multispeed**” functions are selected the relative references are used. This reference can only be used in the **Local** mode.

The overall ramp reference is the result of the sum of the values with the **Ramp ref 3** and **Ramp ref 2** sign.

Example 1: **Ramp ref 3** = + 500 rpm **Ramp ref 2** = + 300 rpm
Ramp ref = 500 rpm + 300 rpm = 800 rpm

Example 2: **Ramp ref 3** = + 400 rpm **Ramp ref 2** = - 600 rpm
Ramp ref = 400 rpm – 600 rpm = - 200 rpm

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.4	610	Ramp ref 1 src		LINK	16/32	1500	0	16384	RW	FVS
5.5	612	Ramp ref 2 src		LINK	16/32	602	0	16384	ERW	FVS
5.6	614	Ramp ref 3 src		LINK	16/32	894	0	16384	ERW	FVS

Selection of the origin (source) of the reference signals on the input of the ramp function block, that defines the main drive speed. The ramp reference values can be selected from among those listed in the “**L_MLTREF**” selection list.

When assigning the reference via terminals, signals with ±10V, 0 ...10V, 0... 20 mA and 4 ... 20 mA can be used.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.7	616	Ramp ref invert src		LINK	16	1050	0	16384	ERW	FVS

Selection of the origin (source) of the signal that inverts the ramp reference output from the “Ramp ref” block. The signal that can be used for this function can be selected from among those listed in the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.8	620	Ramp ref 1 mon	FF	INT16		0	0	0	R	FVS
5.9	622	Ramp ref 2 mon	FF	INT16		0	0	0	ER	FVS
5.10	624	Ramp ref 3 mon	FF	INT16		0	0	0	ER	FVS

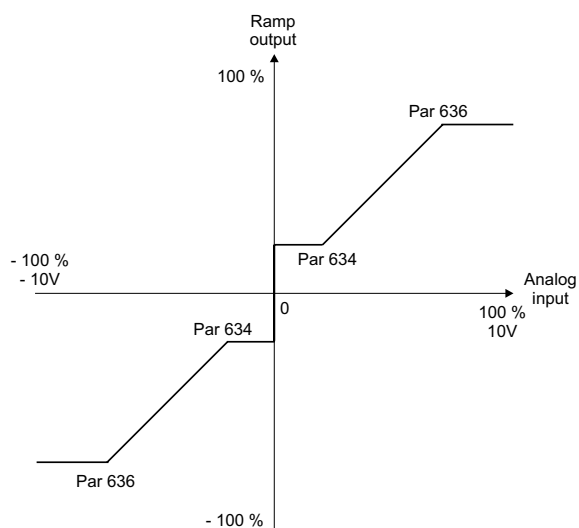
The value of the relative ramp reference on the output of the relative function block is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.11	634	Ramp ref top lim	FF	INT32		0	0	CALCI	ERWZ	FVS

It defines the maximum value of the output of the ramp reference block, regardless of the signal that is present. The ramp reference follows the reference signal from the value set in parameter PAR 636 **Ramp ref bottom lim** up to the value set with this parameter, after which the motor speed remains constant. The limit is valid for both directions of rotation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.12	636	Ramp ref bottom lim	FF	INT32		0	0	CALCI	ERWZ	FVS

It defines the minimum value of the output of the ramp reference block, regardless of the signal that is present. The ramp block output remains at the value set with this parameter until the analog signal exceeds this threshold: the ramp output value then starts to follow the reference up to the value set in parameter PAR 634 **Ramp ref top lim**. The limit is valid for both directions of rotation.

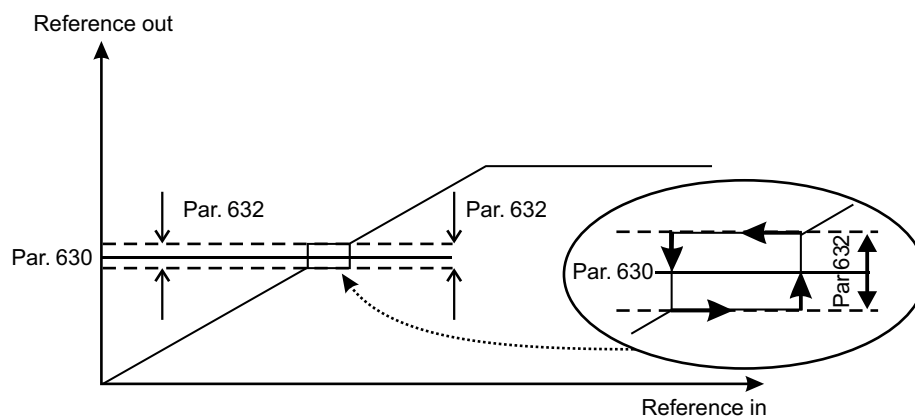


Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.13	630	Reference skip set	rpm	INT16		0	0	CALCI	ERW	FVS

Setting of the prohibited speed threshold at which the drive cannot operate.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.14	632	Reference skip band	rpm	INT16		0	0	CALCI	ERW	FVS

Setting of the prohibited bandwidth.



Example:

A) Increase in the reference by values of less than **Par. 630**

Par. 630 = 300 rpm (prohibited speed threshold)

Par. 632 = 10 rpm (thus prohibited band: 290rpm..310rpm)

Set speed reference = 295 rpmHz

Output speed = 290 rpm

Set speed reference = 305 rpm

Output speed = 290 rpm

B) Decrease in the reference by values above *Par. 630*

Par.630 = 300 rpm (prohibited speed threshold)

Par.632 = 10 rpm (thus tolerance band: 290 rpm...310 rpm)

Set speed reference = 305 rpm

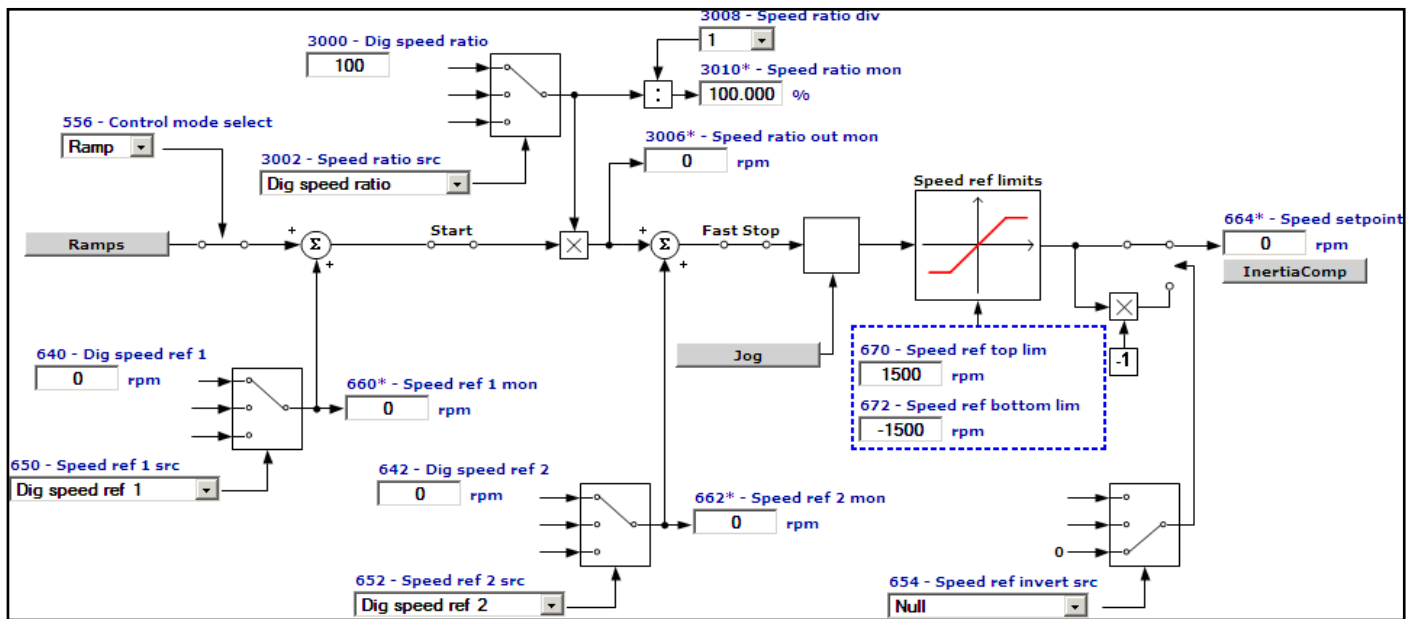
Output frequency = 310 rpm

Set speed reference = 295 rpm

Output frequency = 310 rpm

The user can thus set any reference value, but if the set value is within the prohibited range, the drive automatically maintains the speed outside the limits defined by the tolerance band.

During ramp phases the prohibited speed is passed freely and there are no points of discontinuity in the generation of the output frequency.



The speed reference supplies the desired speed to the drive, which directly follows the reference pattern. This only happens when the available torque is sufficient. In this case the drive functions at its current limit, until reaching the set speed. The speed reference value determines the motor speed value. The sign determines the direction of rotation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.15	640	Dig speed ref 1	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS
5.16	642	Dig speed ref 2	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS

Setting of the digital speed references. The overall speed reference is the result of the sum of the values with the respective signs, of **Dig speed ref 1** and **Dig speed ref 2**. The digital speed references are linked to the ramp circuit output.

The overall speed reference is the result of the sum of the values, with sign, of **Speed ref 1** and **Speed ref 2**.

Example 1: **Speed ref 1** = + 500 rpm **Speed ref 2** = + 300 rpm
Speed ref = 500 rpm + 300 rpm = 800 rpm

Example 2: **Speed ref 1** = + 400 rpm **Speed ref 2** = - 600 rpm
Speed ref = 400 rpm – 600 rpm = - 200 rpm

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.17	650	Speed ref 1 src		LINK	16/32	640	0	16384	ERW	FVS
5.18	652	Speed ref 2 src		LINK	16/32	642	0	16384	ERW	FVS

Selection of the origin (source) of the drive speed reference signals. The values that can be used as speed

references can be selected from those listed in the “**L_MLTREF**” selection list.

When assigning the reference via terminals, signals with $\pm 10V$, 0 ... 10V, 0... 20 mA and 4 ... 20 mA can be used.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.19	654	Speed ref invert src		LINK	16	6000	0	16384	ERWZ	FVS

Selection of the origin (source) of the signal that inverts the speed reference output from the regulator. The terminal that can be used for this function can be selected from among those listed in the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.20	660	Speed ref 1 mon	FF	INT16		0	0	0	ER	FVS
5.21	662	Speed ref 2 mon	FF	INT16		0	0	0	ER	FVS

The value of the relative speed reference is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.22	670	Speed ref top lim	FF	INT32		CALCI	0	CALCI	ERWZ	FVS

Setting of the upper speed reference limit. If the speed reference exceeds the limits, the motor speed remains at the set limit value in any case. Speed limits cannot be more than 200% of the value set in the **Full scale speed** parameter (REFERENCES menu par. 680).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.23	672	Speed ref bottom lim	FF	INT32		CALCI	CALCI	0	ERWZ	FVS

Setting of the lower speed reference limit. If the speed reference exceeds the limits, the motor speed remains at the set limit value in any case. Speed limits cannot be more than 200% of the value set in the **Full scale speed** parameter (REFERENCES menu par. 680).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.24	666	Speed ref filter	ms	UINT16		0	0	1000	ERW	FVS

Setting of the filter to the speed reference value. If IPA 666 **Speed ref filter** is set to 0, filter is disabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.25	680	Full scale speed	rpm	INT16		CALCI	50	32000	RWZ	FVS

Setting of the reference value for all speed percentage data (References, Speed adaptives ...) corresponding to 100 % of the actual speed. This parameter can only be changed with the inverter blocked (Enable drive = Disabled). The recommended setting for the value of this parameter is the motor rated speed. If altered, the self-tuning procedure should be repeated.

Full scale speed does not define the maximum possible speed. In any case, the maximum speed percentage value is ± 200 % of the **Full scale speed** value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.26	222	Theta ref src		LINK	16/32	220	0	16384	ERW	F_S

Selection of the origin (source) of the flux reference. It requires the use of the EXP-FL-XCAN-ADV option and it is needed to manage multi-windings asynchronous motors.

Additional technical informations are available through the Quick startup manual.

Value can be selected from among those listed in the “**L_MLTREF**” selection list.

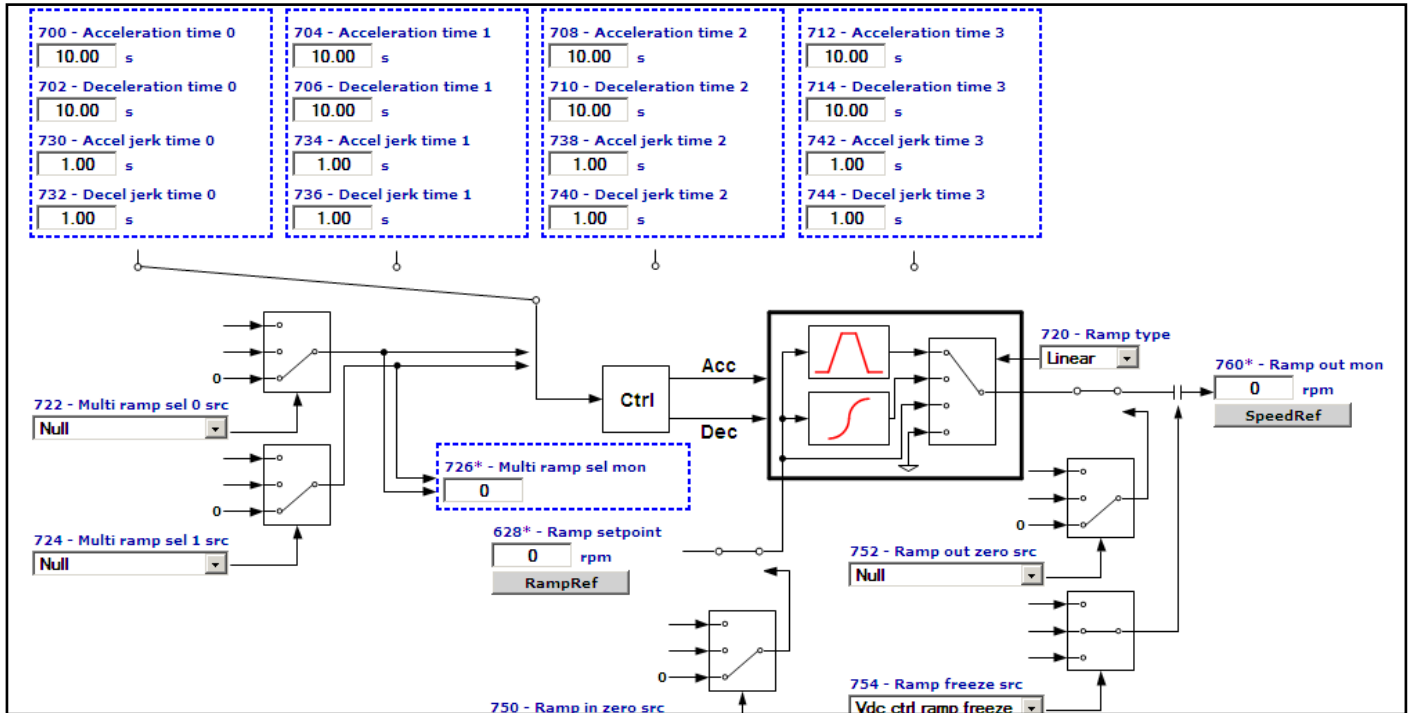
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
5.27	226	Flux ref src		LINK	16/32	224	0	16384	ERW	F_S

Selection of the origin (source) of electrical angle of the motor. It requires the use of the EXP-FL-XCAN-ADV option and it is needed to manage multi-windings asynchronous motors.

Additional technical informations are available through the Quick startup manual.

Value can be selected from among those listed in the “**L_MLTREF**” selection list.

6 – RAMPS



The ramp (reference integrator) determines the acceleration and deceleration times of the drive. Times can be set independently.

The ramp times of Fast stop command are set on **Acceleration time 3** and **Deceleration time 3**. The command can be enabled from the terminal strip..

The ramp can be linear or S-shaped, as preferred.

The references can be set in different ways:

- with the Ramp ref 1 and / or Ramp ref 2 references
- with the Multi speed function
- with the Motor potentiometer function
- with the Jog function

The ramp generator can be used in the “stand alone” mode. When disabled (**Ramp type = Off**), the “Enable drive, Start/Stop and Fast stop” commands do not affect the ramp generator. In this condition the ramp generator can be used separately.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.1	700	Acceleration time 0	s	FLOAT		10.00	0.01	1000.00	RW	FVS
6.2	702	Deceleration time 0	s	FLOAT		10.00	0.01	1000.00	RW	FVS
6.3	704	Acceleration time 1	s	FLOAT		10.00	0.01	1000.00	ERW	FVS
6.4	706	Deceleration time 1	s	FLOAT		10.00	0.01	1000.00	ERW	FVS
6.5	708	Acceleration time 2	s	FLOAT		10.00	0.01	1000.00	ERW	FVS
6.6	710	Deceleration time 2	s	FLOAT		10.00	0.01	1000.00	ERW	FVS
6.7	712	Acceleration time 3	s	FLOAT		10.00	0.01	1000.00	ERW	FVS
6.8	714	Deceleration time 3	s	FLOAT		10.00	0.01	1000.00	ERW	FVS

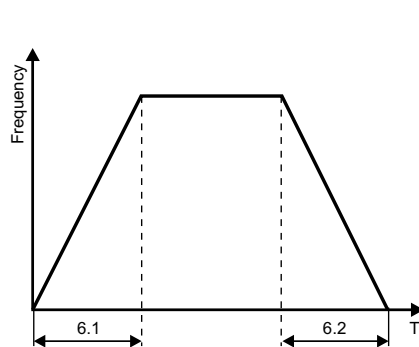
The acceleration and deceleration ramp times are used to avoid sudden changes in the drive output frequency, which could cause mechanical shocks, excessive current on the motor and excessive DC-bus voltage values. The acceleration times (6.1, 6.3, 6.5, 6.7) are expressed as the time necessary to bring the frequency from

zero to the maximum value set in the **Full scale speed (5.22)**. On the other hand, the deceleration times (**6.2, 6.4, 6.6, 6.8**) are expressed as the time necessary to bring the frequency from the maximum value set in the **Full scale speed (5.22)** parameter to zero. Each of the 4 available ramp selections can be selected using one or two digital inputs programmed as **Multi ramp sel**.

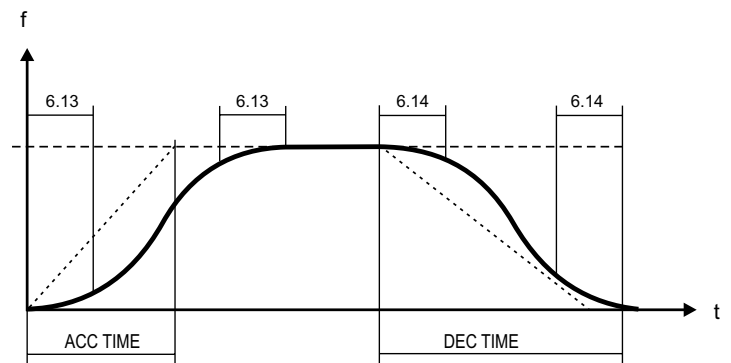
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.9	720	Ramp type		ENUM		Linear	0	3	ERWZ	FVS

This parameter defines the ramp shape (linear/S-shape). It can only be modified with the drive disabled.

- 0 Linear
- 1 S-Shape
- 2 Bypass
- 3 Off



0 = Linear



1 = S-Shape

When linear ramps are set (**Linear**) the motor speed varies in a way that is directly in proportion to the frequency.

When S-shape ramps are set (**S-Shape**) it is possible to avoid sudden mechanical variations in the system at the beginning and end of the acceleration and deceleration phase.

The ramp time, meaning the time necessary to accelerate from zero to the maximum frequency value set, is given by the sum of the linear ramp time and that of the associated **Jerks** (see par. 6.13 – 6.20).

The **Bypass** excludes the ramp circuit and the reference is brought directly to the speed regulator input.

With **Off** the ramp reference is set to zero.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.10	722	Multi ramp sel 0 src		LINK		6000	0	16384	ERWZ	FVS
6.11	724	Multi ramp sel 1 src		LINK		6000	0	16384	ERWZ	FVS

1 or 2 digital inputs can be used to select one of the 4 available sets of ramps.

The origin (source) of the command to enable the ramp selection function can be selected from the “**L_DIG-SEL2**” selection list.

The following table describes the ramp selection procedure:

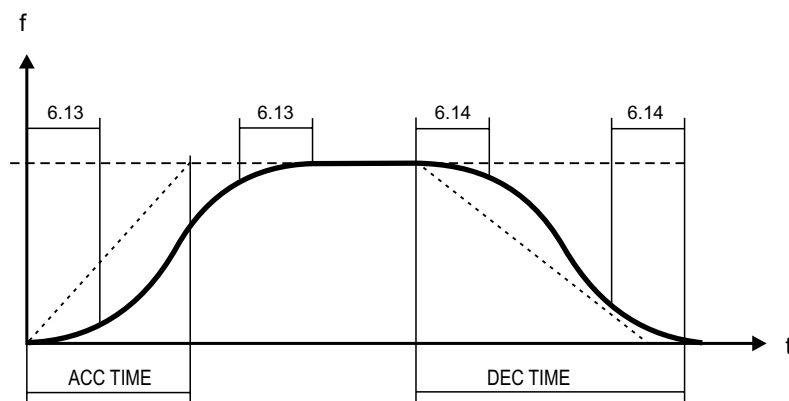
Enabled ramp time	Multi ramp sel 0	Multi ramp sel 1
Acceleration time 0 Deceleration time 0	0	0
Acceleration time 1 Deceleration time 1	1	0
Acceleration time 2 Deceleration time 2	0	1
Acceleration time 3 Deceleration time 3	1	1

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.12	726	Multi ramp sel mon		UINT16		0	0	3	ER	FVS

The set of acceleration/deceleration ramps selected using the digital inputs is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.13	730	Accel jerk time 0	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.14	732	Decel jerk time 0	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.15	734	Accel jerk time 1	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.16	736	Decel jerk time 1	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.17	738	Accel jerk time 2	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.18	740	Decel jerk time 2	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.19	742	Accel jerk time 3	s	FLOAT		1.0	0.02	10.0	ERW	FVS
6.20	744	Decel jerk time 3	s	FLOAT		1.0	0.02	10.0	ERW	FVS

Jerks are variations of acceleration in time. They are used when there is a need to dampen the beginning and end of the ramp. The Jerk value is added, regardless of the variation in speed, to the linear ramp time.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.21	750	Ramp in zero src		LINK	16	6000	0	16384	ERW	FVS

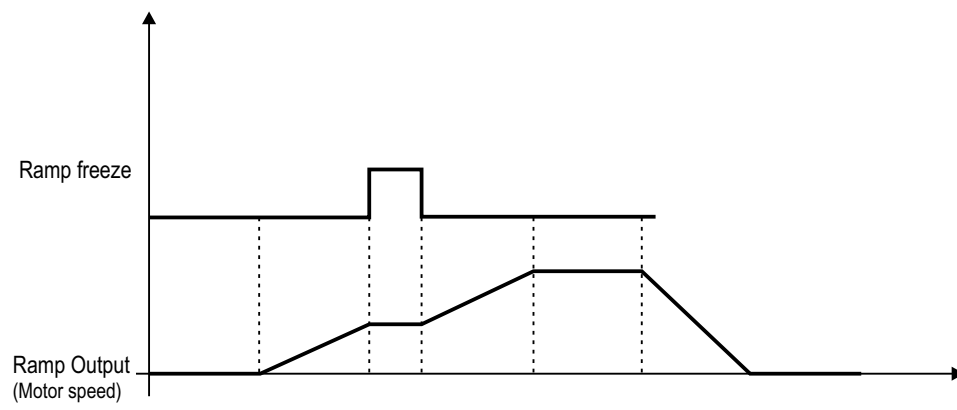
Selection of the origin (source) of the signal that blocks the ramp input and moves the reference to zero. If the ramp input is enabled, the **Ramp ref** parameter corresponds to the set reference. If the ramp input is blocked, the drive slows down with the set deceleration time until reaching zero speed. The terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.22	752	Ramp out zero src		LINK	16	6000	0	16384	ERW	FVS

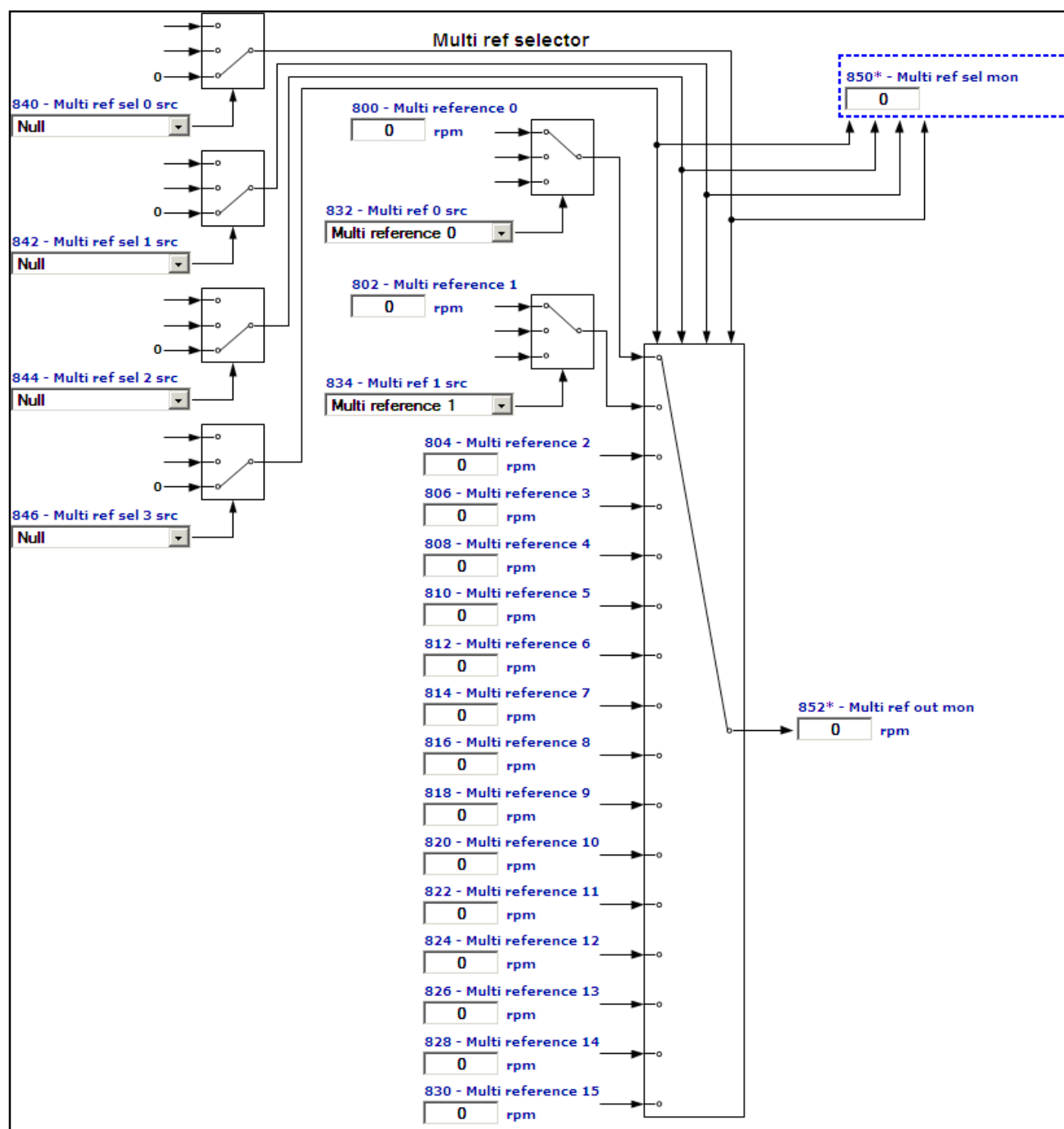
Selection of the origin (source) of the signal that brings the ramp to 0 (**Ramp ref 1/Ramp ref 2 = 0**). When the ramp output is set to zero using **Ramp out zero**, the drive brakes with the maximum available torque; in this case the ramp is disabled. The terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
6.23	754	Ramp freeze src		LINK	16	3480	0	16384	ERW	FVS

Selection of the origin (source) of the signal that temporarily freezes the ramp output value, regardless of any changes in the input reference. The terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.



7 – MULTI REFERENCE



With the “Multispeed” function (**Multi references**) it is possible to recall up to sixteen internally saved speed references to be recalled using a digital signal or via digital inputs on the terminal strip.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
7.1	800	Multi reference 0	FF	INT16	16/32	0	CALCI	CALCI	RW	FVS
7.2	802	Multi reference 1	FF	INT16	16/32	0	CALCI	CALCI	RW	FVS
7.3	804	Multi reference 2	FF	INT16		0	CALCI	CALCI	RW	FVS
7.4	806	Multi reference 3	FF	INT16		0	CALCI	CALCI	RW	FVS
7.5	808	Multi reference 4	FF	INT16		0	CALCI	CALCI	RW	FVS
7.6	810	Multi reference 5	FF	INT16		0	CALCI	CALCI	RW	FVS

7.7	812	Multi reference 6	FF	INT16	0	CALCI	CALCI	RW	FVS
7.8	814	Multi reference 7	FF	INT16	0	CALCI	CALCI	RW	FVS
7.9	816	Multi reference 8	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.10	818	Multi reference 9	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.11	820	Multi reference 10	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.12	822	Multi reference 11	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.13	824	Multi reference 12	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.14	826	Multi reference 13	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.15	828	Multi reference 14	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.16	830	Multi reference 15	FF	INT16	0	CALCI	CALCI	ERW	FVS

It is possible to select up to 16 operating frequencies, which can be set in these parameters.

The frequencies are selected using the binary code of the digital inputs programmed using the **Multi ref sel 0 src**, **Multi ref sel 1 src**, **Multi ref sel 2 src** and **Multi ref sel 3 src** parameters.

References can be set via the keypad, serial line, digital inputs and Fieldbus.

A sign can be given to the references, so that when they are defined so too is the desired direction of rotation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
7.17	832	Multi ref 0 src		LINK	16/32	800	0	16384	RW	FVS
7.18	834	Multi ref 1 src		LINK	16/32	802	0	16384	RW	FVS

Selection of the origin (source) of the drive speed reference signals. The speed reference values can be selected from those listed in the “**L_MLTREF**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
7.19	840	Multi ref sel 0 src		LINK	16	6000	0	16384	RW	FVS
7.20	842	Multi ref sel 1 src		LINK	16	6000	0	16384	RW	FVS
7.21	844	Multi ref sel 2 src		LINK	16	6000	0	16384	RW	FVS
7.22	846	Multi ref sel 3 src		LINK	16	6000	0	16384	ERW	FVS

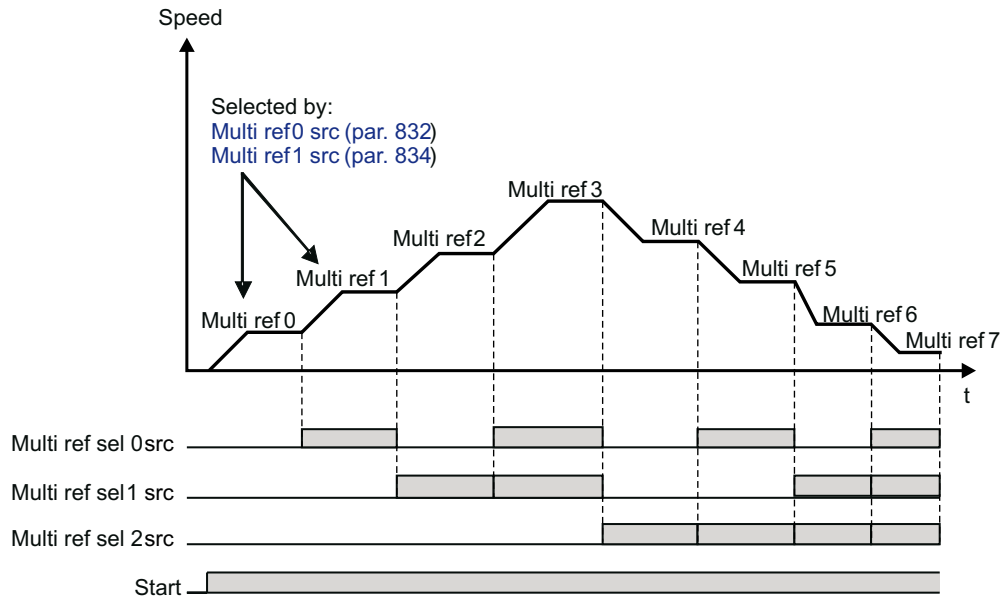
Selection of the origin (source) of the signals used to select one of the preset speeds. These parameters can only be used together in combinations. The terminals that can be used for this function can be selected from among those listed in the “**L_DIGSEL2**” selection list.

The following table describes the selection of the Multispeed function:

Active speed ref	Multi ref sel 0 src	Multi ref sel 1 src	Multi ref sel 2 src	Multi ref sel 3 src
Multi reference 0	0	0	0	0
Multi reference 1	1	0	0	0
Multi reference 2	0	1	0	0
Multi reference 3	1	1	0	0
Multi reference 4	0	0	1	0
Multi reference 5	1	0	1	0
Multi reference 6	0	1	1	0
Multi reference 7	1	1	1	0
Multi reference 8	0	0	0	1
Multi reference 9	1	0	0	1
Multi reference 10	0	1	0	1
Multi reference 11	1	1	0	1
Multi reference 12	0	0	1	1
Multi reference 13	1	0	1	1

Active speed ref	Multi ref sel 0 src	Multi ref sel 1 src	Multi ref sel 2 src	Multi ref sel 3 src
Multi reference 14	0	1	1	1
Multi reference 15	1	1	1	1

The following figure describes the selection of a control for 8 Multispeeds.



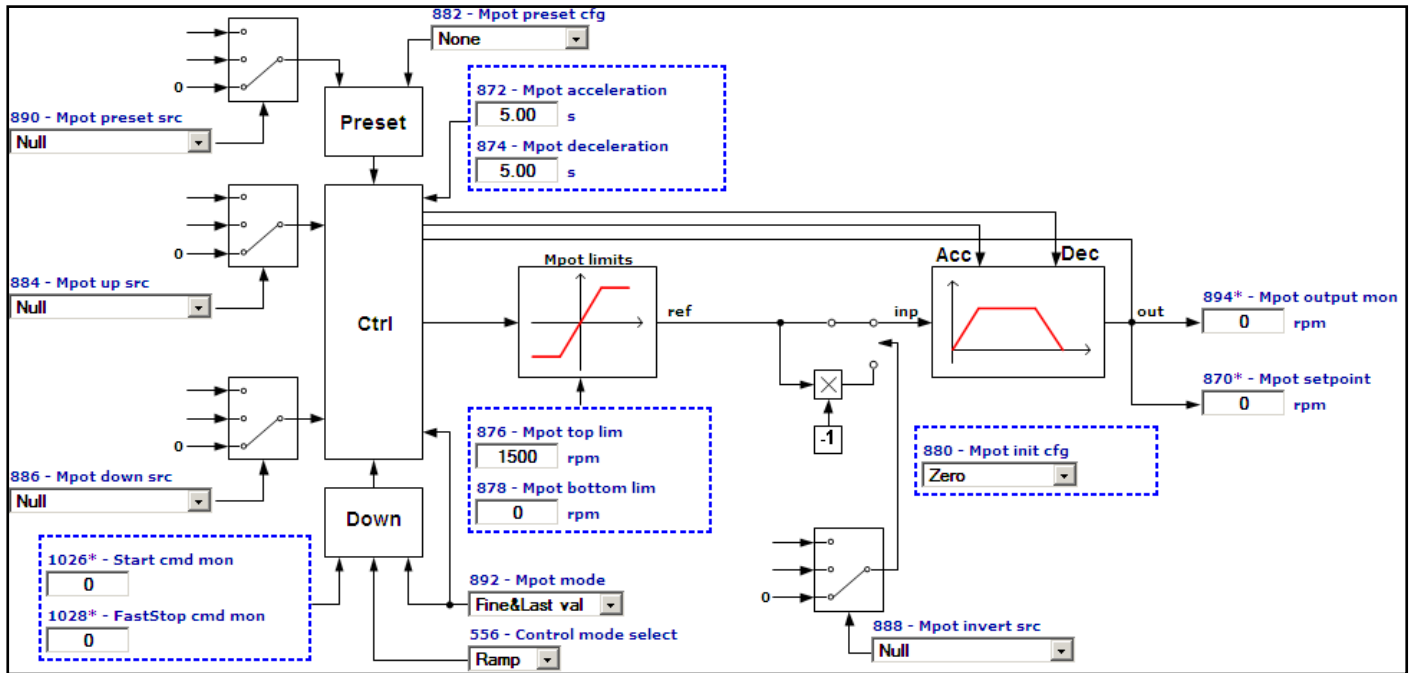
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
7.23	850	Multi ref sel mon		UINT16		0	0	15	R	FVS

The multispeed that has been selected using the digital commands or by the digital inputs selected in the terminal strip.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
7.24	852	Multi ref out mon	FF	INT16	16/32	0	0	0	R	FVS

The selected speed reference on the Multispeed block output is displayed.

8 – MOTORPOTENTIOMETER



The Motor potentiometer function allows the speed reference of the drive to be changed by pressing buttons with which the UP and DOWN commands are associated.

The UP and DOWN commands can be sent from the keypad, by digital inputs, the serial line or fieldbus.

To send the UP and DOWN commands from the keypad, enter the **MPot setpoint** parameter modify mode and press the UP and DOWN keys.

The UP and DOWN commands increase or decrease the speed of the motor for as long as they are present. The simultaneous presence of both commands will not produce any change (see time chart).

The speed changes according to the set ramp times and within the set lower and upper limits.

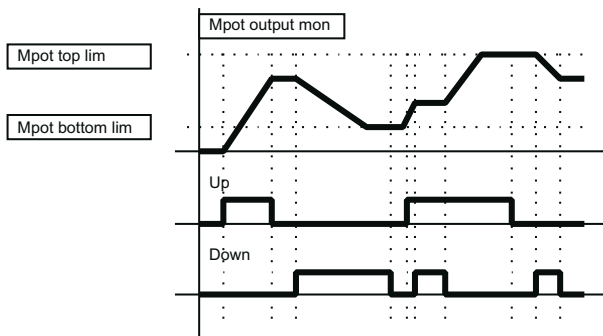
The value of the Motor potentiometer function output at drive power-on can be configured.

The preset command can be used to force a preset value for the input and output of the Motor potentiometer function.

The invert command can be used to force an inversion of the reference sign of the Motor potentiometer function.

In the default condition, the speed reference produced by the Motor potentiometer function is connected in input to the Ramp function. For direct control of the motor speed, the Acceleration time and Deceleration time parameters in the RAMP menu should be set = 0.

Note ! The Motor potentiometer function produces a speed reference. Therefore a RUN command must always be sent to start motor rotation.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.1	870	Mpot setpoint	FF	INT16	16/32	0	CALCI	CALCI	R	FVS

The speed reference value of the Motor potentiometer function is displayed. Default setting is “rpm”. It can be modified thru the DIMENSION FACT function.

Enter this parameter to send the UP and DOWN commands from the keypad.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.2	872	Mpot acceleration	s	FLOAT		5.0	0.01	1000.00	RW	FVS
8.3	874	Mpot deceleration	s	FLOAT		5.0	0.01	1000.00	RW	FVS

Setting of the acceleration/deceleration ramp times (in seconds) used with the Motor potentiometer function.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.4	876	Mpot top lim	FF	INT16		CALCI	CALCI	CALCI	ERW	FVS

Setting of the top limit for the speed reference output from the motor potentiometer.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.5	878	Mpot bottom limit	FF	INT16		0	CALCI	CALCI	ERW	FVS

Setting of the bottom limit for the speed reference output from the motor potentiometer.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.6	880	Mpot init cfg		ENUM		Zero	0	3	ERW	FVS

Use this parameter to configure the output value of the Motor potentiometer at drive start-up.

- 0 Last power off
- 1 Zero
- 2 Lower Limit
- 3 Upper Limit

When set to **Last power off**, the motor potentiometer output starts from the last frequency that was set before the drive was switched off.

When set to **Zero** the motor potentiometer output starts from a value of 0.

When set to **Lower limit** the output of the motor potentiometer starts from the value of the lower limit set in the **Mpot bottom limit** parameter.

When set to **Upper limit** the output of the motor potentiometer starts from the value of the upper limit set in the **Mpot top limit** parameter.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.7	882	Mpot preset cfg		ENUM		None	0	11	ERW	FVS

This parameter can be used to configure the preset of the Motor potentiometer function, i.e. to configure the value at which the Motor potentiometer input and output are set when the Preset command is enabled.

The Preset command has priority over the Up command and the Down command.

Mpot mode (PAR 892) = [1] **Ramp&Follow** has priority over the Preset command, i.e. actions programmed with **Mpot preset cfg** (PAR 882) are not executed.

The Up and Down commands are enabled again when the Preset command is disabled.

- 0 None
- 1 Input = 0
- 2 Input = low lim
- 3 Input & ref = 0
- 4 Input & ref = low lim
- 5 Output = 0

- 6 Output = low lim
- 7 Output & ref = 0
- 8 Output & ref = low lim
- 9 Input = upp lim
- 10 Input & ref = upp lim
- 11 Freeze input

When set to **None**, no setting is executed.

Input = 0 sets input = 0 i.e. a temporary reference setting is performed and the previous reference value is maintained. The output of the Motor potentiometer function varies with the set ramp times. The previous reference value is restored when the preset command is removed.

Input = low lim sets Inp = low lim i.e. a temporary reference setting is performed and the previous reference value is maintained. The output of the Motor potentiometer function varies with the set ramp times. The previous reference value is restored when the preset command is removed.

Input & ref = 0 sets Inp = 0 and Ref = 0 i.e. a definitive reference setting is performed. The output of the Motor potentiometer function varies with the set ramp times.

Input & ref = low lim sets Inp = low lim and Ref = low lim i.e. a definitive reference setting is performed. The output of the Motor potentiometer function varies with the set ramp times.

Output = 0 sets Out = 0 i.e. a temporary output setting for the Motor potentiometer function is performed. The previous reference value is maintained. If the preset command is enabled, the output of the Motor potentiometer function continues to be = 0, if the preset command is not enabled the output of the Motor potentiometer function varies with the set ramp times.

Output = low lim sets Out = low lim i.e. a temporary setting for the output of the Motor potentiometer function is performed. The previous reference value is maintained. If the preset command is enabled, the output of the Motor potentiometer function continues to be = low lim, if the preset command is not enabled the output of the Motor potentiometer function varies with the set ramp times.

Output & ref = 0 sets Out = 0 i.e. a definitive setting for the output of the Motor potentiometer function is performed.

Output & ref = low lim sets Out = low lim i.e. a definitive setting for the output of the Motor potentiometer function is performed.

Input = upp lim sets Inp = upp lim i.e. a temporary setting for the reference is performed and the previous reference value is maintained. The output of the Motor potentiometer function varies with the set ramp times. The previous reference value is restored when the preset command is removed.

Input & ref = upp lim sets Inp = upp lim and Ref = upp lim i.e. a definitive reference setting is performed. The output of the Motor potentiometer function varies with the set ramp times.

When **Freeze input** is set, the Up and Down commands are temporarily disabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.8	884	Mpot up src		LINK	16	6000	0	16384	RW	FVS
Selection of the origin (source) of the signal that increases the speed reference of the motor potentiometer with the set ramp. The terminal to be associated with this function can be selected from the " L_DIGSEL2 " selection list.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.9	886	Mpot down src		LINK	16	6000	0	16384	RW	FVS
Selection of the origin (source) of the signal that decreases the speed reference of the motor potentiometer with the set ramp. The terminal to be associated with this function can be selected from the " L_DIGSEL2 " selection list.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.10	888	Mpot invert src		LINK	16	6000	0	16384	ERW	FVS
Selection of the origin (source) of the signal that inverts the speed reference of the motor potentiometer. The										

terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.11	890	Mpot preset src		LINK	16	6000	0	16384	ERW	FVS

Selection of the origin (source) of the signal to preset the motor potentiometer function. The signal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.12	892	Mpot mode		ENUM		Fine&Last val	0	3	ERW	FVS

Setting of the configuration of two possible options of the Motor potentiometer function. There are two operating modes for each of the two options.

- 0 Ramp&Last val
- 1 Ramp&Follow
- 2 Fine&Last val
- 3 Fine&Follow

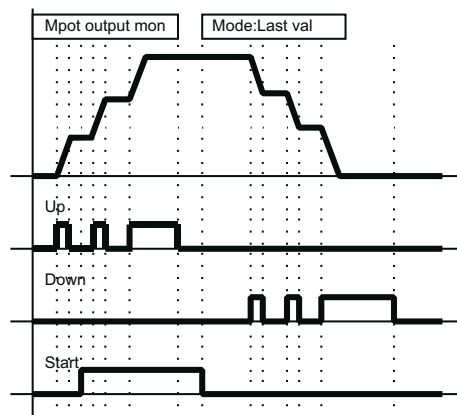
Option 1: Behaviour of the Motor potentiometer function with the Stop or FastStop command present with the PAR 556 **Control mode = Ramp** parameter.

The two operating modes are: **Last val** or **Follow**.

With the Control mode not equal to Ramp setting, this option is not completely applicable and it always behaves in Last val mode.

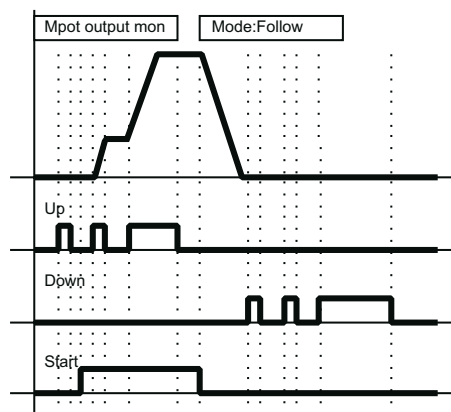
In **Last val** mode with the Stop or FastStop command present, the speed reference of the Motor potentiometer function is not altered.

The motor speed moves to 0 according to the selected control mode (**Control mode = Ramp** or **Control mode = Speed**). When the Run command is sent, the motor speed moves to the speed reference set by the motor potentiometer function according to the selected control mode.



In **Follow** mode with the Stop or FastStop command present, the Down command is simulated, i.e. the output of the Motor potentiometer function moves to 0 with the set ramp time.

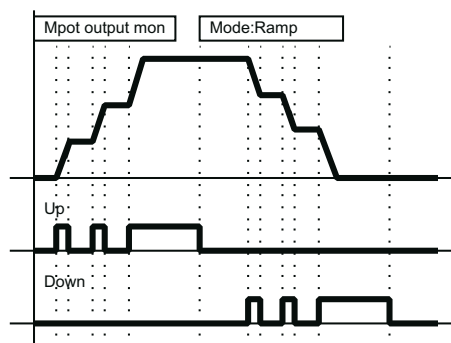
If the Run command is sent when the 0 speed has been reached, it is maintained until the Up command is sent. If the Run command is sent before the motor reaches the 0 speed, the speed at that moment is taken as the new reference.



Option 2: Ramp behaviour

The two operating modes are: **Ramp** or **Fine**

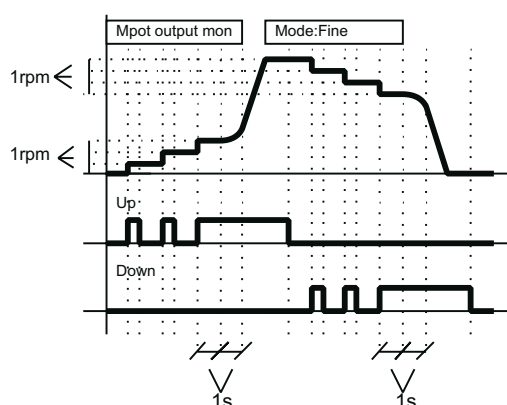
In **Ramp** mode, each time the Up or Down commands are enabled, the output of the Motor potentiometer function increases or decreases with the set ramp. When the Up or Down command is removed, the last value that was reached is maintained.



In **Fine** mode, each time the Up or Down commands are enabled, the output of the Motor potentiometer function increases or decreases by 1 rpm.

If the command persists for less than 1 second, no other changes are made on the output.

If the command persists for more than 1 second, the output increases or decreases with the set ramp. The variation with the set ramp is performed gradually (1 second). When the Up or Down command is removed the last value that was reached is maintained.



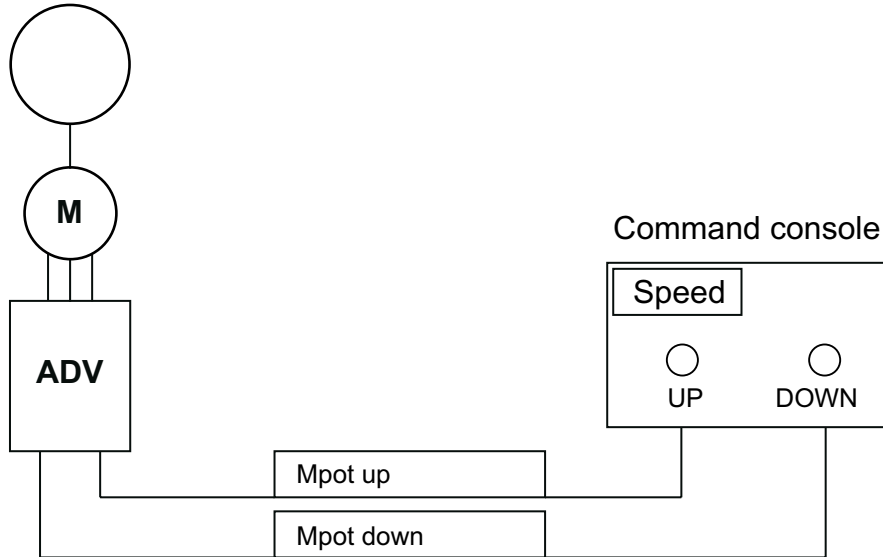
Mpot mode	Ramp behaviour	Behaviour of the Motor potentiometer function with the Stop or FastStop command present with the Control mode = Ramp parameter.
0	Ramp	Last val
1	Ramp	Follow
2	Fine	Last val
3	Fine	Follow

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
8.13	894	Mpot output mon	rpm	INT16	16/32	0	0	0	ER	FVS

The value of the output of the motor potentiometer function is displayed.

Two examples of application of the motor potentiometer function are shown below.

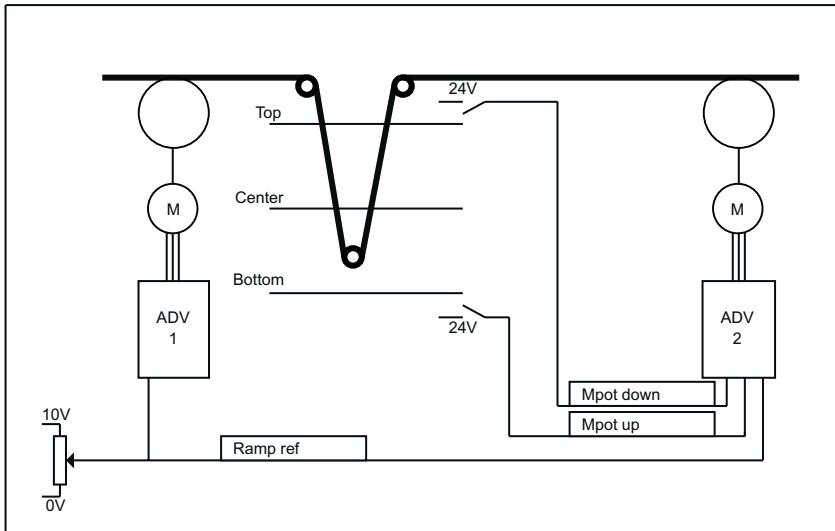
Manual speed control with command sent from external control desk.



The Up and Down keys are used to adjust the speed of a motor.

For fine-tuning of the speed reference value the recommended settings are **Mpot Mode = Fine&Follow** or **Fine&Last Val**. Each time they are pressed for 1 second, the speed increases by 1 rpm. For an immediate effect on motor speed, the Acceleration time and Deceleration time parameters should be set to short times.

Automatic speed control for rudimentary dancer control.

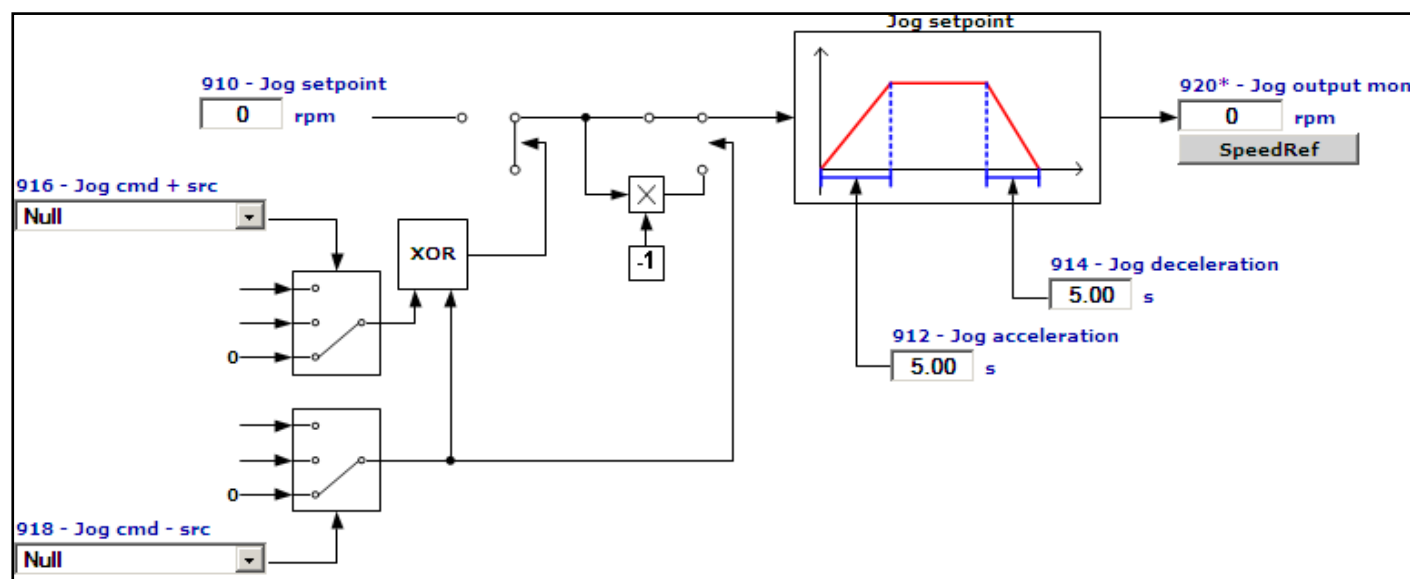


The limit switches at the ends of dancer travel ranges are connected to the Up and Down commands in the motor potentiometer function. If the dancer presses the bottom limit switch, this means motor 2 is running slowly and the Up command must be sent. If the dancer presses the top limit switch, this means motor 2 is running quickly and the Down command must be sent.

Connect the line reference to **Ramp ref 1 src** on both drives, connect the motor potentiometer function output to **Speed ref 1 src** on drive 2.

To change the motor speed immediately, the recommended settings are **Mpot Mode = Ramp&Follow** or **Rampa&Last Val**.

9 – JOG FUNCTION



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
9.1	910	Jog setpoint	rpm	INT16		0	CALCI	CALCI	RW	FVS

The reference for Jog mode operation. This reference can also be set via an analog input. The **Jog** reference is enabled when the signal used for the **Jog +** or **Jog -** command is enabled, the Run command is not present and the drive output frequency is zero.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
9.2	912	Jog acceleration	s	FLOAT		5.0	0.01	1000.00	RW	FVS
9.3	914	Jog deceleration	s	FLOAT		5.0	0.01	1000.00	RW	FVS

Setting of the acceleration/deceleration ramp time (in seconds) used during **Jog** operation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
9.4	916	Jog cmd + src		LINK	16	6000	0	16384	RW	FVS

Selection of the origin (source) of the **Jog +** function enabling signal. When this command is enabled it generates a Jog Mode reference with a sign matching the value entered for the **Jog setpoint value** parameter. The signal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Note ! The **Run** command has priority over the **Jog +** command.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
9.5	918	Jog cmd - src		LINK	16	6000	0	16384	RW	FVS

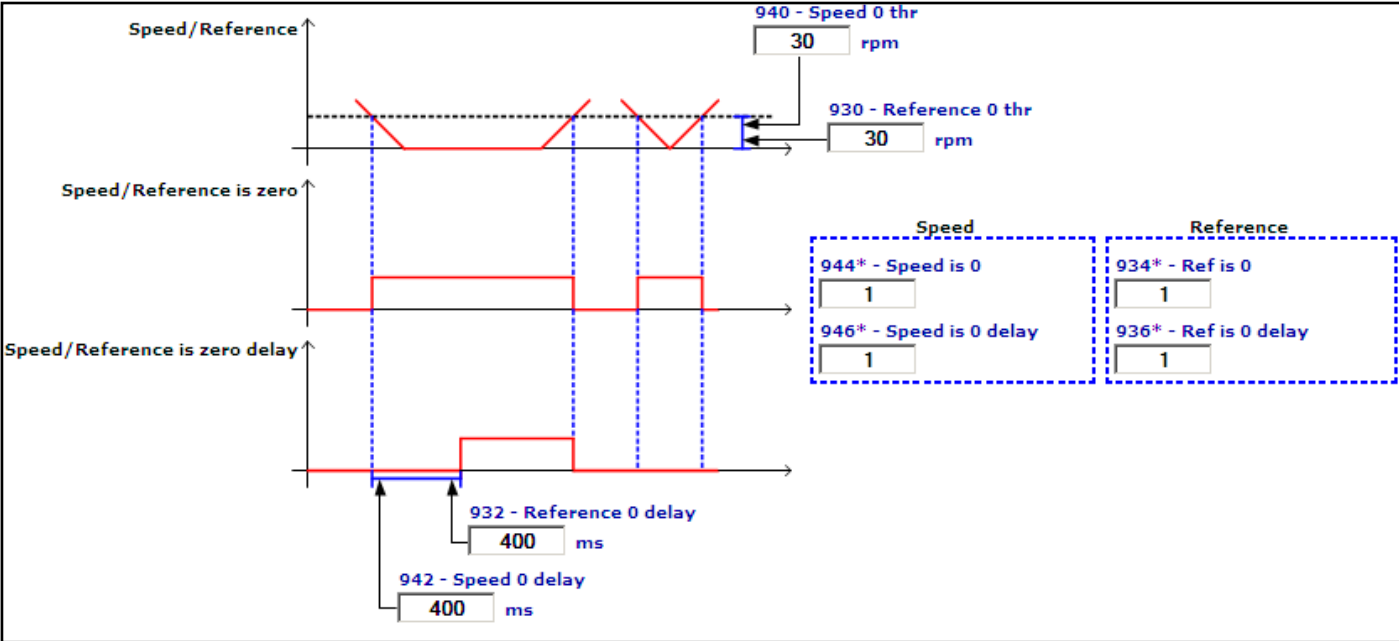
Selection of the origin (source) of the **Jog -** function enabling signal. When this command is enabled the Jog Mode reference sign is inverted with respect to the value entered in the **Jog setpoint value** parameter. The signal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Note ! The **Run** command has priority over the **Jog -** command.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
9.6	920	Jog output mon	rpm	INT16	16/32	0	0	0	ER	FVS

The speed reference used by the **Jog** command is displayed.

10 – MONITOR FUNCTION



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.1	930	Reference 0 thr	rpm	INT16		30	0	CALCI	RW	FVS

Setting of the threshold for recognition of the speed = 0 reference. The value is valid for both directions of rotation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.2	932	Reference 0 delay	ms	UINT16		400	0	10000	RW	FVS

Setting of the delay in milliseconds after which the reference = 0 reached signal is enabled.

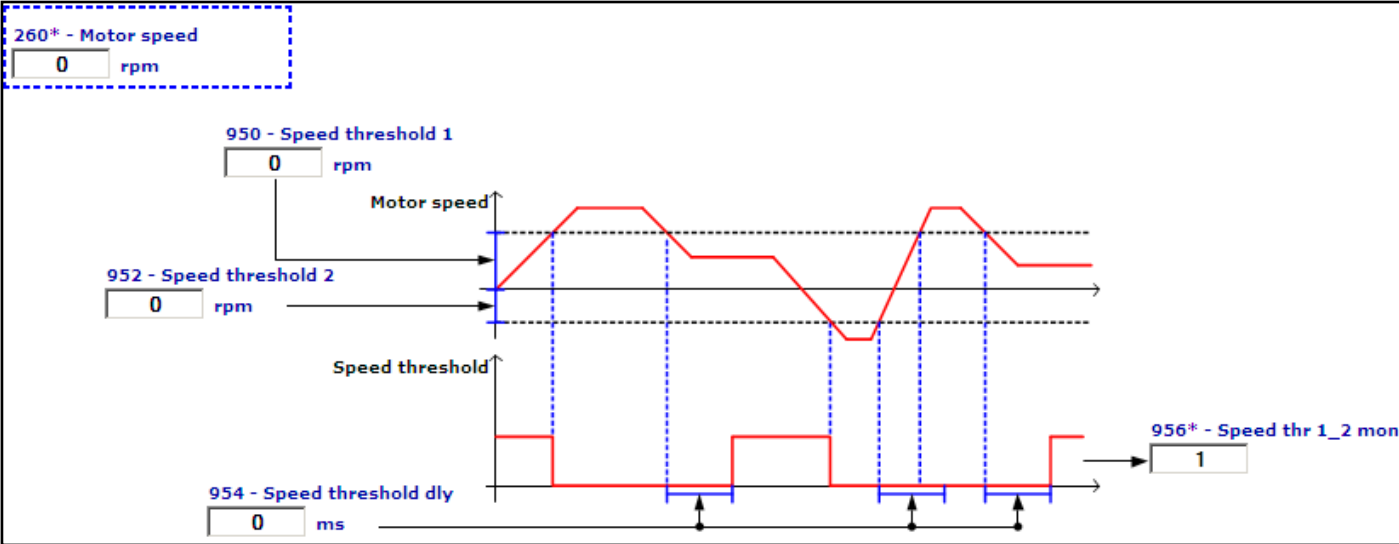
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.3	940	Speed 0 thr	rpm	INT16		30	0	CALCI	RW	FVS

Setting of the threshold for recognizing speed value = 0. The value is valid for both directions of rotation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.4	942	Speed 0 delay	ms	UINT16		400	0	10000	RW	FVS

Setting of the delay in milliseconds after which the speed = 0 reached signal is enabled.

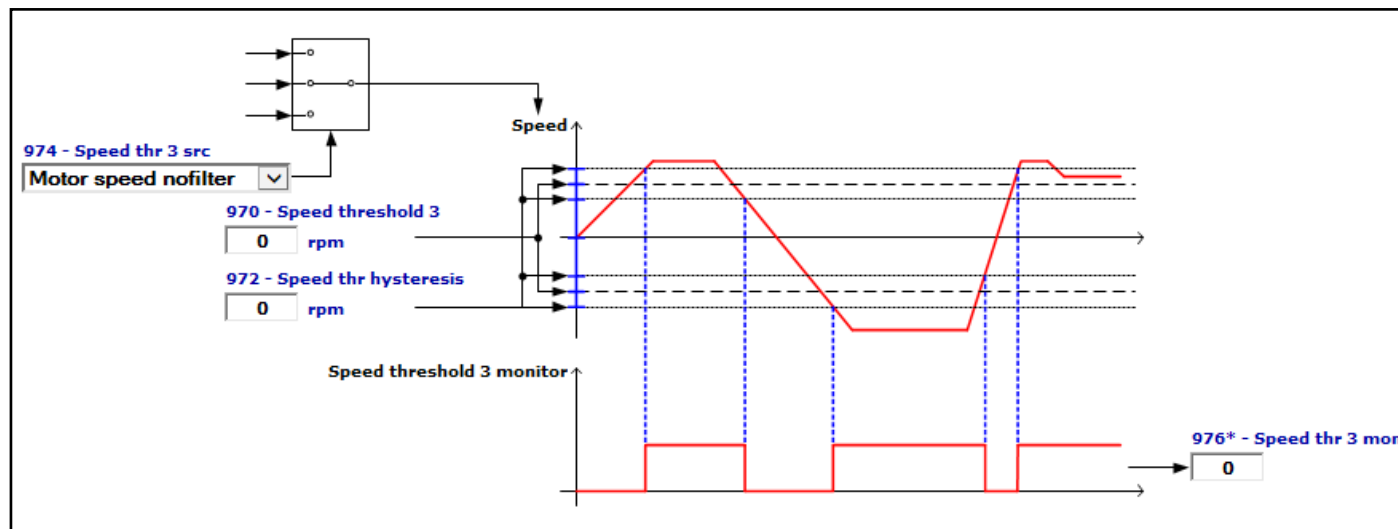
When the motor reaches a speed that is below the zero speed threshold, it stops and the n=0 LED lights up.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.5	950	Speed threshold 1	rpm	INT32		0	CALCI	CALCI	RW	FVS
Setting of speed threshold 1 (upper). When the threshold is exceeded the Speed threshold signal is disabled, with a delay that can be set in Speed threshold dly .										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.6	952	Speed threshold 2	rpm	INT32		0	CALCI	CALCI	RW	FVS
Setting of speed threshold 2 (lower). When the threshold is exceeded the Speed threshold signal is disabled, with a delay that can be set in Speed threshold dly .										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.7	954	Speed threshold dly	ms	UINT16		0	0	50000	RW	FVS
Setting of the delay after which the transition from 0 $\Rightarrow$ 1 is activated. The transition from 0 $\Rightarrow$ 1 occurs when the speed is within the set limits. The Speed threshold signal transition from 1 $\Rightarrow$ 0 is always immediate. If the motor speed is between Speed threshold 1 and Speed threshold 2 , the Speed threshold signal is active. If Speed threshold 1 < Speed threshold 2 the Speed threshold signal is not significant.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.8	960	Set speed ref src		LINK	16/32	628	0	16384	ERW	FVS
Selection of the origin (source) of the signal used as speed reference and on which the speed reached control is performed (for control with ramp, use Ramp setpoint , for control without ramp, use Speed setpoint). The signal that can be used as the speed reference can be selected from among those listed in the “ L_CMP ” selection list.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.9	962	Set speed error	rpm	INT16		100	0	CALCI	RW	FVS
Setting of the bandwidth of the tolerance within which, even if the speed is not equal to the reference, the two values are considered to coincide and the Set speed signal is enabled.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.10	964	Set speed delay	ms	UINT16		0	0	50000	RW	FVS
Setting of a delay in ms before the signal (Set speed programmed on a digital output), if the speed is within a tolerance band defined by the Set speed error parameter, after which the transition from 0 $\Rightarrow$ 1 is enabled. The transition of the Set Speed signal from 0 $\Rightarrow$ 1 is always immediate.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.11	968	Dig set speed ref	rpm	UINT16 16/32		0	CALCI	CALCI	RW	FVS
Setting of the threshold used as the speed reference: this parameter is used to set a fixed threshold regardless of the speed reference.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.12	970	Speed threshold 3	rpm	INT32		0	0	CALCI	ERW	FVS

Setting of the speed 3 threshold. When this threshold + the tolerance band set in parameter **972 Speed thr hysteresis** are exceeded, parameter **976 Speed thr 3 mon** is enabled. The signal is disabled when the motor speed falls below the threshold - the tolerance band. If the threshold value is lower than the value set in **972 Speed thr hysteresis**, the result produced is always 0. The value set in this parameter is active in both directions of rotation.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.13	972	Speed thr hysteresis	rpm	UINT16		0	0	CALCI	RW	FVS

Setting of the tolerance band around **Speed threshold 3**. The tolerance band is the same for both directions of rotation of the motor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.14	974	Speed thr 3 src		LINK	16/32	262	0	16384	ERW	FVS

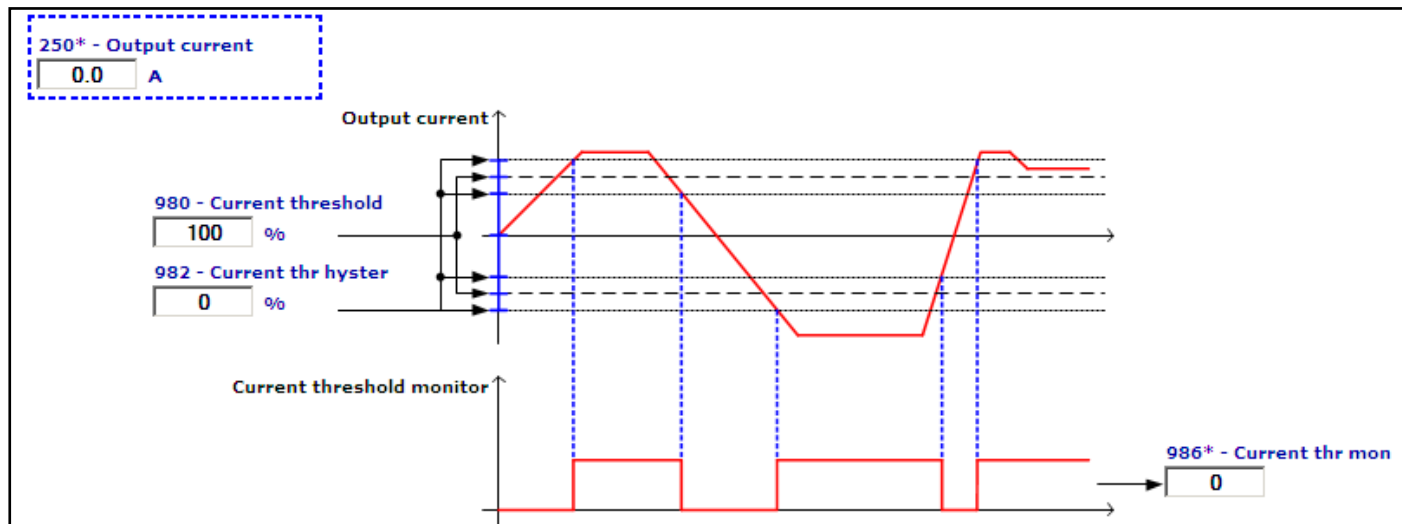
Lets you select the source of the "Speed threshold 3" function block to compare **Speed threshold 3** (IPA 970) with the real or estimated motor speed or speed reference.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.15	980	Current threshold	perc	UINT16		100	0	200	RW	FVS

Setting of the current threshold. A value of 100% corresponds to the value of the drive heavy duty continuous current, displayed in parameter **488 Drive cont current**, when parameter **566 Drive overload mode** is set to **Heavy duty**, and no derating of the drive continuous current has been activated due to any modification of Mains voltage, Switching frequency and Ambient temperature.

The drive heavy duty continuous current value to be used is the factory setting read in PAR 488 **Drive cont current**.

When this threshold + the tolerance band set in parameter **982 Current thr hyster** are exceeded, parameter **986 Current thr mon** is enabled. The signal is disabled when the motor speed falls below the threshold - the tolerance band. If the threshold value is lower than the value set in **982 Current thr hyster**, the result produced is always 0. The value set in this parameter is active in both directions of rotation.



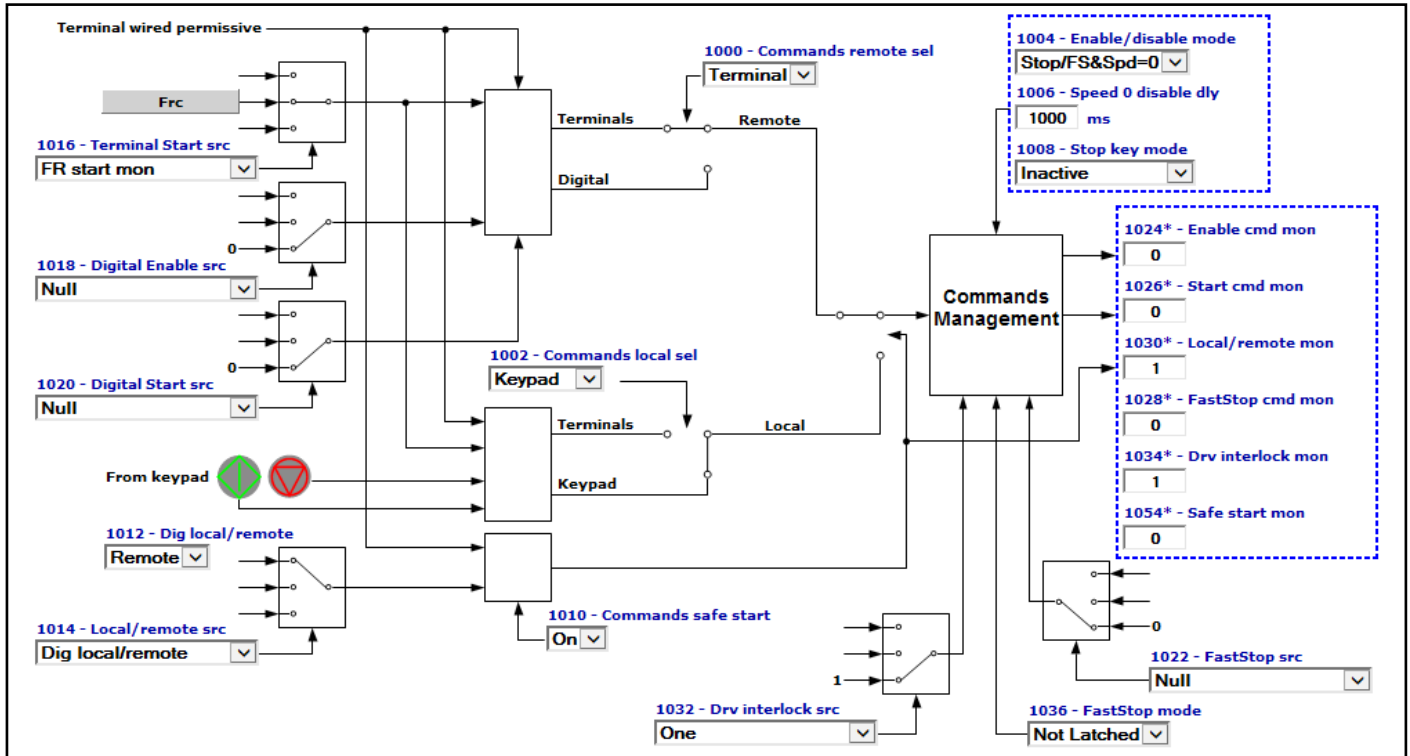
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
10.16	982	Current thr hysteresis	perc	UINT16		0	0	100	RW	FVS

Setting of the tolerance band around the current threshold. A value of 100% corresponds to the value of the drive heavy duty continuous current, displayed in parameter **488 Drive cont current**, when parameter **566 Drive overload mode** is set to **Heavy duty**, and no derating of the drive continuous current has been activated due to any modification of Mains voltage, Switching frequency and Ambient temperature.

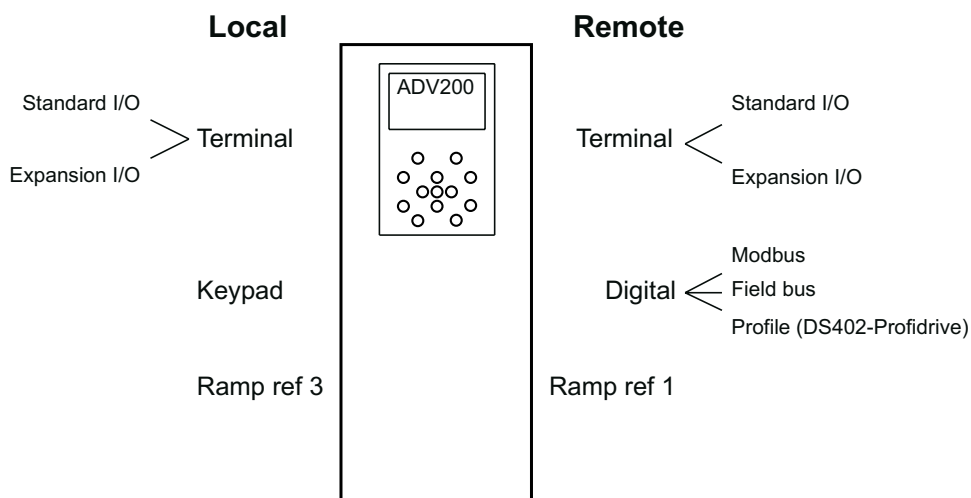
The drive heavy duty continuous current value to be used is the factory setting read in PAR 488 **Drive cont current**.

The tolerance band is the same for both directions of rotation of the motor.

11 – COMMANDS



It is possible to work in **Local** or **Remote** mode.



When switching between **Remote** and **Local** modes the origin of the Enable and Start commands is switched and in the **Ramp Ref** block, switching occurs between Ramp ref 1 and Ramp ref 3.

In **Remote** mode the “**Commands remote sel**” parameter is used to configure the source of the Enable and Start commands which can be **Terminal** (standard digital input, expansion digital input) or **Digital** (Modbus, Fieldbus, Profile DS402, Profile profidrive).

In **Local** mode the “**Commands local sel**” parameter is used to configure the source of the Enable and Start commands, which can be **Terminal** (standard digital input, expansion digital input) or **Keypad** (Start key, Stop key).

In **Remote** ⇌ **Digital** mode the **Digital Enable src** and **Digital Start src** parameters must be used to configure the source.

Normally the sources are the Pad parameters. Modbus or Fieldbus must therefore write the desired value on the Pad parameters. Alternatively, the value of 6000 can be written directly on the **Digital Enable src** and **Digital Start src**

parameters for a source of Null (0) or the value of 6002 for a source of One (1).

Another alternative is to configure the **Digital Enable src** and **Digital Start src** sources on the **BitX decomp mon** parameters, so that the Modbus or Fieldbus can then write the desired value on the **Dig word decomp** parameter.

Local ⇌ **Remote** switching is performed with the variable value configured as **Loc/Remote src**, i.e. it can be a standard digital input, expansion digital input, Modbus, Fieldbus, **Dig Local/Remote**.

In the default condition, the associated variable is **Dig Local/Remote**, which is written by the **LOC** key from the keypad: switching is thus performed by pressing the **LOC** key.

For safety reasons, **Local** ⇌ **Remote** switching is only performed with **Terminal Enable = 0**.

Example 1

With the machine in automatic operating mode, the drive works in Remote -> Digital -> Fieldbus mode.

With the machine in manual operating mode, the drive works in Local -> Terminal -> Standard digital input mode.

If switching from automatic to manual machine operation, the drive must switch between Remote and Local mode. The switch command must be sent via standard digital input or fieldbus.

Example 2

With the machine controlled from console A, the drive operates in Local -> Terminal -> Standard digital input mode.

With the machine controlled from console B, the drive operates in Remote -> Digital -> Expansion digital input mode.

When switching the control console, the drive must switch between Remote and Local mode. The switch command must be sent via Standard digital input or Expansion digital input.

This configuration is allowed because the Terminal variables are available in the digital command selection lists.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.1	1000	Commands remote sel		ENUM		Terminals	0	1	RWZ	FVS

This parameter defines the source of the command signals when the drive is used in the Remote mode.

The Enable command can only be set via hardware, connecting a positive voltage (+24VDC) to terminal 7.

0 Terminals

1 Digital

When the parameter is set to **Terminals** the source of the **Enable cmd mon** command is the **Enable** terminal (7) and the origin of the **Start cmd mon** command is configured using the **Terminal Start src** parameter.

When the parameter is set to **Digital** the origin of the **Enable cmd mon** command is configured using the **Digital Enable src** parameter and the origin of the **Start cmd mon** command is configured using the **Digital Start src** parameter.

If **Digital** is set to generate the **Enable cmd mon** command, as well as the variable associated with **Digital Enable src**, the enable hardware command must also be sent to the **Enable** terminal.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.2	1002	Commands local sel		ENUM		Keypad	0	2	ERWZ	FVS

This parameter defines the source of the command signals when the drive is used in the **Local** mode.

0 Terminals

2 Keypad

When the parameter is set to **Terminals** the source of the **Enable cmd mon** command is the **Enable** terminal (7) and the origin of the **Start cmd mon** command is configured using the **Terminal Start src** parameter.

When the parameter is set to **Keypad** the origin of the **Enable cmd mon** and **Start cmd mon** commands is the Start key. When **Keypad** is set to generate the **Enable cmd mon** command, as well as the Start key the enable hardware command must also be sent to the **Enable** terminal (7).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.3	1004	Enable/disable mode		ENUM		Stop/FS&Spd=0	0	3	ERWZ	FVS

This parameter is used to define the generation of **Enable cmd mon**, i.e. to configure the type of control used for enabling and disabling the drive.

- 0 Off
- 1 Stop/FS&Spd = 0
- 2 Stop&Spd = 0
- 3 FS&Spd = 0

If set to **0 Off**:

In **Terminal** mode the drive is enabled and disabled via the **Enable** terminal.

In **Digital** mode the drive is enabled and disabled when the signal on the **Enable** terminal and the **Digital Enable** command are present simultaneously.

In **Keypad** mode the drive is enabled if the hardware is enabled on the **Enable** terminal and the **Start** key is pressed.

In **Keypad** mode it is disabled if the hardware is not enabled on the **Enable** terminal or if the **Stop** key is pressed twice.

If **1 Stop/FS&Spd = 0** is set:

In **Terminal** mode the drive is enabled when the hardware is enabled on the **Enable** terminal, on the terminal programmed as **Terminal Start** and the **FastStop** terminal must not be enabled.

In **Terminal** mode the drive is instantly disabled if there is no signal on the **Enable** terminal, or when speed=0 is reached if the **Start command** is disabled or the terminal programmed as **FastStop** is enabled.

In **Digital** mode the drive is enabled when the hardware is enabled on the **Enable** terminal, the **Digital Enable**,
In **Digital** mode the drive is instantly disabled if there is no signal on the **Enable** terminal, or when speed=0 is reached if the **Digital Start** command is disabled or the terminal programmed as **FastStop** is enabled.

In **Keypad** mode the drive is enabled if the hardware is enabled on the **Enable** terminal and the **Start** key is pressed, with the command disabled on the **FastStop** terminal.

In **Keypad** mode the drive is disabled instantly if the signal is not present on the **Enable** terminal or the **Stop** key is pressed twice.

If **2 Stop&Spd = 0** is set:

In **Terminal** mode the drive is enabled if the hardware is enabled on the **Enable** terminal and the signal is enabled on the terminal programmed as **Terminal Start**.

In **Terminal** mode the drive is instantly disabled if there is no signal on the **Enable** terminal, or if, upon reaching the speed=0, the **Terminal Start** command is disabled.

In **Digital** mode the drive is enabled when the hardware is enabled on the **Enable** terminal and the **Digital Enable** and **DigitalStart** signals are present.

In **Digital** mode the drive is instantly disabled if the signal is not present on the **Enable** terminal, or the **Digital Enable** command is not present, or upon reaching the speed=0 if the **Digital Start** command is set to 0.

In **Keypad** mode the drive is enabled when the hardware is enabled on the **Enable** terminal and the **Start** key is pressed.

In **Keypad** mode the drive is instantly disabled if the signal is not present on the **Enable** terminal or the **Stop** key is pressed twice, or when the speed=0 is reached if the **Stop** key is pressed.

If **3 FS&Spd = 0** is set:

In **Terminal** mode the drive is enabled when the hardware is enabled on the **Enable** terminal and the **FastStop**

terminal is not enabled.

In **Terminal** mode the drive is instantly disabled if there is no signal on the **Enable** terminal, or when the speed=0 is reached if the terminal programmed as **FastStop** is enabled.

In **Digital** mode the drive is enabled if the hardware is enabled on the **Enable** terminal and the **Digital Enable** signal is present, with the command on the **FastStop** terminal disabled.

In **Digital** mode the drive is instantly disabled if there is no signal on the **Enable** terminal, or no **Digital Enable** command, or when the speed=0 is reached if the **Digital Start** command is set to 0.

In **Keypad** mode the drive is enabled if the hardware is enabled on the **Enable** terminal and the **Start** key is pressed, with the **FastStop** command disabled.

In **Keypad** mode the drive is instantly disabled if there is no signal on the **Enable** terminal or the **Stop** key is pressed twice, or if, when the speed=0 is reached, the terminal programmed as **FastStop** is enabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.4	1006	Speed 0 disable dly	ms	UINT16		1000	0	10000	ERW	FVS

Setting of a delay in milliseconds between reaching the zero speed and disabling the drive when **Enable/Disable mode** is set to a value other than **Off**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.5	1008	Stop key mode		ENUM		Inactive	0	1	ERW	FVS

Setting of the stop key functioning on the keypad. In Local with command from Keypad , this configuration is ineffective.

Active in remote control mode (PAR 1012=1) both by using "Terminals" command or "Digital" commands and, in local control mode (PAR 1012=0) by using "Terminals" command.

0 Inactive

1 EmgStop&Alarm

If the command is set to **Inactive**, pressing the Stop key on the keypad is ineffective.

If the command is set to **EmgStop&Alarm**, when the Stop key is pressed the motor stops in FastStop mode and the **Emg stop alarm** is generated. When the motor reaches the speed=0, the drive is automatically disabled and waits for the **Fault reset** command. The **Fault reset** command must be sent twice to reset the drive.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.6	1010	Commands safe start		BIT		1	0	1	ERW	FVS

This parameter is used to define whether the safe start command is disabled or enabled at drive power-on.

0 Off

1 On

If set to **Off**, the safe start command is disabled. If the drive is powered-on with the hardware enabled on the **Enable** terminal, the motor could start rotating.

When set to **On**, the safe start command is enabled. If the drive is powered-on with the hardware enabled on the **Enable** terminal, the motor will not rotate. To set the drive to accept subsequent commands, open the hardware enabling contact on the **Enable** terminal and then close it again.

If the drive is restarted (and the Enable command is present), message [23] **Safe start active** is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.7	1012	Dig local/remote		ENUM	16	Remote	0	1	ERW	FVS

Setting **Local** or **Remote** operating mode.

0 Local

1 Remote

Writing this parameter is only effective if it is associated with **Local/Remote src** and if performed without the hardware enabled on the **Enable** terminal. Press LOC to modify the value of this parameter 0<->1.

To disable the LOC key, set **Local/Remote src** to a value other than **Dig local/remote**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.8	1014	Local/remote src		LINK	16	1012	0	16384	ERW	FVS
Selection of the origin (source) of the signal that switches between Remote and Local. Switching can only be performed if the hardware is not enabled on the Enable terminal. The signal to be associated with this function can be selected from the “L_DIGSEL3” selection list. 0 Local 1 Remote In Remote mode the “Commands remote sel” parameter is used to configure the source of the Enable and Start commands, which can be Terminal (standard digital input, expansion digital input) or Digital (Modbus, Fieldbus, Profile DS402, Profile profidrive). In Local mode the “Commands local sel” parameter is used to configure the source of the Enable and Start commands, which can be Terminal (standard digital input, expansion digital input) or Keypad (Start key, Stop key).										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.9	1016	Terminal Start src		LINK	16	1048	0	16384	ERW	FVS
Selection of the origin (source) of the Terminal Start signal. Switching can only be performed if the hardware is not enabled on the Enable terminal. The signal to be associated with this function can be selected from the “L_DIGSEL3” selection list. In the default condition, the origin of the Terminal Start signal is the Start output of the ForwardReverseControl (FRC) block.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.10	1018	Digital Enable src		LINK	16	6000	0	16384	ERW	FVS
Selection of the origin (source) of the signal that defines the enabling of the drive when the commands are sent via serial line or fieldbus. The command to be associated with this function can be selected from the “L_DIGSEL2” selection list.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.11	1020	Digital Start src		LINK	16	6000	0	16384	ERW	FVS
Selection of the origin (source) of the Digital Start signal. The signal to be associated with this function can be selected from the “L_DIGSEL2” selection list.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.12	1022	FastStop src		LINK	16	6000	0	16384	ERW	FVS
Selection of the origin (source) for the fast stop signal (FastStop). The terminal to be associated with this function can be selected from the “L_DIGSEL2” selection list. During the execution of the FastStop command the ramps used are Acceleration time 3 and Deceleration time 3. The FastStop mode (PAR 1036) parameter can be used to define the specific operating modes for automatic motor restart.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.13	1024	Enable cmd mon		BIT	16	0	0	1	R	FVS
The status of the enable command is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.14	1026	Start cmd mon		BIT	16	0	0	1	R	FVS
The status of the Start command is displayed.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.15	1028	FastStop cmd mon		BIT	16	0	0	1	R	FVS

This parameter is used to display the value of the FastStop command state.

- 0 FastStop not active
- 1 FastStop active

If the “FastStop mode” parameter is set to 0 = “Not Latched”, the value of the FastStop command monitor changes to 1 when the FastStop input is activated and remains high (1) until the Enable or FastStop inputs are deactivated (0 state).

If the “FastStop mode” parameter is set to 1 = “Latched”, the value of the FastStop command monitor changes to 1 when the FastStop input is activated and remains high (1) until the Enable, Start, FastStop inputs are deactivated (0 state).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.16	1054	Safe start mon		BIT	16	0	0	1	ER	FVS

Display of state of “check safe start” function:

- 0 Disable
- 1 Enable

The function is enabled with PAR 1010 **Commands safe start**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.17	1040	FR mode		ENUM		Normal	0	2	ERWZ	FVS

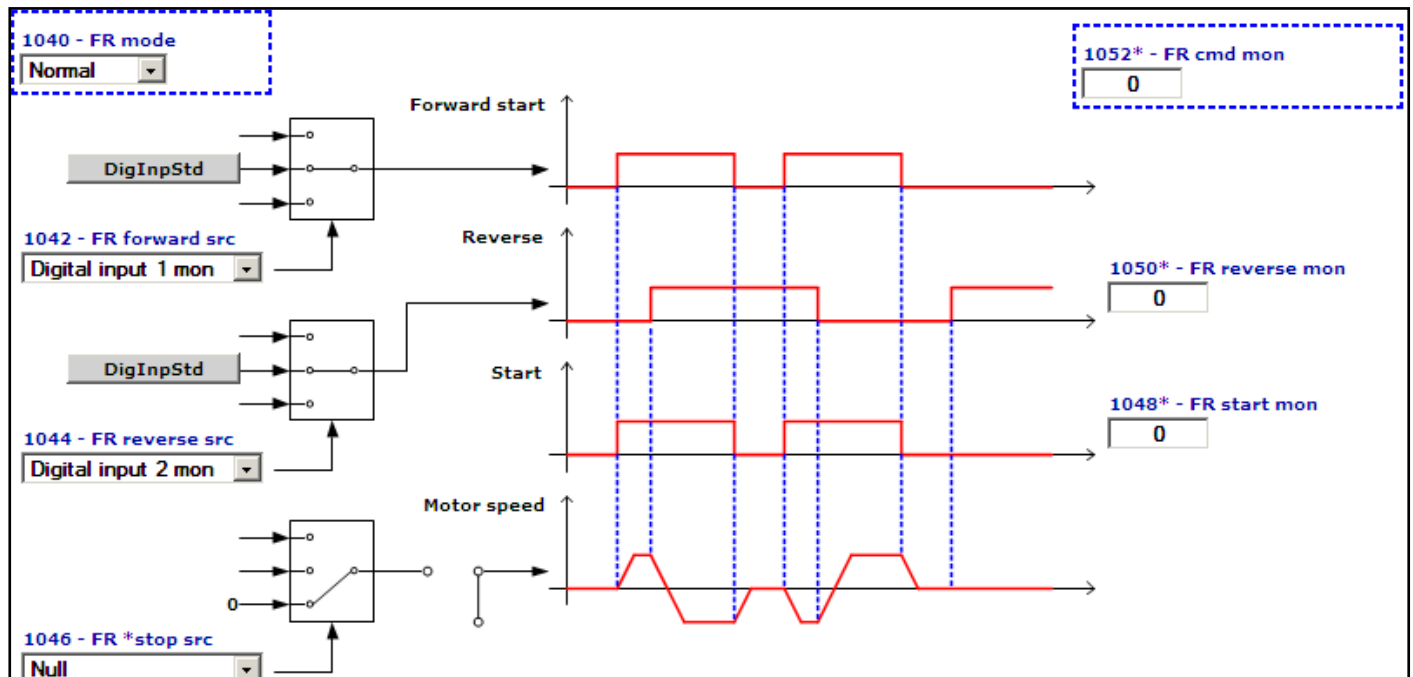
Setting of the operating mode of the Forward Reverse Control (FRC) block.

- 0 Normal
- 1 Two wire Two wire control
- 2 Three wire Three wire control

The default use of the FRC block is shown below.

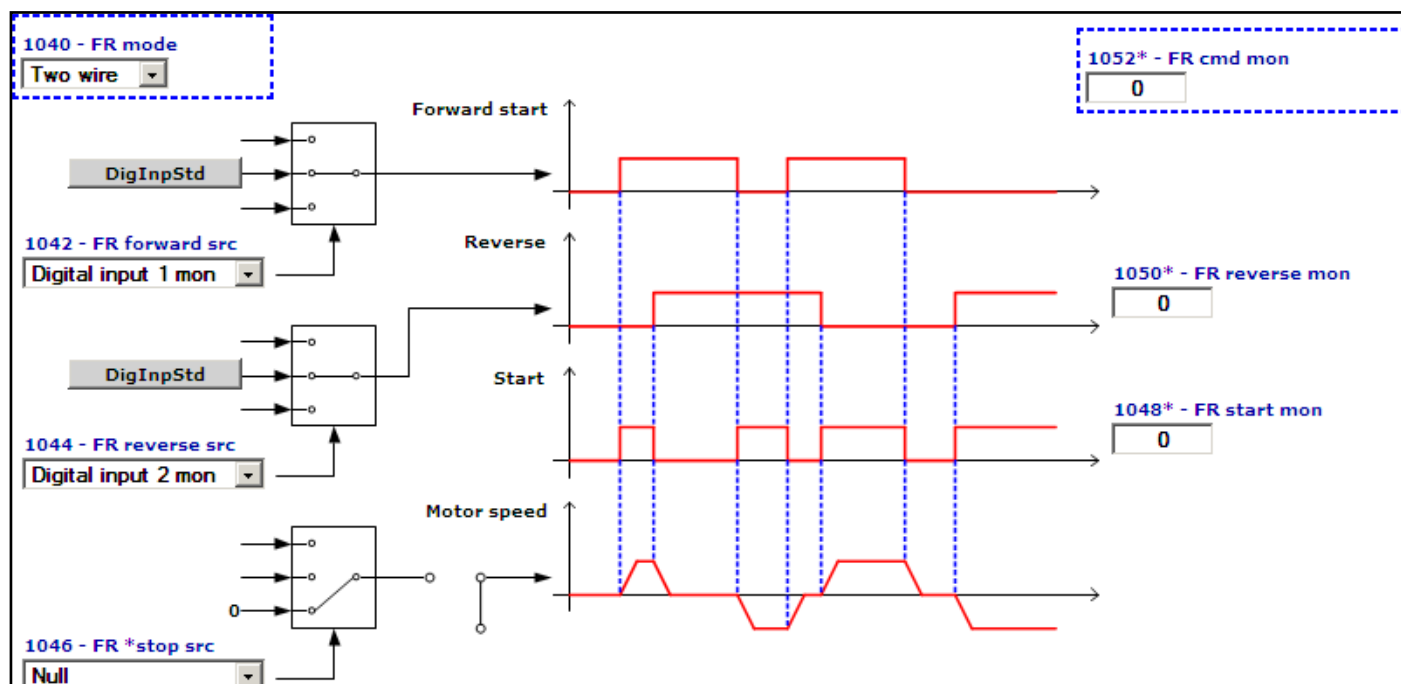
The Start command is linked to the Start terminal and the Reverse command is linked to Ramp ref invert.

The function diagrams of the 3 modes are shown below.



When 0 - **Normal** control is set the motor only starts rotating when the **FR Forward** command is sent. If the **FR Reverse** command is present the motor rotates in the reverse direction,

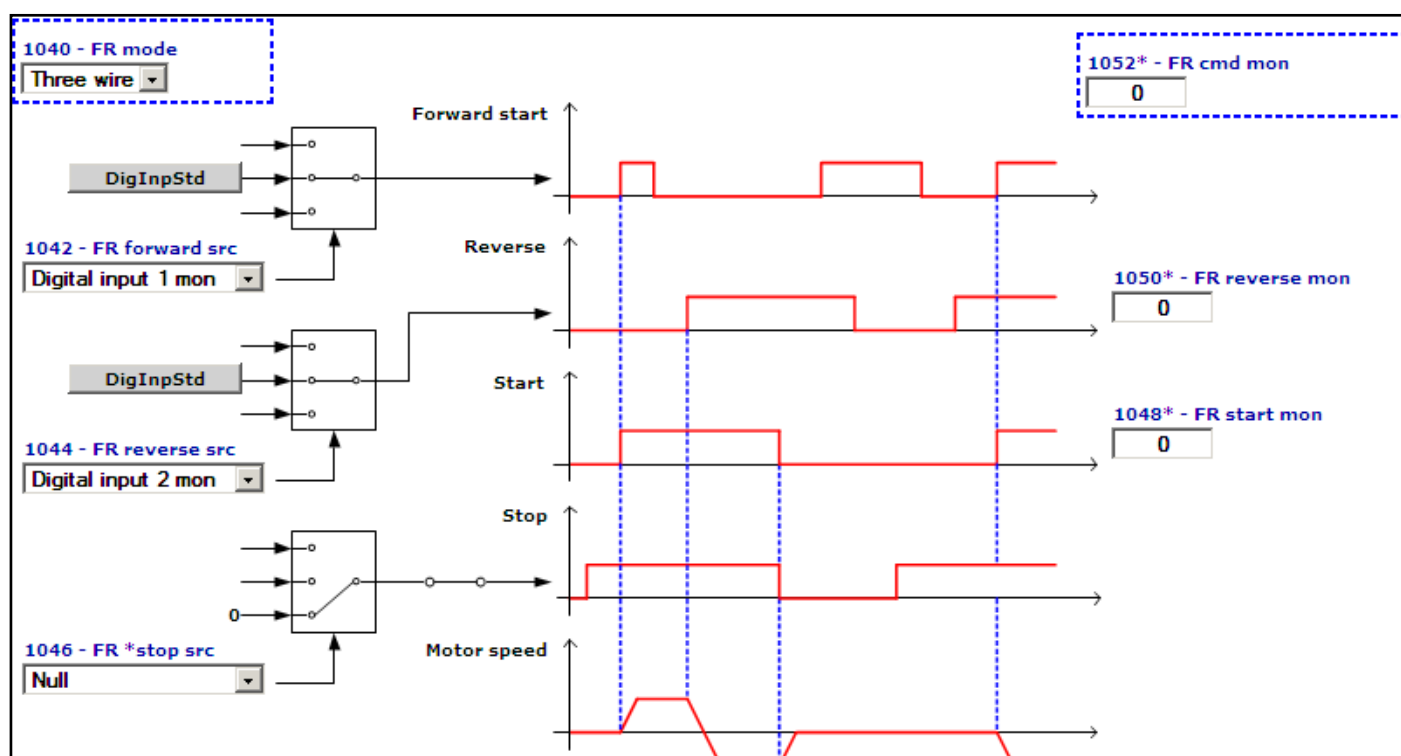
The **FR start mon** output repeats the status of the **FR Forward** command, while the **FR reverse mon** output repeats the status of the **FR Reverse** command.



When set to **1 - Two wire** control, the motor only rotates if the **FR Forward** command or **FR Reverse** command is present. The simultaneous presence of the **FR Forward** and **FR Reverse** commands causes the motor to stop.

The **FR start mon** output is enabled if the **FR Forward** and **FR Reverse** commands are not present simultaneously.

The **FR reverse mon** output repeats the status of the **FR Reverse** command.



For **2 - Three wire** control the **FR *stop** command must be present on a digital input programmed via the **FR *stop src** parameter (not present in the default condition). When set to **Three wire** control, the motor starts upon receiving an impulse of not less than 50 msec on the **FR Forward** terminal. Once the motor has started the command is no longer necessary on the **FR Forward** terminal. To reverse the direction of rotation enable the **FR Reverse** command: the motor will be brought to the zero speed with the set ramp and will restart in the opposite direction of rotation. The motor rotates in the Reverse direction for as long as the **FR Reverse** signal is enabled. If the **FR Reverse** signal is disabled the motor rotates in the **Forward** direction. To stop the motor open the **FR *stop** contact.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.18	1042	FR forward src		LINK	16	1112	0	16384	ERW	FVS

Selection of the origin (source) for the FR forwardstart signal. With this command the motor starts to rotate (with the **Enable** command enabled). The terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.19	1044	FR reverse src		LINK	16	1114	0	16384	ERW	FVS

Selection of the origin (source) for the FR reverse signal. With this command the motor reverses the direction of rotation (with the **Enable** command enabled). The terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.20	1046	FR *stop src		LINK	16	6000	0	16384	ERW	FVS

Selection of the origin (source) for the FR stop signal. The terminal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.21	1048	FR start mon		BIT	16	0	0	1	ER	FVS

The status of the Start output of the **Forward Reverse Control (FRC)** block is displayed.

0 Stop

1 Start

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.22	1050	FR reverse mon		BIT	16	0	0	1	ER	FVS

The status of the Reverse output of the **Forward Reverse Control (FRC)** block is displayed.

0 No Reverse

1 Reverse

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.23	1052	FR cdm mon		UINT16		0	0	0	ER	FVS

The status of the commands of the **Forward Reverse Control (FRC)** block are displayed.

FR *stop src	FR reverse src	FR forward src	FR cdm mon
0	0	0	0
0	0	1	1
0	1	0	2
0	1	1	3
1	0	0	4
1	0	1	5
1	1	0	6
1	1	1	7

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.24	1032	Drv Interlock src		LINK	16	6002	0	16384	ERW	FVS

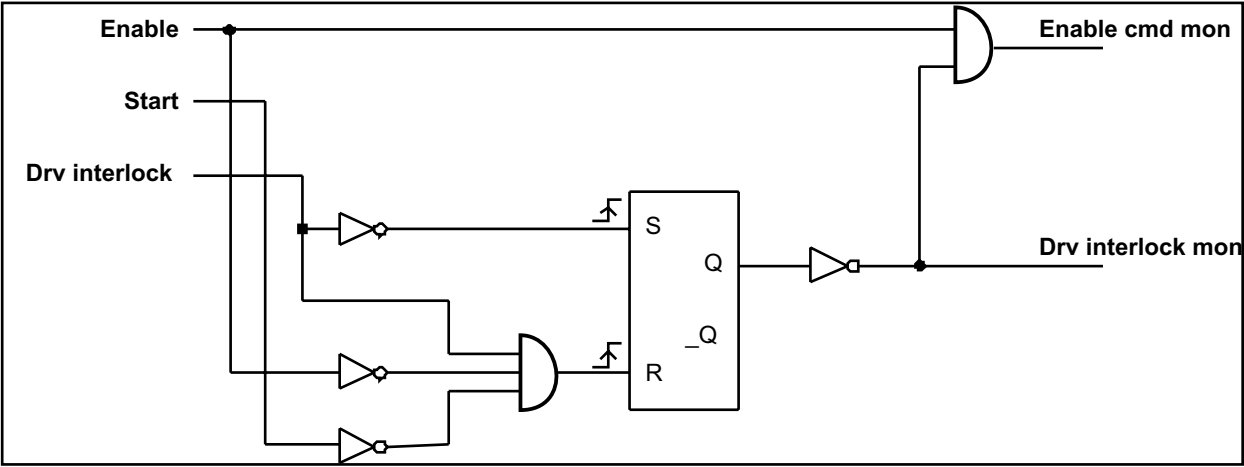
This parameter is used to select the origin (source) of the Drv Interlock signal.

The signal to be associated with this function can be selected from the “**L_DIGSEL2**” selection list.

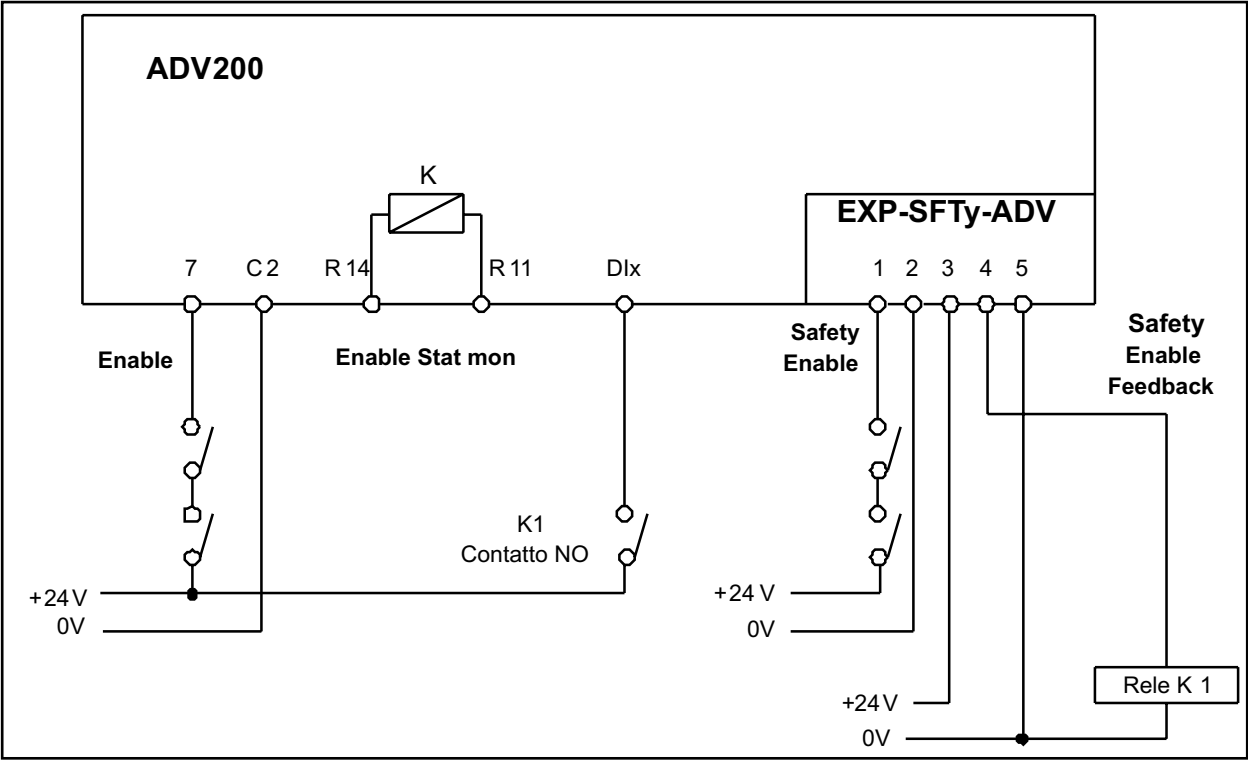
0 Drive interlock active (Drive disabled)

1 Drive interlock not active (Drive can be enabled)

If the Drive Interlock command is active, the drive cannot be enabled (Drive Enable command).
 If the Drive Interlock command is not active, the drive can be enabled by applying the Drive enable command.
 In default conditions the “**Drv Interlock src**” signal is connected to “One”. In this configuration the Drive interlock function is not active and the drive can only be enabled with the “Enable” command.



The **Drv Interlock** signal, with the “**EXP-SFTy-ADV**” (ADV200.....-SI series) safety card, is used to disable the drive under certain conditions and to prevent any dangerous situations from arising.
 The drive reads the state of the Safety card via the **Drv Interlock src** input
 The EXP-SFTy-ADV card can be connected to the drive as shown in the figure below.



If the “Drv Interlock” command is active (low state = 0) the drive is disabled immediately. To enable the drive again, set the “Drv Interlock” command to the high state (1) (Drive interlock not active) and the “Enable” and “Start” commands to the 0 state (Disabled and Stop) and then to the high state (1).
 The “Drv Interlock” command must be sent before the “Enable” command.
 The EXP-SFTy-ADV card supplies the Safety Enable Feedback digital output as shown in the following table.

Safety Enable	Safety Enable Feedback	Description
Open	0V	Safety function active The drive does not supply current
+24V	+24V	Safety function not active The drive can supply current

A relay (K1) can be used to repeat the safety card feedback signal. A normally open (NO) contact of the relay can be connected to a drive input set to “**Drv Interlock src**”.

If the **Safety card is active** (the drive does not supply current) the Safety Enable Feedback digital output is set to low (0), the relay is not excited and the NO contact is open.

When the “Drv interlock” signal receives a low command (0) (Drive interlock active) the drive is disabled.

The “**Drv Interlock src**” can be used to know the instantaneous state of the Safety Enable Feedback function.

The “**Drv interlock mon**” parameter can be used to know the state of the Safety Enable Feedback function taking into account the interlocking logic with the drive Enable command.

0 Drive interlock active (the Safety card is active)

1 Drive interlock not active (the Safety card is not active)

In “**Drv interlock mon**” the Drive interlock state remains active until the Safety card is deactivated and the “Enable” and “Start” commands are set to low (0).

The drive remains disabled until the “Drv Interlock” command is set to the high state (1) (Drive interlock not active) and the “Enable” and “Start” commands to the low state (0) (Disabled and Stop) and then to the high state (1).

If the **Safety card is not active** (the drive can supply current) the Safety Enable Feedback digital output is set to high (1), the relay is excited and the NO contact is closed.

The “Drv interlock” signal receives a high (1) signal (Drive interlock not active), the drive can be enabled by applying the drive enable command.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.25	1034	Drv interlock mon		BIT	16	0	0	1	ER	FVS

In “**Drv interlock mon**” the Drive interlock state remains active until the Safety card is deactivated and the “Enable” and “Start” commands are set to low (0).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
11.26	1036	FastStop mode		ENUM		Not Latched	0	1	ERW	FVS

This parameter is used to select the operating mode of the FastStop command.

0 Not Latched

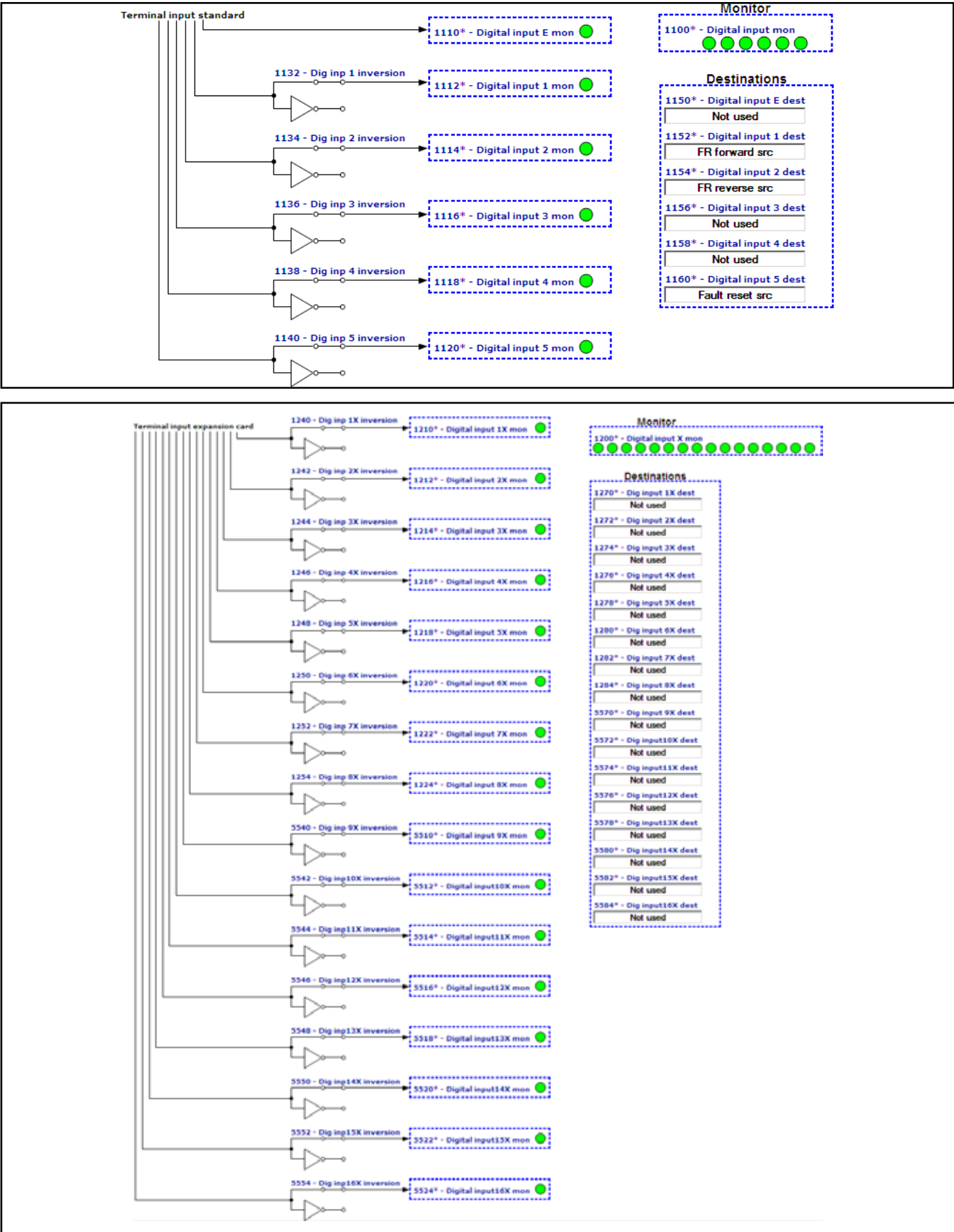
1 Latched

If set to 0 (Not Latched), the FastStop command is not stored. Therefore, if the FastStop command is removed the drive automatically restarts.

If set to 1 (Latched) the FastStop command is stored. If the FastStop command is removed, the drive will not restart automatically. It can only restart after removing the FastStop command and sending a new Enable and Start command.

12 – DIGITAL INPUTS

Note: The numbering and description of the following parameters may change if an MDPLc application is active.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
12.1	1132	Dig inp 1 inversion		BIT		0	0	1	RW	FVS
12.2	1134	Dig inp 2 inversion		BIT		0	0	1	RW	FVS
12.3	1136	Dig inp 3 inversion		BIT		0	0	1	RW	FVS
12.4	1138	Dig inp 4 inversion		BIT		0	0	1	RW	FVS
12.5	1140	Dig inp 5 inversion		BIT		0	0	1	RW	FVS

Reversal of the logic status of the function associated with the digital input (e.g. from enabled with +24V signal to enabled with low signal).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
12.6	1150	Digital input E dest		ILINK		0	0	0	ER	FVS
12.7	1152	Digital input 1 dest		ILINK		0	0	0	ER	FVS
12.8	1154	Digital input 2 dest		ILINK		0	0	0	ER	FVS
12.9	1156	Digital input 3 dest		ILINK		0	0	0	ER	FVS
12.10	1158	Digital input 4 dest		ILINK		0	0	0	ER	FVS
12.11	1160	Digital input 5 dest		ILINK		0	0	0	ER	FVS

The function to which the associated digital input refers is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
12.12	1240	Dig inp 1X inversion		BIT		0	0	1	RW	FVS
12.13	1242	Dig inp 2X inversion		BIT		0	0	1	RW	FVS
12.14	1244	Dig inp 3X inversion		BIT		0	0	1	RW	FVS
12.15	1246	Dig inp 4X inversion		BIT		0	0	1	RW	FVS
12.16	1248	Dig inp 5X inversion		BIT		0	0	1	RW	FVS
12.17	1250	Dig inp 6X inversion		BIT		0	0	1	RW	FVS
12.18	1252	Dig inp 7X inversion		BIT		0	0	1	RW	FVS
12.19	1254	Dig inp 8X inversion		BIT		0	0	1	RW	FVS
12.20	5540	Dig inp 9X inversion		BIT		0	0	1	RW	FVS
12.21	5542	Dig inp 10X inversion		BIT		0	0	1	RW	FVS
12.22	5544	Dig inp 11X inversion		BIT		0	0	1	RW	FVS
12.23	5546	Dig inp 12X inversion		BIT		0	0	1	RW	FVS
12.24	5548	Dig inp 13X inversion		BIT		0	0	1	RW	FVS
12.25	5550	Dig inp 14X inversion		BIT		0	0	1	RW	FVS
12.26	5552	Dig inp 15X inversion		BIT		0	0	1	RW	FVS
12.27	5554	Dig inp 16X inversion		BIT		0	0	1	RW	FVS

These parameters invert the state of the corresponding digital input of the expansion card.

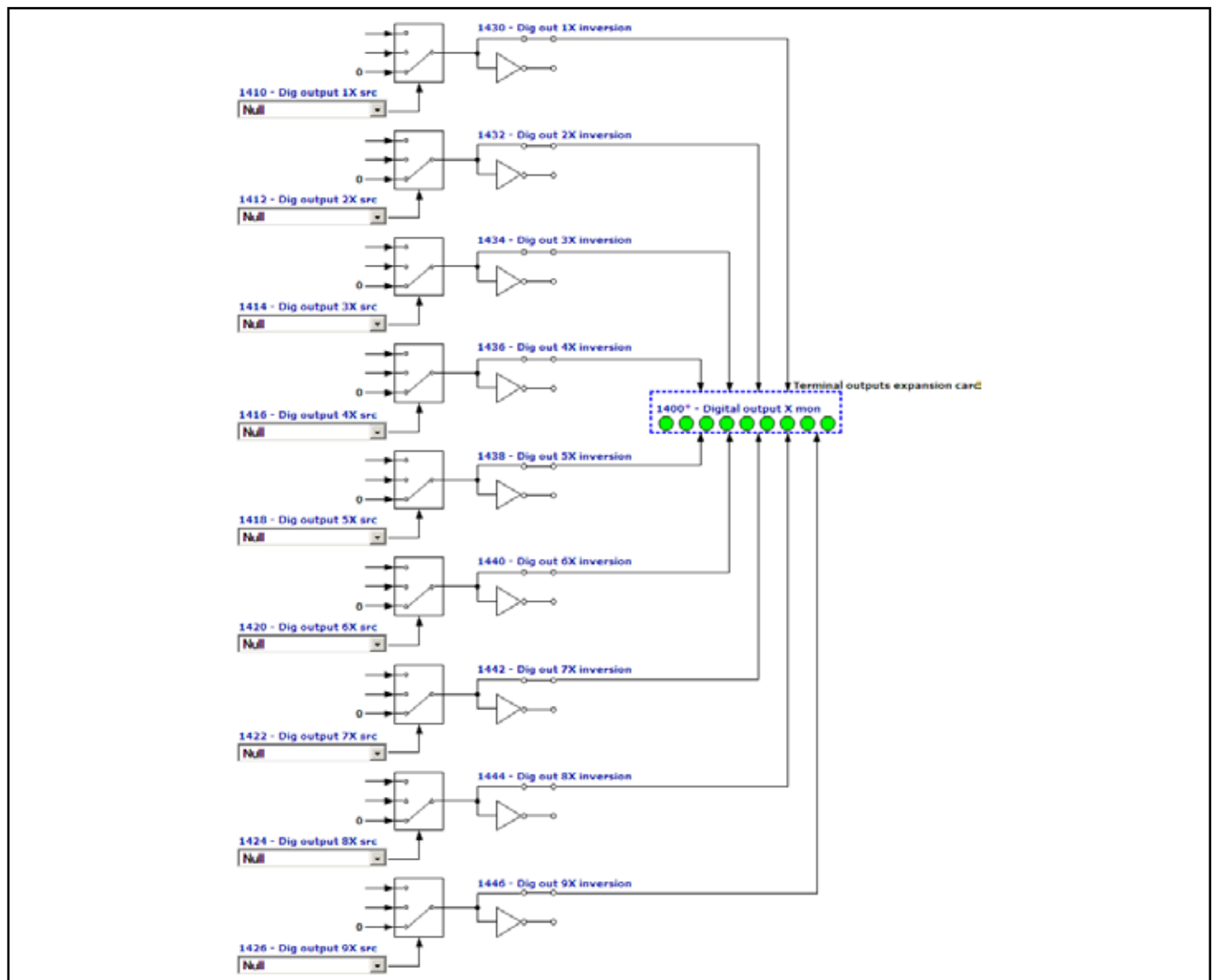
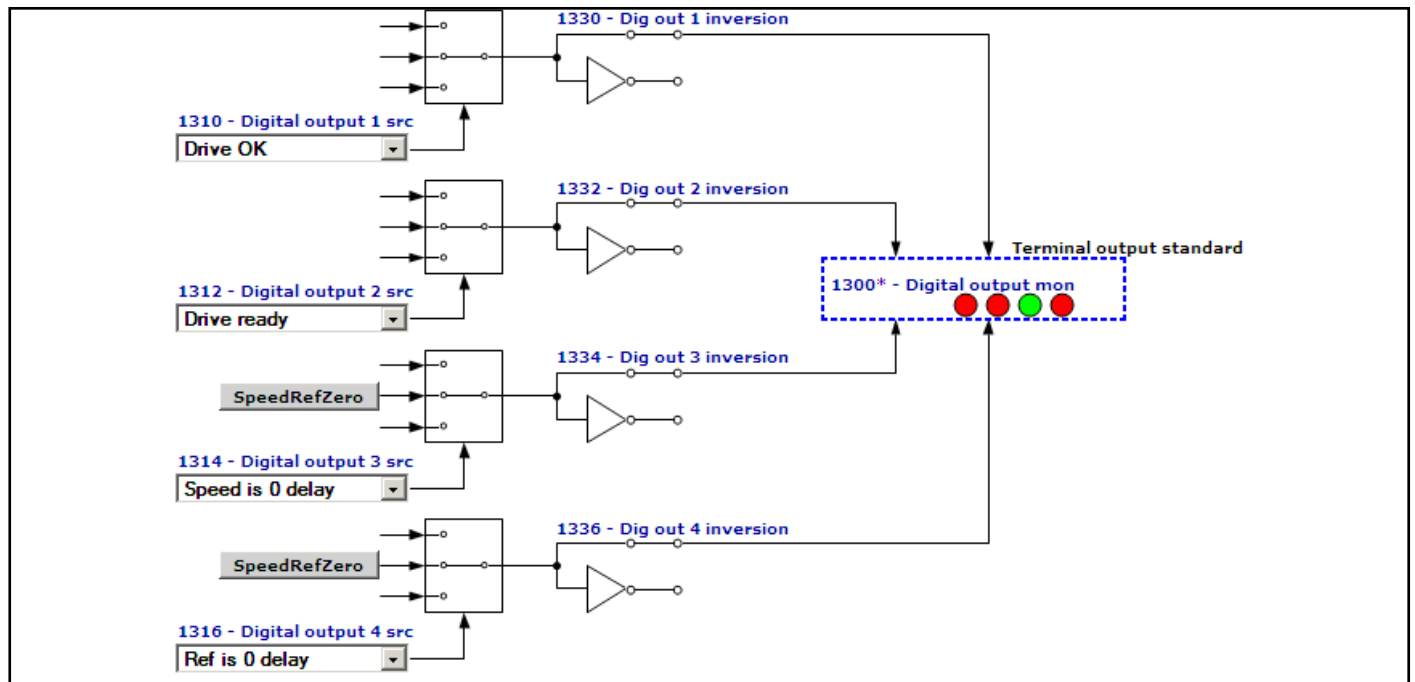
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
12.28	1270	Dig input 1X dest		ILINK		0	0	0	ER	FVS
12.29	1272	Dig input 2X dest		ILINK		0	0	0	ER	FVS
12.30	1274	Dig input 3X dest		ILINK		0	0	0	ER	FVS
12.31	1276	Dig input 4X dest		ILINK		0	0	0	ER	FVS
12.32	1278	Dig input 5X dest		ILINK		0	0	0	ER	FVS
12.33	1280	Dig input 6X dest		ILINK		0	0	0	ER	FVS
12.34	1282	Dig input 7X dest		ILINK		0	0	0	ER	FVS
12.35	1284	Dig input 8X dest		ILINK		0	0	0	ER	FVS
12.36	5570	Dig input 9X dest		ILINK		0	0	0	ER	FVS
12.37	5572	Dig input 10X dest		ILINK		0	0	0	ER	FVS

12.38	5574 Dig input 11X dest	ILINK	0	0	0	ER	FVS
12.39	5576 Dig input 12X dest	ILINK	0	0	0	ER	FVS
12.40	5578 Dig input 13X dest	ILINK	0	0	0	ER	FVS
12.41	5580 Dig input 14X dest	ILINK	0	0	0	ER	FVS
12.42	5582 Dig input 15X dest	ILINK	0	0	0	ER	FVS
12.43	5584 Dig input 16X dest	ILINK	0	0	0	ER	FVS

These parameters show which “src” parameter is using the corresponding digital input of the expansion card.

13 – DIGITAL OUTPUTS

Note: The numbering and description of the following parameters may change if an MDPLc application is active.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
13.1	1310	Digital output 1 src		LINK	16	1062	0	16384	RW	FVS
13.2	1312	Digital output 2 src		LINK	16	1064	0	16384	RW	FVS
13.3	1314	Digital output 3 src		LINK	16	946	0	16384	RW	FVS
13.4	1316	Digital output 4 src		LINK	16	936	0	16384	RW	FVS

Selection of the origin (source) of the signal to be assigned to the relative digital output. The functions that can be associated with the digital outputs are listed in the “**L_DIGSEL1**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
13.5	1330	Dig out 1 inversion		BIT		0	0	1	RW	FVS
13.6	1332	Dig out 2 inversion		BIT		0	0	1	RW	FVS
13.7	1334	Dig out 3 inversion		BIT		0	0	1	RW	FVS
13.8	1336	Dig out 4 inversion		BIT		0	0	1	RW	FVS

Reversal of the logic status of the function associated with the digital output.

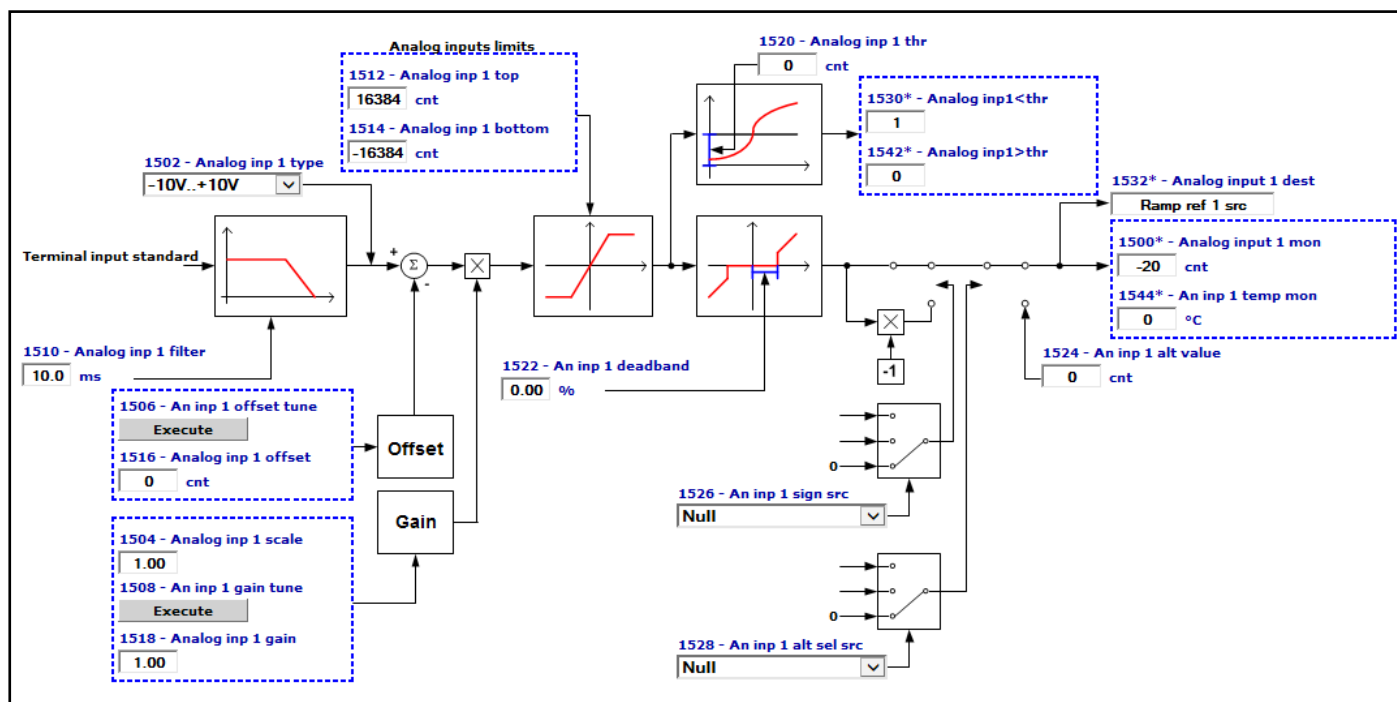
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
13.9	1410	Dig output 1X src		LINK	16	6000	0	16384	RW	FVS
13.10	1412	Dig output 2X src		LINK	16	6000	0	16384	RW	FVS
13.11	1414	Dig output 3X src		LINK	16	6000	0	16384	RW	FVS
13.12	1416	Dig output 4X src		LINK	16	6000	0	16384	RW	FVS
13.13	1418	Dig output 5X src		LINK	16	6000	0	16384	RW	FVS
13.14	1420	Dig output 6X src		LINK	16	6000	0	16384	RW	FVS
13.15	1422	Dig output 7X src		LINK	16	6000	0	16384	RW	FVS
13.16	1424	Dig output 8X src		LINK	16	6000	0	16384	RW	FVS
13.17	1426	Dig output 9X src		LINK	16	6000	0	16384	RW	FVS

Selection of the origin (source) of the signal to be assigned to the relative digital output of the expansion card. The functions that can be associated with the digital outputs are listed in the “**L_DIGSEL1**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
13.18	1430	Dig out 1X inversion		BIT		0	0	1	RW	FVS
13.19	1432	Dig out 2X inversion		BIT		0	0	1	RW	FVS
13.20	1434	Dig out 3X inversion		BIT		0	0	1	RW	FVS
13.21	1436	Dig out 4X inversion		BIT		0	0	1	RW	FVS
13.22	1438	Dig out 5X inversion		BIT		0	0	1	RW	FVS
13.23	1440	Dig out 6X inversion		BIT		0	0	1	RW	FVS
13.24	1442	Dig out 7X inversion		BIT		0	0	1	RW	FVS
13.25	1444	Dig out 8X inversion		BIT		0	0	1	RW	FVS
13.26	1444	Dig out 9X inversion		BIT		0	0	1	RW	FVS

Reversal of the logic status of the function associated with the digital output of the expansion card.

14 – ANALOG INPUTS



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.1	1500	Analog input 1 mon	cnt	INT16	16/32	0	0	0	R	FVS
14.17	1550	Analog input 2 mon	cnt	INT16	16/32	0	0	0	R	FVS

The value of the voltage on the output of the function block of the relative analog input is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.2	1502	Analog inp 1 type		ENUM		-10V...+10V	0	2	RW	FVS
14.18	1552	Analog inp 2 type		ENUM		-10V...+10V	0	2	RW	FVS

Selection of the type of input (voltage or current). Depending on the input signal, move the switches on the regulation card. The factory parameter is inputs set for differential voltage signals ($\pm 10V$).

- 0 -10V...+10V
- 1 0,20mA ... 10V
- 2 4...20mA
- 3 0.1V...10.1V
- 4 KTY84

Select option **0** in order to connect a maximum voltage of $\pm 12.5V$ (typically $\pm 10V/5mA$) to the analog input concerned. If the signal is used as a reference, reverse the direction of rotation by inverting the voltage polarity.

With this selection, the analog input can acquire the temperature of motor with KTY84 / PTC sensor. (An analog output need to be used as power supply signal).

Additional info are available through the Quick startup manual.

Select option **1** to connect a max voltage of 12.5V (typically 10V/5mA) or a signal in current from 0 ... 20 mA to the analog input concerned. The signal must be positive.

Select option **2** to connect a current signal of 4...20 mA to the analog input concerned. The signal must be positive.

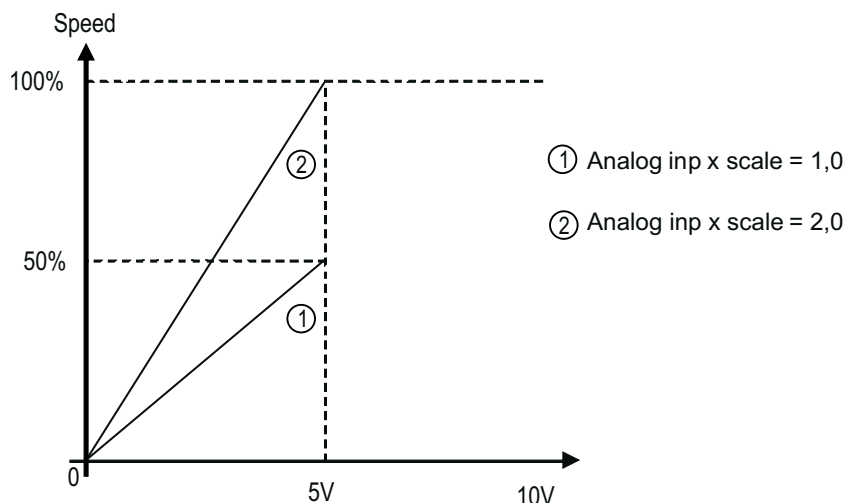
Select option **3** to connect 0.1V...10.1V to the analog input in use. You can also detect signal loss (due to disconnection or short circuit) with alarm [62] **AnalogInpLoss**.

Select option **4** to connect a KTY84 temperature sensor to the analog input in use (you have to use an analog output as power supply signal). You can also detect signal loss (due to disconnection or short circuit) with alarm [62] **AnalogInpLoss**.

NOTE! See chapter 7.2 of Quick startup manual for setting as readding of a temperature sensor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.3	1504	Analog inp 1 scale		FLOAT		1.0	-10.0	10.0	RW	FVS
14.19	1554	Analog inp 2 scale		FLOAT		1.0	-10.0	10.0	RW	FVS

Setting of a multiplier factor to apply to the relative analog input.



Example:

The speed reference of a drive is assigned with a max external voltage of 5V. With this value the drive must reach the maximum speed allowed (set using **Full scale speed**).

As the **Analog inp x scale** parameter a scale factor of 2 is entered (10V : 5V)

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.4	1506	An inp 1 offset tune		BIT		0	0	1	RW	FVS
14.20	1556	An inp 2 offset tune		BIT		0	0	1	RW	FVS

Self-tuning command for the relative analog input offset. Automatic fine tuning of the input. To perform self-tuning, set the input signal to its minimum value and execute the command. The conditions containing an offset can be compensated. When this command is sent, **An inp x offset tune** is automatically selected so that the available input signal corresponds to the zero value of the variable. Offset tuning can also be performed with the drive enabled.

Automatic tuning can only be performed if the following condition is present:

- Input voltage less than 1V or input current less than 2 mA

Note ! The value that is obtained automatically can be changed manually if necessary, using **Analog inp x offset**.

If the voltage setting on the analog input is higher than 1V, the Value too low alarm is generated.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.5	1508	An inp 1 gain tune		BIT		0	0	1	RW	FVS
14.21	1558	An inp 2 gain tune		BIT		0	0	1	RW	FVS

Self-tuning command for the relative analog input gain. Automatic fine tuning of the input. When this command is sent, **Analog inp 1 gain x** is automatically selected so that the available input signal corresponds to the maximum value of the variable. Offset tuning can also be performed with the drive enabled.

Two conditions are necessary in order to perform automatic tuning:

- Input voltage greater than 1V or input current greater than 2 mA
- Positive polarity. The value that is found is automatically accepted for the other direction of rotation.

Note ! If necessary, the value obtained automatically can be changed manually via **Analog inp x gain**.

To perform self-tuning, set the input signal to its maximum value and execute the command. A multiplier factor

is calculated to apply to the input signal value (not considering the **Analog inp scale** parameter) to reach the full scale value.

If the voltage setting on the analog input is less than 1V, the Value too low alarm is generated.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.6	1510	Analog inp 1 filter	ms	FLOAT		10.0	1.0	1000.0	ERW	FVS
14.22	1560	Analog inp 2 filter	ms	FLOAT		10.0	1.0	1000.0	ERW	FVS

Filter on the measurement of the corresponding analog input. This parameter can be used to control the response of the analog input and reduce any possible noise and interference.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.7	1512	Analog inp 1 top	cnt	INT16		16384	-32768	+32767	ERW	FVS
14.23	1562	Analog inp 2 top	cnt	INT16		16384	-32768	+32767	ERW	FVS

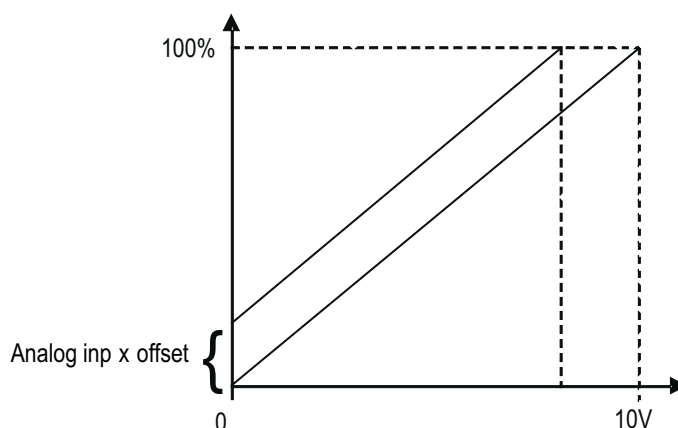
Setting of the upper speed reference limit as a function of the voltage (or current) of the relative analog reference.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.8	1514	Analog inp 1 bottom	cnt	INT16		-16384	-32768	+32767	ERW	FVS
14.24	1564	Analog inp 2 bottom	cnt	INT16		-16384	-32768	+32767	ERW	FVS

Setting of the lower speed reference limit as a function of the voltage (or current) of the relative analog reference.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.9	1516	Analog inp 1 offset	cnt	INT16		0	-32768	+32767	ERW	FVS
14.25	1566	Analog inp 2 offset	cnt	INT16		0	-32768	+32767	ERW	FVS

Setting of a value to compensate the condition in which the analog signal contains an offset, or when the variable assigned to the input already has a value even though no signal is connected.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.10	1518	Analog inp 1 gain		FLOAT		1.0	-10.0	10.0	ERW	FVS
14.26	1568	Analog inp 2 gain		FLOAT		1.0	-10.0	10.0	ERW	FVS

This parameter contains the value of the multiplier factor to apply to the analog reference calculated using the **Analog inp gain tune** function.

Example:

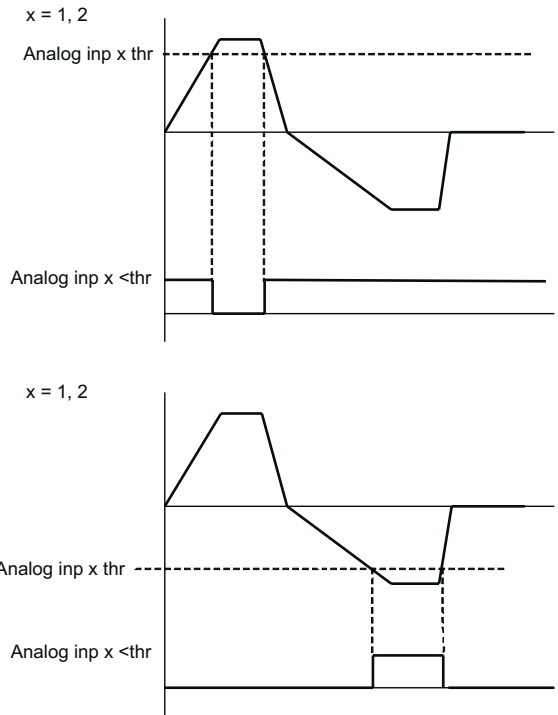
An external analog reference only reaches a maximum of 9.8V instead of 10V. 1.020 (10V : 9.8V) is entered as the **Analog inp x gain** parameter.

The same result can be achieved using the **An inp x gain tune** function. This parameter can be selected from the keypad menu. The maximum analog value available (in this case 9.8V) must be present on the terminal,

with positive polarity. Press the Enter key on the keypad to start analog reference self-tuning.

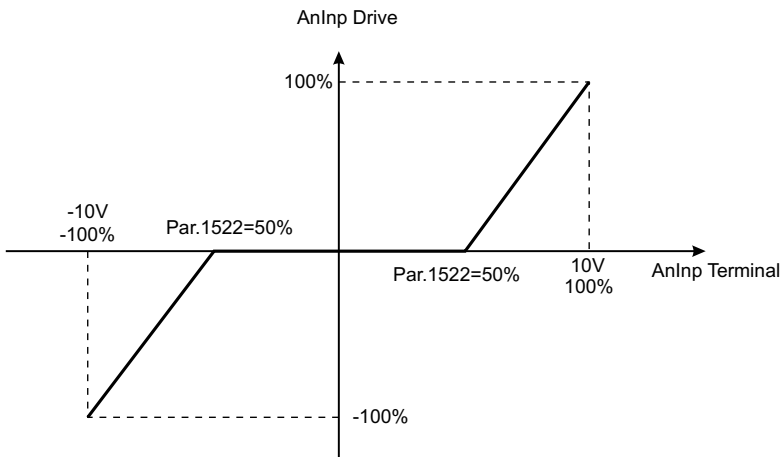
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.11	1520	Analog inp 1 thr		INT16		0	-16384	+ 16383	ERW	FVS
14.27	1570	Analog inp 2 thr		INT16		0	-16384	+ 16383	ERW	FVS

Setting of the analog input threshold for the **speed not exceeded** signal, which allows enabling of the digital outputs **Analog inp1** (par. 1530) and **Analog inp2** (par.1580).



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.12	1522	An inp 1 deadband	perc	FLOAT		0	0	100.0	ERW	FVS
14.28	1572	An inp 2 deadband	perc	FLOAT		0	0	100.0	ERW	FVS

Deadband referring to the analog input signal. When the value on the input terminal is below the threshold defined by the parameter, the output signal of the analog input block is forced to zero. Outside the deadband, the block output varies linearly from zero to 100%.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.13	1524	An inp 1 alt value	cnt	INT16	16/32	0	-16384	16384	ERW	FVS
14.29	1574	An inp 2 alt value	cnt	INT16	16/32	0	-16384	16384	ERW	FVS

Setting of a fixed alternative value for the relative analog input, which can be selected via a command enabled by a digital input programmed with the **An inp alt sel src** parameter.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.14	1526	An inp 1 sign src		LINK	16	6000	0	16384	ERW	FVS
14.30	1576	An inp 2 sign src		LINK	16	6000	0	16384	ERW	FVS

Selection of the origin (source) of the signal to be assigned to the relative digital input for selecting the direction of rotation of the motor. The functions that can be associated with the digital outputs are listed in the “**L_DIG-SEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.15	1528	An inp 1 alt sel src		LINK	16	6000	0	16384	ERW	FVS
14.31	1578	An inp 2 alt sel src		LINK	16	6000	0	16384	ERW	FVS

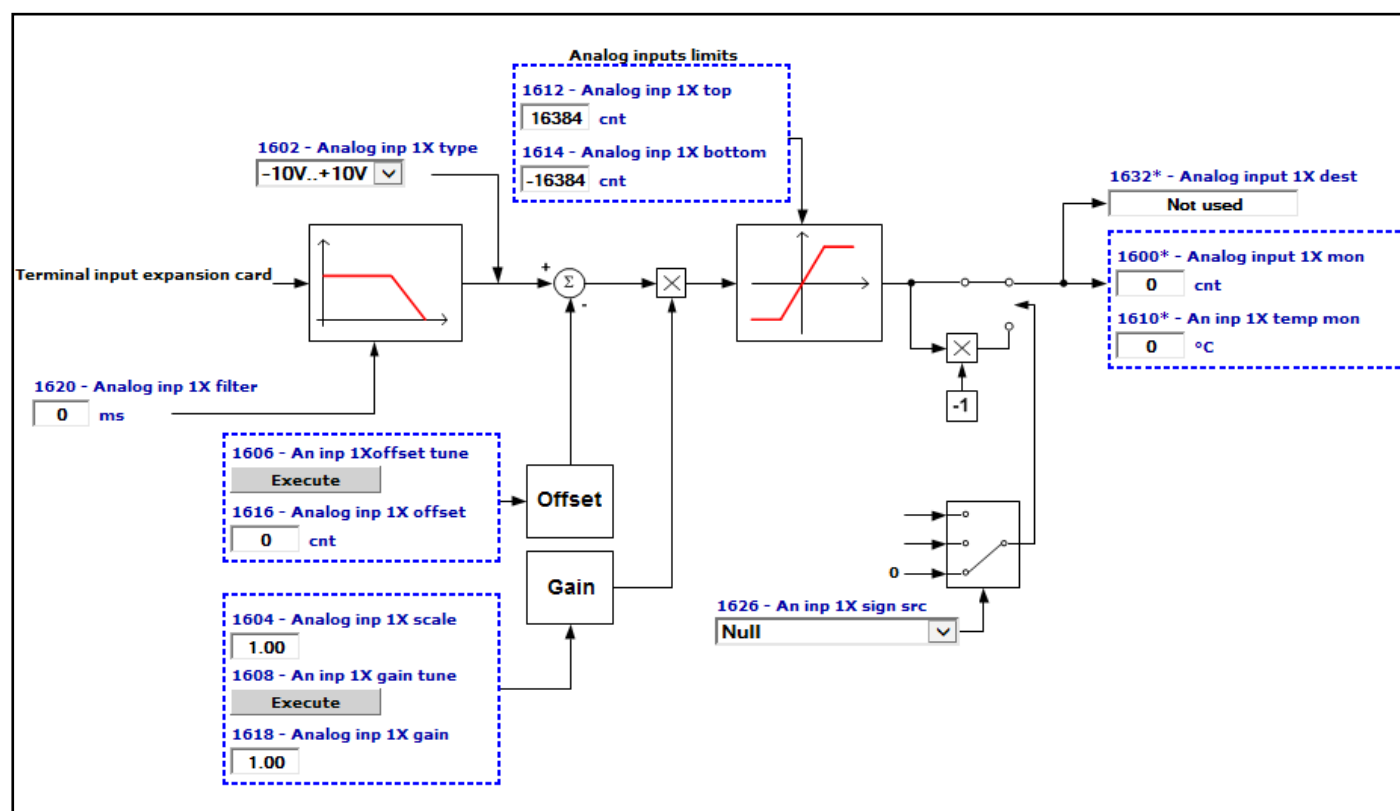
Selection of the origin (source) of the signal to be assigned to the relative digital input for selecting the alternative analog reference. The functions that can be associated with the digital outputs are listed in the “**L_DIG-SEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.16	1532	Analog inp 1 dest		ILINK		0	0	0	ER	FVS
14.32	1582	Analog inp 2 dest		ILINK		0	0	0	ER	FVS

The function for which the relative analog input has been programmed and on which it acts is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.33	1600	Analog input 1X mon	cnt	INT16	16/32	0	-16384	16384	R	FVS
14.45	1650	Analog input 2X mon	cnt	INT16	16/32	0	-16384	16384	R	FVS

The value of the voltage output of the function block of the relative analog input is displayed.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.34	1602	Analog inp 1X type		ENUM		-10V..+10V	0	6	RW	FVS
14.46	1652	Analog inp 2X type		ENUM		-10V..+10V	0	6	RW	FVS

Selection of the type of expansion card input (voltage or current input). Depending on the input signal, move the switches on the expansion card. Standard inputs are coded for voltage signals.

- 0 -10V...+10V
- 1 0..10V
- 2 4..20mA
- 3 0..20mA
- 4 PT1000
- 5 NI1000
- 6 PT100
- 7 0.1V..10.1V
- 8 KTY84

Select option **0** in order to connect a maximum voltage of $\pm 12.5V$ (typically $\pm 10V/5mA$) to the analog input concerned. If the signal is used as a reference, reverse the direction of rotation of the drive by inverting the voltage polarity.

Select option **1** to connect a max voltage of 12.5V (typically 10V/5mA).

Select option **2** to connect a current signal of 4...20 mA to the analog input concerned. The signal must be positive.

Select option **3** to connect a current signal of 0...20 mA to the analog input concerned. The signal must be positive.

Select option **4** to connect a signal from a PT1000 probe to the analog input concerned.

Select option **5** to connect a signal from an NI1000 probe to the analog input concerned.

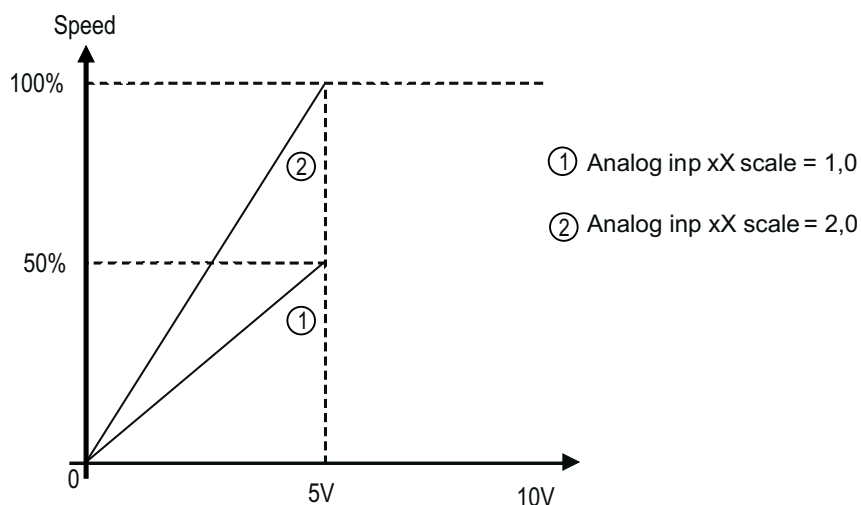
Select option **6** to connect a signal from a PT1000 probe to the analog input concerned.

Select option **7** to connect 0.1V...10.1V to the analog input in use. You can also detect signal loss (due to disconnection or short circuit) with alarm [62] **AnalogInpLoss**.

Select option **8** to connect a KTY84 temperature sensor to the analog input in use (you have to use an analog output as power supply signal). You can also detect signal loss (due to disconnection or short circuit) with alarm [62] **AnalogInpLoss**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.35	1604	Analog inp 1X scale		FLOAT		1.0	-20.0	20.0	RW	FVS
14.47	1654	Analog inp 2X scale		FLOAT		1.0	-20.0	20.0	RW	FVS

Setting of a multiplier factor to apply to the relative analog input of the expansion card.



Example:

The speed reference of a drive is assigned with a max external voltage of 5V. With this value the drive must reach the maximum speed allowed (set using **Full scale speed**).

As the **Analog inp X scale** parameter the scale factor of 2 is entered (10V : 5V)

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.36	1606	An inp 1Xoffset tune		BIT		0	0	1	RWZ	FVS
14.48	1656	An inp 2Xoffset tune		BIT		0	0	1	RWZ	FVS

Self-tuning command for the offset of the relative analog input of the expansion card. Automatic fine tuning of the input. To perform self-tuning, set the input signal to its minimum value and execute the command. The conditions containing an offset can be compensated. When this command is sent, **An inp xX offset tune** is automatically selected so that the available input signal corresponds to the zero value of the variable.

Automatic tuning can only be performed if the following condition is present:

- Input voltage less than 1V or input current less than 2 mA

Note ! The value that is obtained automatically can be changed manually, if necessary, using **An inp offset xX**.
If the voltage setting on the analog input is higher than 1V, the Value too low alarm is generated.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.37	1608	An inp 1X gain tune		BIT		0	0	1	RWZ	FVS
14.49	1658	An inp 2X gain tune		BIT		0	0	1	RWZ	FVS

Self-tuning command for the relative analog input gain. Automatic fine tuning of the input. When this command is sent, **Analog inp 1 gain x** is automatically selected so that the available input signal corresponds to the maximum value of the variable.

Two conditions are necessary in order to perform automatic tuning:

- Input voltage greater than 1V or input current greater than 2 mA
- Positive polarity. The value that is found is automatically accepted for the other direction of rotation.

Note ! If necessary, the value obtained automatically can be changed manually via **Analog inp Xx gain**.

To perform self-tuning, set the input signal to its maximum value and execute the command. A multiplier factor is calculated to apply to the input signal value (not considering the **Analog inp scale** parameter) to reach the full scale value.

If the voltage setting on the analog input is less than 1V, the Value too low alarm is generated.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.38	1620	Analog inp 1X filter	ms	UINT16		0	0	1000	ERW	FVS
14.50	1670	Analog inp 2X filter	ms	UINT16		0	0	1000	ERW	FVS

Parameters used to filter input signals to the I/O expansion card, especially if the card is used to measure motor temperature with KTY84.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.39	1612	Analog inp 1X top	cnt	INT16		16384	-32768	+ 32767	ERW	FVS
14.51	1662	Analog inp 2X top	cnt	INT16		16384	-32768	+ 32767	ERW	FVS

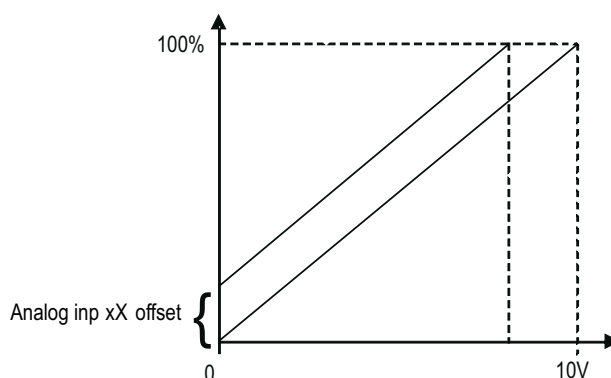
Setting of the upper speed reference limit as a function of the voltage (or current) of the relative analog reference of the expansion card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.40	1614	Analog inp 1X bottom	cnt	INT16		-16384	-32768	+ 32767	ERW	FVS
14.52	1664	Analog inp 2X bottom	cnt	INT16		-16384	-32768	+ 32767	ERW	FVS

Setting of the lower speed reference limit as a function of the voltage (or current) of the relative analog reference of the expansion card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.41	1616	Analog inp 1X offset	cnt	INT16		0	-32768	+ 32767	ERW	FVS
14.53	1666	Analog inp 2X offset	cnt	INT16		0	-32768	+ 32767	ERW	FVS

Setting of an offset value to algebraically add to the relative analog input of the expansion card.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.42	1618	Analog inp 1X gain		FLOAT		1.0	-20.0	20.0	ERW	FVS
14.54	1668	Analog inp 2X gain		FLOAT		1.0	-20.0	20.0	ERW	FVS

This parameter contains the value of the multiplier factor to apply to the analog reference of the expansion card calculated using the **Analog inp gain tune** function.

Example:

An external analog reference only reaches a maximum of 9.8V instead of 10V. 1.020 (10V : 9.8V) is entered as the **Analog inp x gain** parameter.

The same result can be achieved using the **Analog inp x gain tune** function. This parameter can be selected from the keypad menu. The maximum analog value available (in this case 9.8V) must be present on the terminal, with positive polarity. Press the Enter key on the keypad to start analog reference self-tuning.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.43	1626	An inp 1X sign src		LINK	16	6000	0	16384	ERW	FVS
14.55	1676	An inp 2X sign src		LINK	16	6000	0	16384	ERW	FVS

Selection of the origin (source) of the signal to be assigned to the relative digital input of the expansion card for selecting the direction of rotation of the motor. The functions that can be associated with the digital outputs are listed in the "**L_DIGSEL2**" selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.44	1632	Analog inp 1X dest		ILINK		0	0	0	ER	FVS
14.56	1682	Analog inp 2X dest		ILINK		0	0	0	ER	FVS

The function for which the relative analog input of the expansion card has been programmed and on which it acts is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.57	5410	Analog inp 0Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.58	5412	Analog inp 1Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.59	5414	Analog inp 2Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.60	5416	Analog inp 3Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.61	5418	Analog inp 4Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.62	5420	Analog inp 5Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.63	5422	Analog inp 6Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.64	5424	Analog inp 7Ext mon		INT16	16	0	-32768	32767	ER	FVS

These parameters show the value of the analog input of the I/O remotable module (EXP-FL-XCAN-ADV expansion board is needed).

Analog input modules can have a resolution of 12 to 16 bits and scaling may vary from manufacturer to manu-

facturer.

E.g.:

12-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3	Variant 4
-10V..+10V	-2048..+2047	-32768..+32767	-16384..+16383	
0V..+10V	0..+4095	0..+2047	0..+32767	0..+65535
4..20mA	0..+32767	+6553..+32767	+3276..+16383	

16-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3	
-10V..+10V	-32768..+32767			
0V..+10V	0..+65535	0..+32767		
4..20mA				

There is no single Unit suitable for all models of analog input module. Check the scaling provided by the model being used and use the system variables accordingly.

Analog input 0 and analog input 1 can also be managed by the drive parameters. To ensure correction operation, the scaling provided by the external module must be compatible with the scaling requested by the drive.

The drive needs I/O modules that supply datum scaled as follows

Analog inp X type	Range
-10V..+10V	-32768..+32767
0V..+10V	0..+65535
4..20mA	+13107..+65535

When the **An inp X gain tune** (PAR 1508, PAR1558) command is sent with analog input set to the maximum value, the gain needed to adjust the full scale value is calculated.

For modules with scaling other than that requested by the drive, the **An inp X gain tune** command attempts to adjust the scaling. For that reason the maximum value is increased for **An inp X gain tune** parameters.

The tables below show the output of the analog input block according to the signal connected and the configuration of the **Analog inp X type** parameter (PAR 1502, PAR1552).

Signal connected: -10V..+10V

An input type	-10V	0V	+10V
-10V..+10V	Bottom	Obtained from straight line	Top
0V..+10V	Less than 0V saturation at Bottom	Bottom	Top
4.0.20 mA	Less than 2V saturation at Bottom	Bottom	Top

Signal connected: 0V..+10V

An input type		0V	+10V
-10V..+10V		Obtained from straight line	Top
0V..+10V		Bottom	Top
4..20 mA		Less than 2V saturation at Bottom	Top

Signal connected: 4..20 mA

An input type		4mA	20mA
-10V..+10V			Top

0V..+10V		Less than 4 mA saturation at Bottom	Top
4..20 mA		Bottom	Top

The Analog inputs voltage or current inputs must be configured on the external module using a dedicated switch or tool. For analog input 0 and analog input 1 the An input type parameter must be set according to the type of external device.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.65	1586	Sensor inp X type		ENUM		None	0	3	ERW	FVS

0 None

1 Klixon

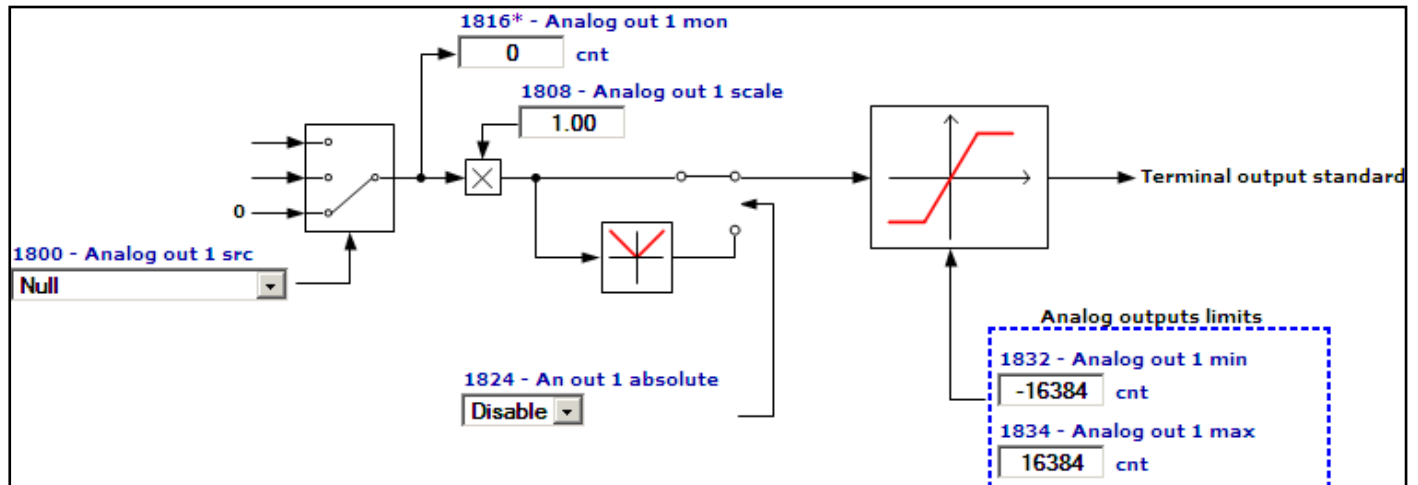
2 KTY84

3 PTC

Setting of sensor type connected to dedicated input of temperature expansion cards EXP-IO-SENS-100-ADV or EXP-IO-SENS-1000-ADV.

When these cards are used, alarm [62] **An inpLoss** signals the disconnection or short circuit of the KTY84 or PTC sensor.

15 – ANALOG OUTPUTS



On the AVD regulation card there are two programmable analog outputs.

Analog output 1 supplies a two-pole +/-10VDC voltage signal, while analog output 2 can be programmed to obtain a 0-20mA or 4-20mA output signal in current or a signal in two-pole +/-10VDC voltage, depending on the parameter assigned.

Table: value of the signal of the analog outputs according to the measurement used

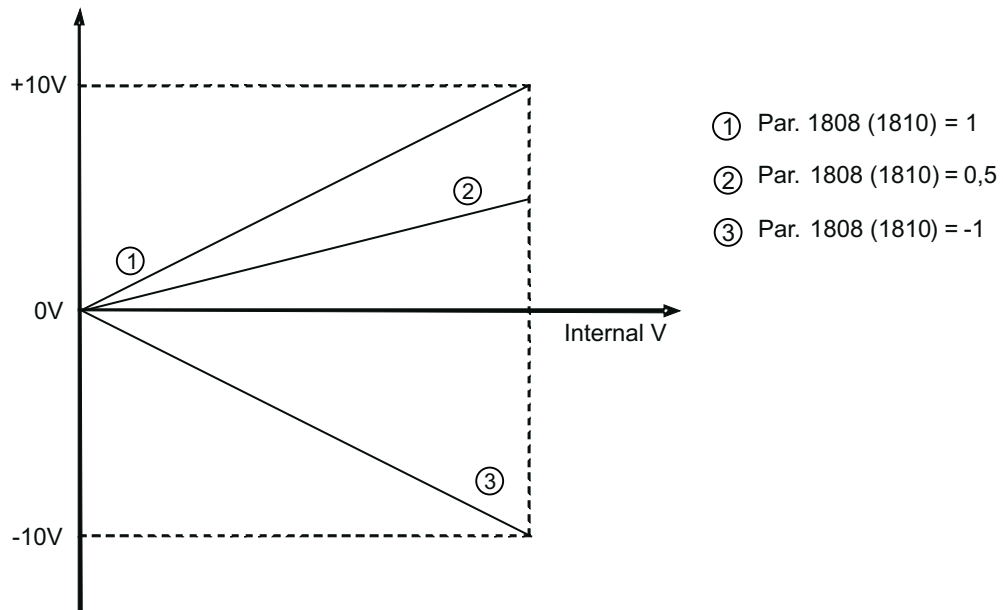
PAR	Description	Full scale output
626	Ramp ref out mon	10V = Full scale speed (Par 680)
628	Ramp setpoint	
760	Ramp out mon	
664	Speed setpoint	
260	Motor speed	
262	Motor speed nofilter	
2150	Encoder 1 speed	
852	Multi ref out mon	
870	Mpot setpoint	
894	Mpot output mon	
920	Jog output mon	10V = 200% CT drive rated current (available on Quick startup manual, this value is defined @400Vac, default switching frequency and 40°C)
250	Output current	
280	Torque current ref	
282	Magnet current ref	
284	Torque current	
286	Magnet current	
2360	Torque lim Pos Inuse	
2362	Torque lim Neg Inuse	10V = 200% Nominal motor torque
2386	Torque ref	
2388	Torque ref nofilter	
3070	Droop out mon	
3104	Inertia comp mon	10V = 200% Mains voltage (Par 560)
252	Output voltage	10V = 1000Hz
254	Output frequency	10V = 7000V
270	DC link voltage	10V = 100%
3006	Speed ratio out mon	10V = 10V Analog input
1500	Analog input 1 mon	
1550	Analog input 2 mon	
1600	Analog input 1X mon	
1650	Analog input 2X mon	5V = 100% Accumulator
368	Drive overload accum	
3212	Motor overload accum	
3260	Bres overload accum	
2232	Spd reg P gain Inuse	10V = 400%
2234	Spd reg I gain Inuse	10V = 50%
3446	Powerloss nexratio	10V = 16384 * 2 ¹⁶
4024 ... 4174	Fieldbus M->SX mon	
3700 ... 3730	Pad X	

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.1	1800	Analog out 1 src		LINK	16/32	6000	0	16384	RW	FVS
15.2	1802	Analog out 2 src		LINK	16/32	6000	0	16384	RW	FVS

Selection of the origin (source) of the signals that can be placed as variables on the analog outputs. The functions that can be assigned to the analog outputs are listed in the “**L_ANOUT**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.3	1808	Analog out 1 scale		FLOAT		1.0	-10.0	10.0	RW	FVS
15.4	1810	Analog out 2 scale		FLOAT		1.0	-10.0	10.0	RW	FVS

Parameter for setting a multiplier factor of the signal of the relative analog output. It can be used to amplify or reduce the input value of the relative analog output block.



$$V_{out} = 10 \times \left(\frac{\text{Stp Var} \times \text{par. 1808 (1810)}}{\text{FS Var}} \right)$$

where:

Vout output voltage on the card terminals.
Stp Var actual value of the variable (variable unit)
SF Var full scale of the variable (variable unit)

Example of calculation of scale factor **Analog out x scale**

To display the drive speed, use an analog instrument with field of measurement from 0...2V. This means that, to display the speed of the drive, a voltage of 2V on the analog output of the drive must correspond to the maximum speed. With a scale factor equal to 1 a voltage of 10V would correspond to the maximum speed.

With a scale factor equal to 0.2 = 2V/10V a voltage of 2V would correspond to the maximum speed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.5	1816	Analog out 1 mon	cnt	INT16		0	0	0	ER	FVS

The value of the actual voltage present on analog output 1 is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.6	1818	Analog out 2 mon	cnt	INT16		0	0	0	ER	FVS

The value of the actual voltage or current present on analog output 2 is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.7	1824	An out 1 absolute		ENUM		Disable	0	1	ERW	FVS
15.8	1826	An out 2 absolute		ENUM		Disable	0	1	ERW	FVS

Enables the relative analog output as an absolute value. If this parameter is set to 1 the voltage on the analog output assumes the value of 0 - 10V regardless of the sign of the command signal.

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.9	1832	Analog out 1 min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.10	1834	Analog out 1 max	cnt	INT16		16384	-32768	+32767	ERW	FVS

Setting of the minimum and maximum values for the analog output for the voltage present on analog output 1

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.11	1840	Analog out 2 min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.12	1842	Analog out 2 max	cnt	INT16		16384	-32768	+32767	ERW	FVS

Setting of the minimum and maximum values for the analog output for the voltage present on analog output 2

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.13	1848	Analog out 2 type		ENUM		-10V..+10V	0	2	ERW	FVS

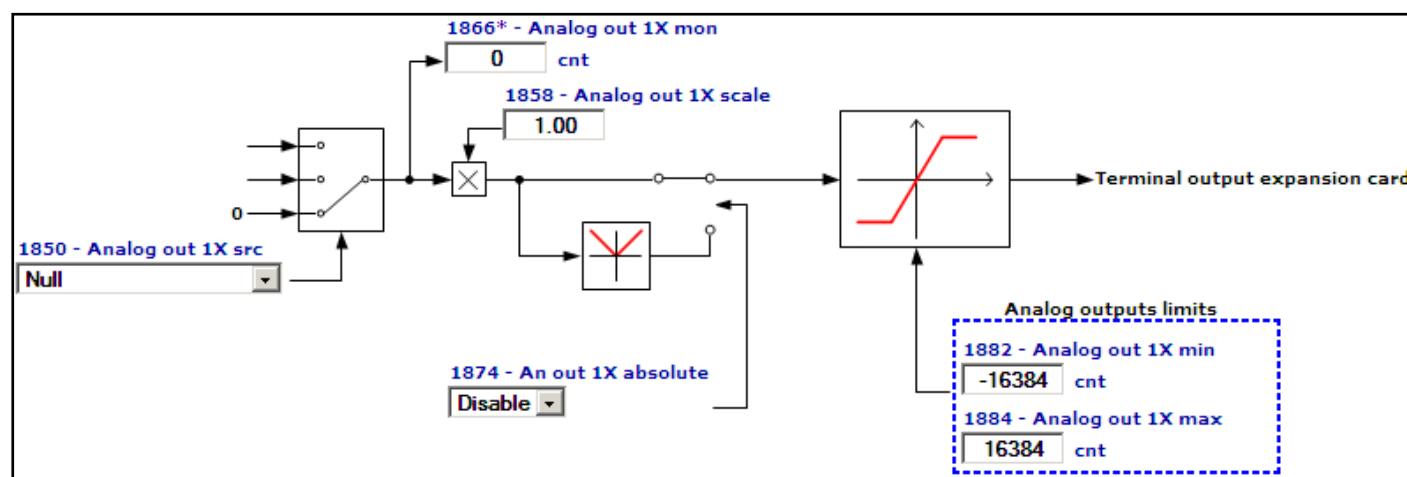
Selection of the type of output (in voltage or current). Depending on the output signal, move the S3 switch on the regulation card. The standard output is coded for the signal in voltage.

- 0 0...20mA
- 1 4...20mA
- 2 -10V..+10V

If set to **0** the analog output sends 0...20mA
If set to **1** the analog output sends 4...20mA
If set to **2** the analog output sends -10...+10V

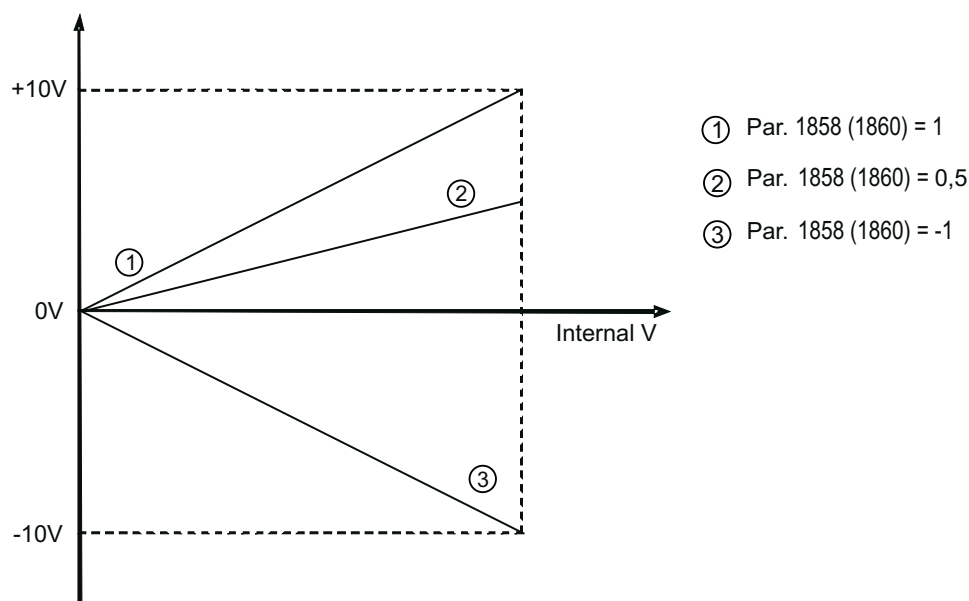
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.14	1850	Analog out 1X src		LINK	16/32	6000	0	16384	RW	FVS
15.15	1852	Analog out 2X src		LINK	16/32	6000	0	16384	RW	FVS

Selection of the origin (source) of the signals that can be placed as variables on the analog outputs of the expansion card. The functions that can be assigned to the analog outputs are listed in the “**L_ANOUT**” selection list.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.16	1858	Analog out 1X scale		FLOAT		1.0	-20.0	20.0	RW	FVS
15.17	1860	Analog out 2X scale		FLOAT		1.0	-20.0	20.0	RW	FVS

Parameter for setting a multiplier factor of the signal of the relative analog output of the expansion card. It can be used to amplify or reduce the input value of the relative analog output block.



$$V_{out} = 10 \times \left(\frac{\text{Stp Var} \times \text{par. 1858 (1860)}}{\text{FS Var}} \right)$$

where:

Vout output voltage on the card terminals.
Stp Var actual value of the variable (variable unit)
SF Var full scale of the variable (variable unit)

Example of calculation of the **Analog out Xx** scale factor

To display the drive speed, use an analog instrument with field of measurement from 0 ... 2V. This means that, to display the speed of the drive, a voltage of 2V on the analog output of the drive must correspond to the maximum speed. With a scale factor of 1 this would be 10V (Scale factor = 2V / 10 V = 0.200).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.18	1866	Analog out 1X mon	cnt	INT16		0	0	0	ER	FVS

The actual value of the voltage present on analog output 1 of the expansion card is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.19	1868	Analog out 2X mon	cnt	INT16		0	0	0	ER	FVS

The actual value of the voltage or current present on analog output 2 of the expansion card is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.20	1874	An out 1X absolute		ENUM		Disable	0	1	ERW	FVS
15.21	1876	An out 2X absolute		ENUM		Disable	0	1	ERW	FVS

Enables the relative analog output as an absolute value. If this parameter is set to 1 the voltage on the analog

output assumes the value of 0 - 10V regardless of the sign of the command signal.

- 0** Disable
- 1** Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.22	1882	Analog out 1X min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.23	1884	Analog out 1X max	cnt	INT16		16384	-32768	+32767	ERW	FVS

Setting of the minimum and maximum values for the analog output for the voltage present on analog output 1 of the expansion card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.24	1886	Analog out 1X type		ENUM		-	0	3	ERW	FVS

Selection of the programmed signal on analog output 1 of the expansion card. Depending on the output signal, move the dedicated switch on the expansion card. The standard output is coded for the signal in voltage.

- 0** 0...20mA
- 1** 4...20mA
- 2** -10V..+10V
- 3** 0..10V

If set to **0** the analog output sends 0...20mA
 If set to **1** the analog output sends 4...20mA
 If set to **2** the analog output sends -10..+10V
 If set to **3** the analog output sends 0..+10V.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.25	1890	Analog out 2X min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.26	1892	Analog out 2X max	cnt	INT16		16384	-32768	+32767	ERW	FVS

Setting of the minimum and maximum values for the analog output in current or voltage present on analog output 2 of the expansion card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.27	1898	Analog out 2X type		ENUM		-10V..+10V	0	3	ERW	FVS

Selection of the programmed signal on analog output 2 of the expansion card. Depending on the output signal, move the dedicated switch on the expansion card. The standard output is coded for the signal in voltage.

- 0** 0...20mA
- 1** 4...20mA
- 2** -10V..+10V
- 3** 0..10V

If set to **0** the analog output sends 0...20mA
 If set to **1** the analog output sends 4...20mA
 If set to **2** the analog output sends -10..+10V

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
15.28	5460	Dig Analog out 0 ext		INT16	16	0	-32768	32767	ERW	FVS
15.29	5462	Dig Analog out 1 ext		INT16	16	0	-32768	32767	ERW	FVS
15.30	5464	Dig Analog out 2 ext		INT16	16	0	-32768	32767	ERW	FVS
15.31	5466	Dig Analog out 3 ext		INT16	16	0	-32768	32767	ERW	FVS
15.32	5468	Dig Analog out 4 ext		INT16	16	0	-32768	32767	ERW	FVS
15.33	5470	Dig Analog out 5 ext		INT16	16	0	-32768	32767	ERW	FVS
15.34	5472	Dig Analog out 6 ext		INT16	16	0	-32768	32767	ERW	FVS

These parameters are used with I/O remotable module (EXP-FL-XCAN-ADV expansion board is needed).
Analog output modules can have a resolution of 12 to 16 bits and scaling may vary from manufacturer to manufacturer.

E.g.:
12-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3	Variant 4
-10V..+10V	-2048..+2047	-32768..+32767	-16384..+16383	
0V..+10V	0..+4095	0..+2047	0..+16383	0..+32767
4..20mA	0..+32767	+6553..+32767	+3276..+16383	

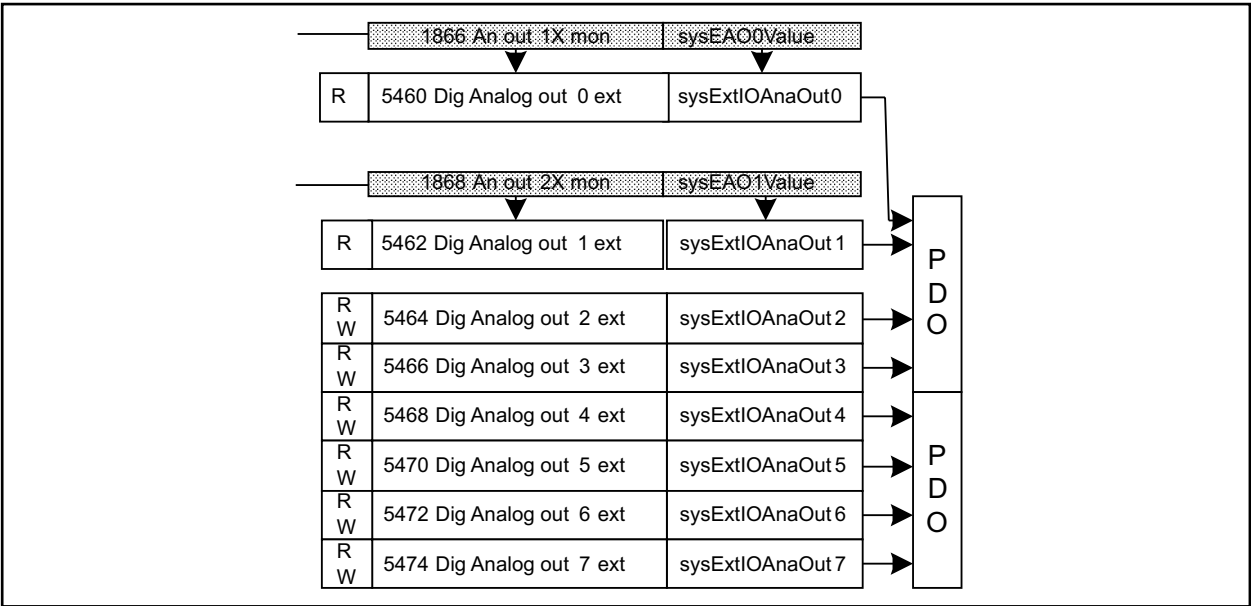
16-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3
-10V..+10V	-32768..+32767		
0V..+10V	0..+65535	0..+32767	
4..20mA			

There is no single unit that is suitable for all models of analog output module.
Check the scaling provided by the model being used and use the system variables accordingly.
Analog output 0 and analog output 1 can also be managed by the drive parameters.
To ensure correction operation, the scaling provided by the external module must be compatible with the scaling provided by the drive.
The drive supplies a datum for the I/O modules scaled as follows

Analog input type	Range
-10V..+10V	-32768..+32767
0V..+10V	0..+65535
4..20mA	+13107..+65535

Analog outputs 0..1 are managed via drive parameters and the value produced by the drive overwrites that written by the MDPLC or serial communication or fieldbus.



16 – MOTOR DATA

From this menu you can enter the motor plate data and “basic” values for the voltage/frequency characteristics. It is important to enter the correct data in order to optimize drive operation and that of the application as a whole. These data are required in order to obtain:

- Computation of the normalization factors necessary for regulation
- Computation of the estimated values for the motor parameters necessary for regulation

Rated voltage, Rated speed, Rated frequency, Rated current, Cos phi, Basic voltage and Basic frequency must be entered (the Cos phi default value can be used if this value is not present on the plate). After entering these parameters, send a Take motor par command to calculate (a) and (b) above. The motor cannot be enabled until the Take motor par command has been set. If some results are inconsistent, or if the motor is much smaller than the inverter, an error message is displayed indicating a numerical capacity overflow and the previous set of parameters is restored in the “Mot plate data” sub-menu.

Motor & Co.				Motor & Co.			
Type: ABCDE	IEC 34-1 / VDE 0530			Type: ABCDE	IEC 34-1 / VDE 0530		
Motor: 3 phase	50 Hz	Nr	12345-91	Motor: 3 phase	60 Hz	Nr	12345-91
Rated voltage	400 V	I nom	6.7 A	Rated voltage	575 V	I nom	2 A
Rated power	3 kW	Power factor	0.8	Rated power	2 Hp	Power factor	0.83
Rated speed (n _n)	1420 rpm			Rated speed (n _n)	1750 rpm	Efficiency	86.5
IP54	Iso	KI	F	IP54	Iso	KI	F
	S1				S1		
Made in				Made in			

Motor data plates

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.1	2000	Rated voltage	V	FLOAT	SIZE		50.0	690.0	RWZS	FVS

Set the motor rated voltage as indicated on the data plate. This is the voltage the drive must supply at the motor rated frequency.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.2	2002	Rated current	A	FLOAT	SIZE		0.3	2200.0	RWZS	FVS

The motor rated current at its rated power (kW / Hp) and voltage (indicated on the motor data plate).

If using a single drive to control several motors connected in parallel (only possible in the V/f mode), enter a value that corresponds to the sum of the rated currents of all the motors; in this case do not perform any self-tuning operations.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.3	2004	Rated speed	rpm	FLOAT	SIZE		10.0	32000.0	RWZS	FVS

Rated speed of the motor with full load in rpm (rpm = m-1). In some motors the synchronous speed (e.g. 1500 rpm for a 4-pole motor) and slippage, i.e. the loss of revolutions between the motor idling condition and the rated load condition (e.g. 80 rpm), is indicated. Enter the following: synchronous speed - slippage.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.4	2006	Rated frequency	Hz	FLOAT	SIZE		10.0	1000.0	RWZS	FVS

Rated frequency of the motor expressed in Hz, at which the flux weakening threshold starts.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.5	2008	Pole pairs		UINT16		SIZE	1	(*)	RWZS	FVS

Motor pole pairs. (*) Open loop (Sensorless) and Closed Loop = 20pp.

The number of motor pole pairs is calculated using the motor plate data and applying the following formula:

$$P = \frac{60 [s] \times f [Hz]}{nN [rpm]}$$

Where:

p = motor pole pairs

f = motor rated frequency (P. 2006)

nN = motor rated speed (P. 2004)

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.6	2010	Rated power	kW	FLOAT		SIZE	0.05	2000.00	RWZS	FVS

Rated power of the motor at the rated voltage and frequency. This value represents the mechanical power produced on the motor shaft.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.7	2012	Rated power factor		FLOAT		SIZE	0.6	0.95	RWZS	FVS

Motor power factor, as indicated on the data plate (Cos φ). This parameter is not always present on the motor data plate: in that case use the default value present in the drive.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.8	2020	Take parameters		BIT		0	0	1	RWZ	FVS

Saves the set motor data in the drive. This command must be supplied last after entering the appropriate values of all the parameters listed above. This means calculating the normalization factors (a) and estimated values for the motor parameters (b). The drive cannot be started until the **Take parameters** command has been set.

Note ! This is not saved permanently. Use the **"Save Parameters"** command in the **DRIVE CONFIG** menu to save in the permanent memory.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.9	2022	Autotune rotation		BIT		0	0	1	RWZ	FVS

Performs self-tuning in rotation: the motor must be uncoupled from the load or the transmission must not represent more than 5% of the load. This procedure allows the greatest degree of accuracy in measuring the motor parameters. To execute the command you must first open the hardware enabling contact between terminals 7 and S3. Next set the **Regulation mode** parameter to **Autotune**. If you are not already in Local mode, press the Local key (the **LOC** LED will light up) and close the hardware enabling contact again (terminals 7 and S3). Self-tuning can now be performed. At the end of the self-tuning procedure, open the contact between terminals 7 and S3 again and reset the parameters that were modified.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.10	2024	Autotune still		BIT		0	0	1	RWZ	FVS

Performs self-tuning with the motor coupled to the transmission. The self-tuning procedure may cause limited rotation of the motor shaft. To perform self-tuning, follow the procedure described for the previous parameter.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.11	2026	Autotune mode		ENUM		Reduced	0	1	ERWZ	FVS

Selection of the motor parameter self-tuning mode.

0 Reduced

1 Extended

If set to **0** all the motor parameters are measured except those relating to the non-linear saturation curve. Use this mode to obtain a faster self-tuning procedure.

If set to **1** all the motor parameters are measured. Use this mode to obtain maximum efficiency: this procedure may take a few minutes.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.12	2028	Take par status		ENUM		Required	0	0	R	FVS
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Indication of the status of parameter saving.

0 Required

1 Done

The parameter displays the Required message when the motor parameters that have been entered need to be saved. When they have been saved the parameter indicates Done.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.13	2030	Autotune status		ENUM		Required	0	0	R	FVS
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Indication of the status of execution of motor parameter self-tuning.

0 Required

1 Done

The parameter displays the Required message when motor parameter self-tuning is required. When self-tuning is complete the parameter indicates Done.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.14	2050	Measured Rs	ohm	FLOAT		CALCF	0.0005	200.0	ERWS	FVS
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Measured stator resistance value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.15	2052	Measured DTL	V	FLOAT		0.0	0.0	100.0	ERWS	FVS
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Measured value of dead time compensation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.16	2054	Measured DTS	V/A	FLOAT		0.0	0.0	100.0	ERWS	FVS
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Measured compensation gradient value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.17	2056	Measured Lsig	mH	FLOAT		CALCF	0.01	700.0	ERWS	FVS
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Measured leakage inductance value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.18	2058	Measured ImN	A	FLOAT		CALCF	0.1	1000.0	ERWS	FVS
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Measured rated magnetizing current value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.19	2060	Measured ImX	A	FLOAT		CALCF	0.0	0.0	ERWS	FVS
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Measured magnetizing current saturation value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
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16.20	2062	Measured FlxN	Wb	FLOAT		CALCF	0.05	10.0	ERWS	FVS
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Measured rated flux value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.21	2064	Measured FlxX	Wb	FLOAT		CALCF	0.0	0.0	ERWS	FVS

Measured flux saturation value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.22	2066	Measured P1		FLOAT		0.05	0.0	1.0	ERWS	FVS

Measured value of the first parameter to define the motor magnetization curve.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.23	2068	Measured P2		FLOAT		9.0	3.0	18.0	ERWS	FVS

Measured value of the second parameter to define the motor magnetization curve.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.24	2070	Measured P3		FLOAT		0.87	0.0	1.0	ERWS	FVS

Measured value of the third parameter to define the motor magnetization curve.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.25	2072	Measured Rr	ohm	FLOAT		CALCF	0.0005	200.0	ERWS	FVS

Measured rotor resistance value.

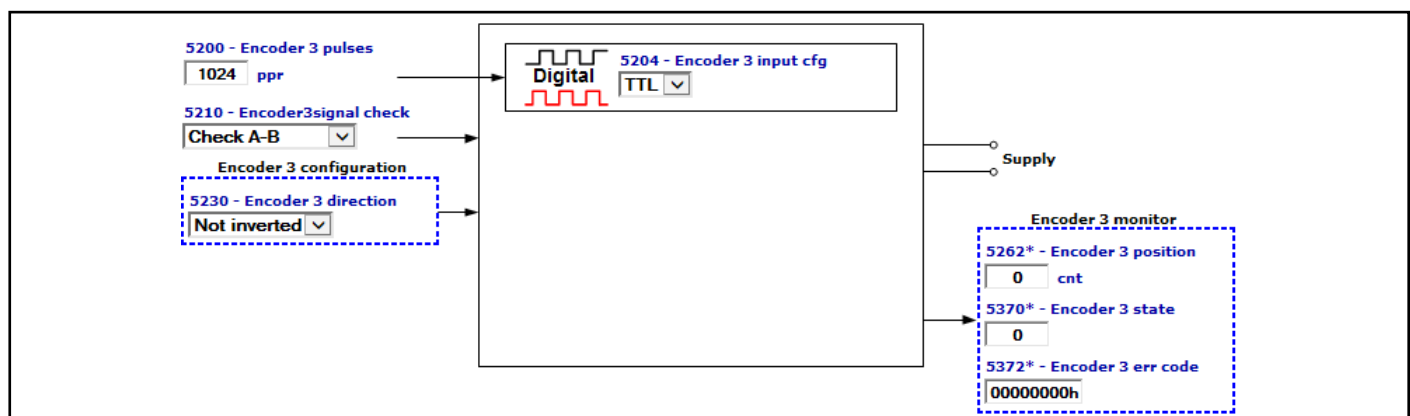
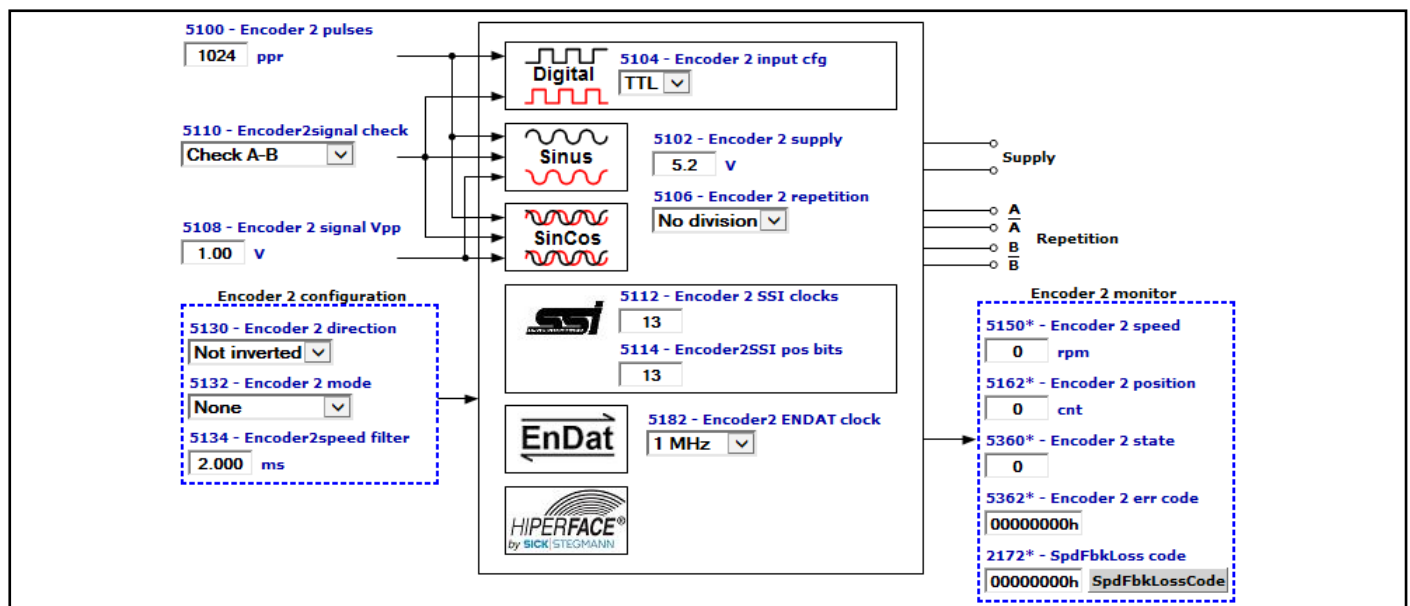
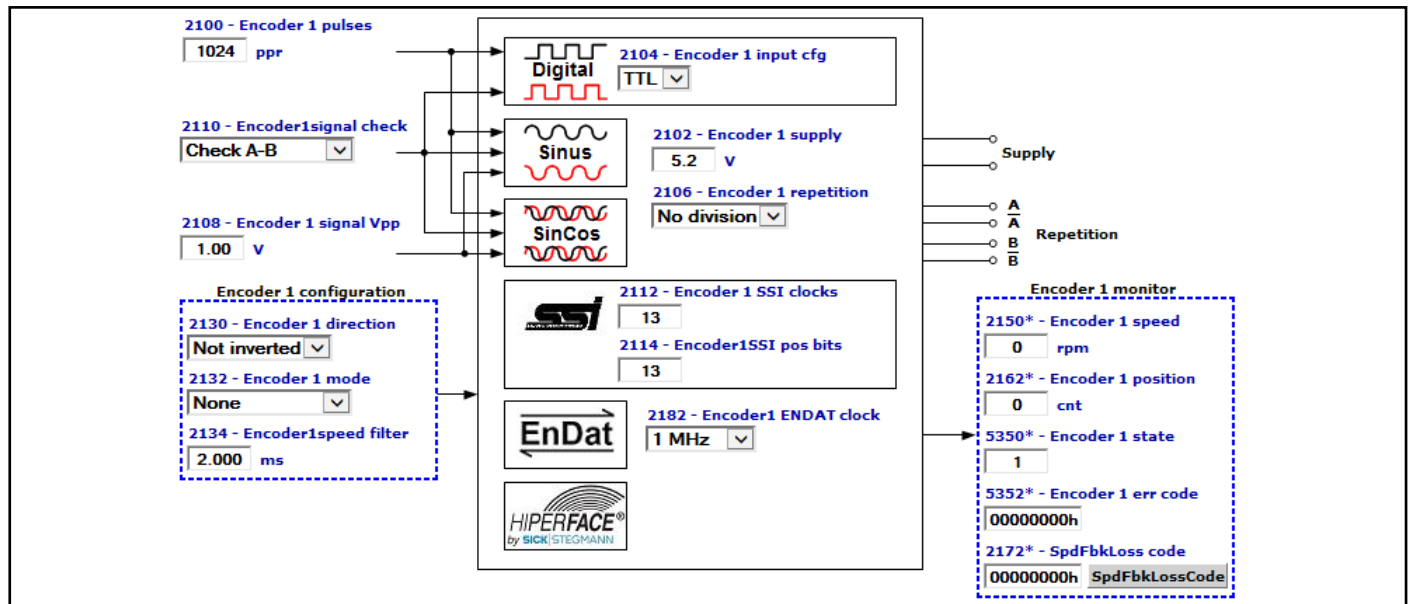
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
16.26	2078	Take tune parameters		BIT		0	0	1	ERWZ	FVS

Saves the motor data calculated by the self-tuning procedure in the drive.

Note ! Data are not saved permanently. Use the “**Save Parameters**” command in the **DRIVE CONFIG** menu to save in the permanent memory.

17 – ENCODER

The closed-loop control mode requires a speed reading by a digital encoder on the motor shaft. The optional EXP-ENC card is necessary in order to acquire the encoder signals. Optional cards have been developed to acquire different types of encoder signals. These enable the drive to use both incremental and absolute signals as its feedback. The natural variation in speed generated by machine load induction, known as slippage, can be compensated by the speed feedback supplied by the encoder in V/f mode. In the field oriented vector mode, closed-loop encoder feedback is essential for correct drive operation.



17.1 - ENCODER/ENCODER CONFIG

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.1.1	5310	Encoder sel src		LINK 16		6000	0	16384	ERW	FVS

Selection of the origin (source) of the input to be used to select the speed feedback encoder. The digital inputs that can be used can be selected from the “**L_DIGSEL2**” selection list.

When the value of the signal is 0, it is associated with encoder 1.

When the value of the signal is 1, it is associated with encoder 2.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.1.2	5314	Encoder sel mon		UINT16		0	0	1	ER	FVS

The encoder selected as the feedback device is displayed.

0 Encoder 1

1 Encoder 2

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.1.3	2172	SpdFbkLoss code		UINT32		0	0	0	ER	FVS

The **Speed fbk loss** alarm generated by an encoder fault is displayed. As each type of encoder generates the alarm differently (incremental signal error, absolute signal error, serial error), this parameter displays information about the alarm that has occurred. If there are several, simultaneous causes, these are shown in this parameter.

Bit	Value	Name
0	0x01	CHA
1	0x02	CHB
2	0x04	CHZ
3	0x08	MOD_INCR
4	0x10	MOD_ABS
5	0x20	CRC_CKS_P
6	0x40	ACK_TMO
7	0x80	DT1_ERR
8	0x100	Error Setup
10..15		Free
16..31		Depending on the type of feedback.

For further details please refer to the description of the **Speed fbk loss** alarm and the “9.2.1 Speed fbk loss alarm according to the type of feedback” chapter of ADV200 QS manual.

Note ! To interpret the causes of the alarm correctly, you will need to convert the hexadecimal code written in parameter 17.29 **SpdFbkLoss code**, PAR 2172, into the corresponding binary code and then use the table of the encoder being used to check the various active bits and relative description.

Example with Endat encoder:

PAR 2172 = A0H (hexadecimal value)

A0 is not present in the value column of the “**Speed fbk loss** [22] with absolute EnDat encoder” table.

A0 must be seen as a bitword meaning A0 -> 10100000 -> bit 5 and bit 7. This indicates the simultaneous intervention of the following causes:

Bit 5 = 20H Cause: disturbed SSI signals cause a **CKS** error or **Parity**

Bit 7 = 80H Cause: Encoder has detected malfunction and signals this to the drive via Error bit. Bits 16..31 contain the type of malfunction detected by the encoder.

17.2 - ENCODER/ENCODER 1

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.1	2100	Encoder 1 pulses	ppr	UINT16		CALCI	CALCI	CALCI	RWZ	FVS

Setting of the number of feedback encoder impulses.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.2	2102	Encoder 1 supply	V	FLOAT		5.2	5.2	CALCF	ERWZ	FVS

Setting of the encoder supply voltage supplied by the relative optional card. Min and max values are modified according to the type of encoder card applied.

Encoder option type		Def	Min	Max
Enc1	EXP-DE-I1R1F2-ADV	5.2V	5.2V	20.0V
Enc2	EXP-SE-I1R1F2-ADV	5.2V	5.2V	6.0V
Enc3	EXP-SESC-I1R1F2-ADV	5.2V	5.2V	6.0V
Enc4	EXP-EN/SSI-I1R1F2-ADV	5.2V	5.2V	10.0V
Enc5	EXP-HIP-I1R1F2-ADV	8.0V	7.0V	12.0V
Enc6	EXP-RES-I1R1-ADV	-	-	-
Enc7	EXP-DE-I2R1F2-ADV	5.2V	5.2V	20.0V
Enc8	EXP-ASC-I1-ADV	5.2V	5.2V	6.0V

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.3	2104	Encoder 1 input cfg		ENUM		TTL	0	1	ERWZ	FVS

Setting of the input configuration of the incremental digital encoder, TTL or HTL.

0 HTL

1 TTL

The value of this parameter is automatically set in HTL when the value entered in the **Encoder 1 supply** parameter is more than 6.0V.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.4	2106	Encoder 1 repetition		ENUM		No division	0	3	ERWZ	FVS

Setting of the divider to apply to the encoder repetition output frequency.

0 No division

1 Divide 2

2 Divide 4

3 Divide 8

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.5	2108	Encoder 1 signal Vpp	V	FLOAT		1.0	0.8	1.2	ERWZ	FVS

Setting of the encoder 1 signal peak-to-peak voltage value. Incremental sinusoidal encoders and absolute SinCos encoders normally produce signals with a peak-to-peak voltage of 1 Vpp. Due to voltage drops along the cable, the signal may have a lower peak-to-peak voltage when it reaches the feedback card, triggering the **Speed fbk loss** alarm.

This parameter is used to configure the value of the peak-to-peak voltage of the incremental sinusoidal encoders and absolute SinCos encoders on the input terminals of the feedback card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.6	2110	Encoder1signal check		ENUM		Check A-B	0	1	ERWZ	FVS

Configuration of which channels of the incremental digital encoder 1 must be controlled for processing the **Speed fbk loss** [22].

0 Check disabled

1 Check A-B

- 2 Check A-B-Z
- 4 Check A-B-SE

If set to 1, the application checks for the presence of the signals of channels A-B

If set to 2, the application checks for the presence of the signals of channels A-B-Z

If set to 4, the application controls loss of feedback for SE (single ended) encoders.

If the application detects the absence of feedback the **Speed fbk loss [22]** is generated.

As loss of feedback cannot be detected at speeds of around zero, the control is only performed if the speed reference is higher than the value set in parameter **4564 SpdFbkLoss threshold**. It is also important to consider the fact that when working with a speed reference slightly above the limit set in parameter **4564 SpdFbkLoss threshold**, the speed error could exceed the set threshold, given the load or current limit, and generate false alarms.

In that case increase the value of parameter **4550 SpdRefLoss threshold** or of parameter **4554 SpdRefLoss holdoff**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.7	2112	Encoder 1 SSI clocks		UINT16		13	11	25	ERWZ	F_S

Setting of the length of the serial package of the SSI encoder 1 used. The value is shown on the encoder data-sheet and defined in clock cycles (usually from 13 to 25 bits).

Example of single-turn encoder

13 position bits: set par 2114 = 13.

13 clock bits: set par 2112 = 13.

Example of multi-turn encoder

13 position bits: set par 2114 = 13.

25 clock bits: set par 2112 = 25.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.8	2114	Encoder1SSI pos bits		UINT16		13	11	25	ERWZ	F_S

Setting of the number of bits used by the SSI encoder 1 to define the position.

See examples of PAR 2112.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.9	2182	Encoder1 ENDAT clock		ENUM		1 MHz	0	1	ERWZ	FVS

Selection of clock value for Encoder 1 ENDAT type.

0 1 MHz

1 500 kHz

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.10	2130	Encoder 1 direction		ENUM		Not inverted	0	1	RWZ	FVS

Selection of the encoder direction

0 Not inverted

1 Inverted

By setting 0 the encoder feedback signals are not inverted.

By setting 1 the encoder feedback signals are inverted.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.11	2132	Encoder 1 mode		ENUM		None	CALCI	CALCI	ERWZ	FVS

Setting of the method for measuring the speed of the encoder connected to the optional card. The drive automatically recognises the encoder card that is inserted and only shows the methods that are compatible.

0 None

1 Digital FP

- 2 Digital F
- 3 Sinus
- 4 Sinus SINCOS
- 5 Sinus ENDAT
- 6 Sinus SSI
- 7 Sinus HIPER
- 8 Resolver
- 9 Abs SINCOS
- 10 ENDAT
- 11 SSI

The speed measurement procedure depends on the type of encoder card; minimum and maximum default values are set according to the type of feedback card that is applied.

Encoder option type	Def	Min	Max
Enc 1	Digital F	Digital FP	Digital F
Enc 2	Sinus	Sinus	Sinus
Enc 3	Sinus SINCOS	Sinus SINCOS	Sinus SINCOS
Enc 4	Sinus SSI	Sinus ENDAT	SSI
Enc 5	Sinus HIPER	Sinus HIPER	Sinus HIPER
Enc 6	Resolver	Resolver	Resolver
Enc 7	Digital F	Digital FP	Digital F
Enc 8	SINCOS / No inc dig	SINCOS / No inc dig	SINCOS / No inc dig

In the presence of the **Enc 1** encoder option:

- setting **1** (Digital FP) selects the method for measuring frequency and period. This selection is preferable for applications that rotate at very low speeds.
- setting **2** (Digital F) selects the method for measuring frequency. This type of measurement lets you achieve high precision and dynamics at medium and high speed.

In the presence of the **Enc 4** encoder option:

- selection **10** (ENDAT), as opposed to selection **5** (Sinusoidal ENDAT), indicates that the encoder has no incremental channels. Switching between the two selections is automatic by means of a recognition procedure.
- selection **11** (SSI), as opposed to selection **6** (Sinusoidal SSI), indicates that the encoder has no incremental channels. Switching between the two selections has to be performed manually during commissioning.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.12	2134	Encoder1speed filter	ms	FLOAT		2.000	0.125	20.000	ERW	FVS

Setting of the time constant of the filter applied to the feedback encoder pulse reading. The parameter affects both the accuracy of the speed measurement and the dynamics obtainable in closed loop control. Long updating times allow greater stability (more filtering) of the speed measurement, as a higher number of encoder pulses are counted at a given speed of rotation. On the other hand, the use of a speed measurement filter introduces delays that do not permit high control loop dynamics. Low settings extend the regulation bandwidth but may accentuate any disturbance.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.13	2150	Encoder 1 speed	rpm	INT16	16/32	0	0	0	ER	FVS

The motor speed measured by the encoder is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.14	2162	Encoder 1 position	cnt	UINT16	16	0	0	0	ER	FVS

The encoder position is displayed. The scale is Number of encoder impulses *4.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.15	5350	Encoder 1 state		UINT16		0	0	0	ER	FVS

Indicates the state of Encoder 1 (1= error, 0 = no error) regardless of whether this Encoder is used/not used as feedback for motor control.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.2.16	5352	Encoder 1 err code		UINT32		0	0	0	ER	FVS

This parameter contains a hexadecimal code that supplies information on the type of error that occurred.

Error values are the same (and have the same significance) as the ones indicated in parameter IPA 2172 **Spd-FbkLoss** code.

17.3 - ENCODER/ENCODER 2

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.1	5100	Encoder 2 pulses	ppr	UINT16		CALCI	CALCI	CALCI	ERWZ	FVS

Setting of the number of impulses/rev of the incremental encoder mounted in slot 1 or 3.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.2	5102	Encoder 2 supply	V	FLOAT		5.2	5.2	CALCF	ERWZ	FVS

Setting of the encoder supply voltage supplied by the relative optional card. Min and max values refer to the incremental digital encoder cards with one or two encoders.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.3	5104	Encoder 2 input cfg		ENUM		TTL	0	1	ERWZ	FVS

Setting of the input configuration of the incremental digital encoder, TTL or HTL.

- 0 HTL
- 1 TTL

The value of this parameter is automatically set in HTL when the value entered in the **Encoder 2 supply** parameter is more than 6.0V.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.4	5106	Encoder 2 repetition		ENUM		No division	0	3	ERWZ	FVS

Setting of the divider to apply to the encoder repetition output frequency.

- 0 No division
- 1 Divide 2
- 2 Divide 4
- 3 Divide 8

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.5	5108	Encoder 2 signal Vpp	V	FLOAT		1.0	0.8	1.2	ERWZ	FVS

Setting of the encoder 2 signal peak-to-peak voltage value. Incremental sinusoidal encoders and absolute SinCos encoders normally produce signals with a peak-to-peak voltage of 1 Vpp. Due to voltage drops along the cable, the signal may have a lower peak-to-peak voltage when it reaches the feedback card, triggering the **Speed fbk loss** alarm.

This parameter is used to configure the value of the peak-to-peak voltage of the incremental sinusoidal encoders and absolute SinCos encoders on the input terminals of the feedback card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.6	5110	Encoder2signal check		ENUM		Contr A-B	0	3	ERWZ	FVS

Configuration of which channels of the incremental digital encoder 2 must be controlled for processing the **Speed fbk loss** [22].

- 0 Check disabled
- 1 Check A-B
- 2 Check A-B-Z
- 4 Check A-B-SE

If set to 1, the application checks for the presence of the signals of channels A-B

If set to 2, the application checks for the presence of the signals of channels A-B-Z

If set to 4, the application controls loss of feedback for SE (single ended) encoders.

If the application detects the absence of feedback the **Speed fbk loss [22]** is generated.

As loss of feedback cannot be detected at speeds of around zero, the control is only performed if the speed reference is higher than the value set in parameter **4564 SpdFbkLoss threshold**. It is also important to consider the fact that when working with a speed reference slightly above the limit set in parameter **4564 SpdFbkLoss threshold**, the speed error could exceed the set threshold, given the load or current limit, and generate false alarms.

In that case increase the value of parameter **4550 SpdRefLoss threshold** or of parameter **4554 SpdRefLoss holdoff**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.7	5112	Encoder 2 SSI clocks		UINT16		13	11	25	ERWZ	FVS

Setting of the length of the serial package of the SSI encoder 2 used. The value is shown on the encoder data-sheet and defined in clock cycles (usually from 13 to 25 bits).

Example of single-turn encoder

13 position bits: set par 5114 = 13.

13 clock bits: set par 5112 = 13.

Example of multi-turn encoder

13 position bits: set par 5114 = 13.

25 clock bits: set par 5112 = 25.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.8	5114	Encoder2SSI pos bits		UINT16		13	11	25	ERWZ	FVS

Setting of the number of bits used by the SSI encoder 2 to define the position.

See examples of PAR 5112.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.9	5182	Encoder2 ENDAT clock		ENUM		1 MHz	0	1	ERWZ	FVS

Selection of clock value for Encoder 2 ENDAT type.

0 1 MHz

1 500 kHz

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.10	5130	Encoder 2 direction		ENUM		Not inverted	0	1	ERWZ	FVS

Selection of the encoder direction

0 Not inverted

1 Inverted

If set to 0 the encoder feedback signals are not inverted.

If set to 1 the encoder feedback signals are inverted.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.11	5132	Encoder 2 mode		ENUM		None	CALCI	CALCI	ERWZ	FVS

Setting of the method for measuring the speed of the digital encoder connected to the optional card.

0 Nessuna

1 Digital FP

2 Digital F

3 Sinus

4 Sinus SINCOS

5 Sinus ENDAT

- 6 Sinus SSI
- 7 Sinus HIPER
- 8 Resolver
- 9 Abs SINCOS
- 10 ENDAT
- 11 SSI

In the presence of the **Enc 1** encoder option:

- setting **1** (Digital FP) selects the method for measuring frequency and period. This selection is preferable for applications that rotate at very low speeds.
- setting **2** (Digital F) selects the method for measuring frequency. This type of measurement lets you achieve high precision and dynamics at medium and high speed.

In the presence of the **Enc 4** encoder option:

- selection **10** (ENDAT), as opposed to selection **5** (Sinusoidal ENDAT), indicates that the encoder has no incremental channels. Switching between the two selections is automatic by means of a recognition procedure.
- selection **11** (SSI), as opposed to selection **6** (Sinusoidal SSI), indicates that the encoder has no incremental channels. Switching between the two selections has to be performed manually during commissioning.

The other settings are relative to the type of encoder used.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.12	5134	Encoder2speed filter	ms	FLOAT		2.000	0.125	20.000	ERW	FVS

Setting of the time constant of the filter applied to the reading of the feedback encoder impulses. The parameter affects both the precision of the speed measurement and the dynamics obtainable in the closed-loop control mode. Long update times provide greater stability (increased filtering) of speed measurement, as more encoder impulses are counted at a given speed of rotation. On the other hand, the speed measurement filter adds delays that prevent high control loop dynamics. Low settings increase the regulation bandwidth but could accentuate disturbance.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.13	5150	Encoder 2 speed	rpm	INT16 16/32		0	0	0	ER	FVS

The speed measured for encoder 2 is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.14	5162	Encoder 2 position	cmt	UINT16 16		0	0	0	ER	FVS

The encoder position is displayed. The scaling factor is Number encoder impulses *4.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.15	5360	Encoder 2 state		UINT16		0	0	0	ER	FVS

Indicates the state of Encoder 2 (1= error, 0 = no error) regardless of whether this Encoder is used/not used as feedback for motor control.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.3.16	5362	Encoder 2 err code		UINT32		0	0	0	ER	FVS

This parameter contains a hexadecimal code that supplies information on the type of error that occurred.

Error values are the same (and have the same significance) as the ones indicated in parameter IPA 2172 **Spd-FbkLoss code**.

17.4 - ENCODER/ENCODER 3

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.1	5200	Encoder 3 pulses	ppr	UINT16		1024	128	32768	ERWZ	FVS

Setting of the number of impulses/rev of the incremental encoder mounted in slot 1 or 3.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.2	5204	Encoder 3 input cfg		ENUM		TTL	0	1	ERWZ	FVS

Setting of the input configuration of incremental digital encoder 3, TTL or HTL. If the encoder has an internal power supply the level of the encoder's supply voltage is equal to that set for encoder 2.

0 HTL

1 TTL

The value of this parameter is automatically set in HTL when the value entered in the **Encoder 2 supply** parameter is more than 6.0V.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.3	5210	Encoder3signal check		ENUM		Check A-B	0	3	ERWZ	FVS

Configuration of which channels of the incremental digital encoder 3 must be controlled for processing the **Speed fbk loss [22]**.

0 Check disabled

1 Check A-B

2 Check A-B-Z

4 Check A-B-SE

If set to 1, the application checks for the presence of the signals of channels A-B

If set to 2, the application checks for the presence of the signals of channels A-B-Z

If set to 4, the application controls loss of feedback for SE (single ended) encoders.

If the application detects the absence of feedback the **Speed fbk loss [22]** is generated.

As loss of feedback cannot be detected at speeds of around zero, the control is only performed if the speed reference is higher than the value set in parameter **4564 SpdFbkLoss threshold**. It is also important to consider the fact that when working with a speed reference slightly above the limit set in parameter **4564 SpdFbkLoss threshold**, the speed error could exceed the set threshold, given the load or current limit, and generate false alarms.

In that case increase the value of parameter **4550 SpdRefLoss threshold** or of PAR **4554 SpdRefLoss holdoff**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.4	5230	Encoder 3 direction		ENUM		Not inverted	0	1	ERWZ	FVS

Selection of the encoder direction

0 Not inverted

1 Inverted

If set to 0 the encoder feedback signals are not inverted.

If set to 1 the encoder feedback signals are inverted.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.5	5262	Encoder 3 position	cnt	UINT16	16	0	0	0	ER	FVS

The encoder position is displayed. The scaling factor is Number encoder impulses *4.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.6	5370	Encoder 3 state		UINT16		0	0	0	ER	FVS

Indicates the state of Encoder 3 (1= error, 0 = no error) regardless of whether this Encoder is used/not used as feedback for motor control.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.4.7	5372	Encoder 3 err code		UINT32		0	0	0	ER	FVS

This parameter contains a hexadecimal code that supplies information on the type of error that occurred.

Error values are the same (and have the same significance) as the ones indicated in parameter IPA 2172 **Spd-FbkLoss** code.

17.5 - ENCODER/RESOLVER

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.1	2116	Resolver pole pairs		UINT16		1	1	8	ERWZ	FVS

Setting of pairs of poles of resolver used (see resolver plate data).

- 1 1 pair of poles
- 2 2 pairs of poles
- ...

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.2	2118	Resolver frequency	Hz	UINT16		8000	2000.0	10000.0	ERWZ	FVS

Value of the resolver frequency (see Resolver name plate data). Step 250Hz.

Nota!

In order to manage the **EXP-RES-I1R1-ADV** card, three parameters need to be set: PAR 2118, 2120 and 2116.

Parameters PAR 2124 and 2128 could be modify if it is require a fine tuning of the card and resolver output voltage are outside the limits.

Please refer to **EXP-RES-I1R1-ADV** Resolver option card instruction book (code 1S5F33) for more detailed informations

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.3	2120	Resolver T ratio K		FLOAT		0.5	0.2	1.0	ERWZ	FVS

Value of the resolver Trasformer ratio of used resolver (see Resolver name plate data).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.4	2122	Resolver repetition		ENUM		16384 ppr	0	3	ERWZ	FVS

Simulated selection of the resolver repetition.

- 0 256 ppr
- 1 1024 ppr
- 2 4096 ppr
- 3 16384 ppr

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.5	2124	Resolver LOS thr	V	FLOAT		2.200	0.000	4.820	ERWZ	FVS

Loss Of Signal threshold: Setting of the lower threshold value of the Resolver signal. Values below this setting will generate a **Speed fbk loss [22]** alarm.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.6	2128	Resolver MIS thr	V	FLOAT		0.380	0.000	4.820	ERWZ	FVS

A threshold value between SIN and COS signal amplitudes can be set.

An alarm is shown If it is detected an amplitude value differences higher than the value set in MIS threshold.

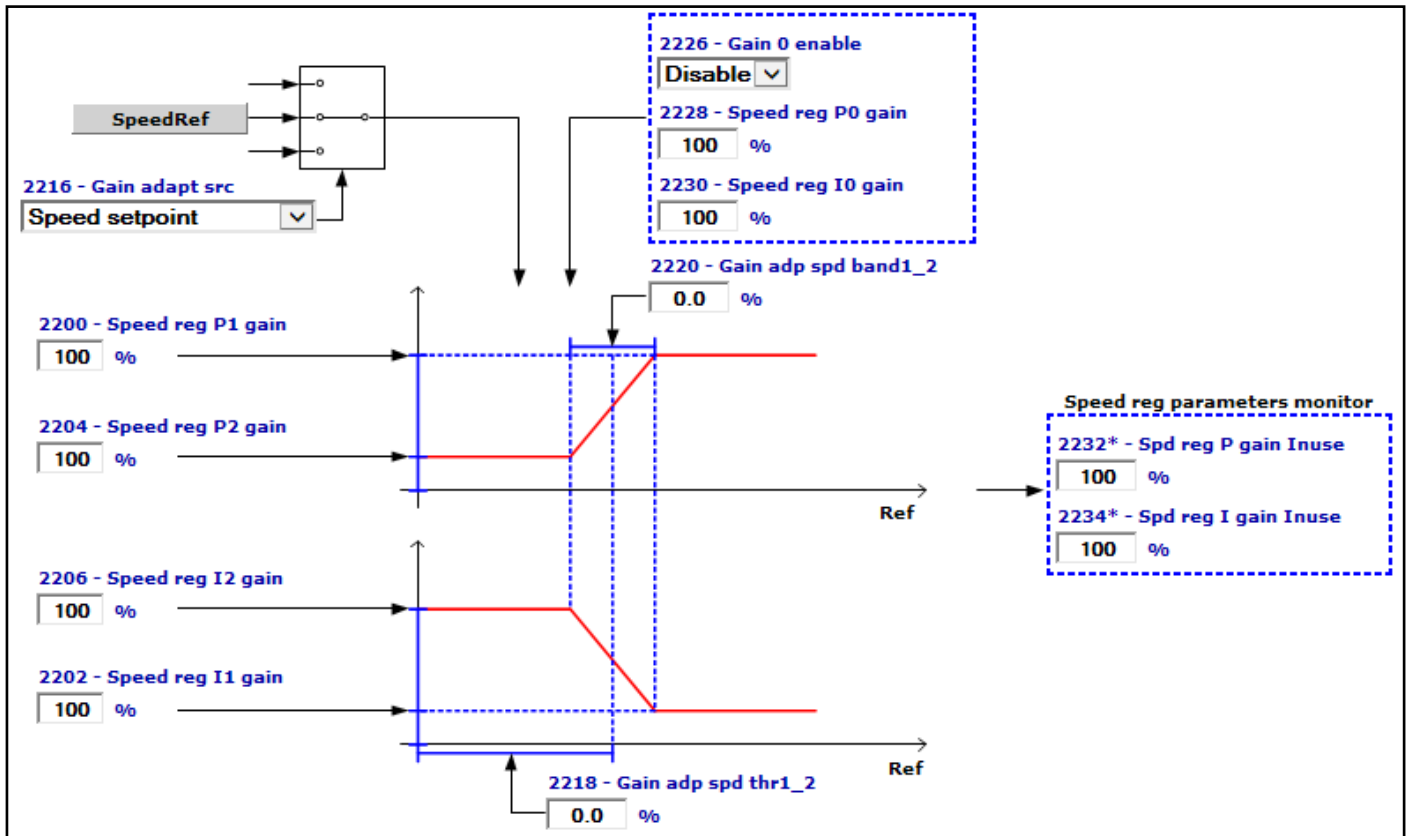
This value can be increased: If the alarm does not disappear, the resolver used could be defective or the wiring drive-resolver are not correct.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
17.5.7	2094	Resolver freeze0 src		LINK	16	6000	0	16384	ERWZ	FVS
17.5.8	2096	Resolver freeze1 src		LINK	16	6000	0	16384	ERWZ	FVS

It indicates which digital input can be used as **Freeze input 0** or **Freeze input 1** when resolver feedback is used and managed thru MDPLC application. Digital input is updated every 125 µsec.

Input can be selected from those available on “**L_RESFREEZE**” selection list.

18 – SPEED REG GAINS



The speed adaptive allows different speed regulator gains to be obtained according to the speed or another value. The behaviour of the speed regulator can thus be configured in the best way for the specific application requirements.

Note ! Current, flux and voltage regulators can be set using the self-tuning procedure. If this is not successful, current and flux regulators can be tuned manually (this does not apply to voltage regulators, which must not be modified by the user). The speed regulator must be tuned manually. Gains are usually adjusted according to the drive speed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.1	2200	Speed reg P1 gain	perc	INT16		100	0	1000	RW	F_S
18.2	2202	Speed reg I1 time	perc	INT16		100	0	1000	RW	F_S

Setting of the proportional and integral gain of the speed regulator, set 1.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.3	2204	Speed reg P2 gain	perc	INT16		100	0	1000	ERW	F_S
18.4	2206	Speed reg I2 time	perc	INT16		100	0	1000	ERW	F_S

Setting of the proportional and integral gain of the speed regulator, set 2.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.5	2216	Gain adapt src		LINK	16/32	664	0	16384	ERW	F_S

Selection of the origin (source) of the signal to be used for the adaptive speed gain. The values that can be associated with the function are listed in the “**L_REF**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.6	2218	Gain adapt spd thr 1_2	perc	FLOAT		0.0	0.0	100.0	ERW	F_S

Setting of the speed threshold for changing gains from set 1 to set 2.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.7	2220	Gain adapt spd band 1_2	perc	FLOAT		0.0	0.0	100.0	ERW	F_S

Setting of the band within which gains vary between set 1 and set 2. The use of this parameter ensures a smooth transition between the two parameter sets.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.8	2226	Gain 0 enable		ENUM		Disable	0	1	ERW	F_S

Enabling of the gain at zero speed.

0 Disable

1 Enable

When this parameter is set to 0 the control of gains at zero speed is disabled.

When this parameter is set to 1 the control of gains at zero speed is enabled. This function is used to improve the response of the motor below the zero speed threshold (Speed zero threshold)..

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.9	2228	Speed reg P0 gain	perc	INT16		100	0	1000	ERW	F_S

Setting of the proportional gain of the speed regulator at zero speed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.10	2230	Speed reg I0 gain	perc	INT16		100	0	1000	ERW	F_S

Setting of the integral gain of the speed regulator at zero speed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.11	2232	Spd reg P gain Inuse	perc	INT16	16/32	100	0	1000	ER	F_S

The current proportional coefficient of the speed regulator is displayed as a percentage.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.12	2234	Spd reg I gain Inuse	perc	INT16	16/32	100	0	1000	ER	F_S

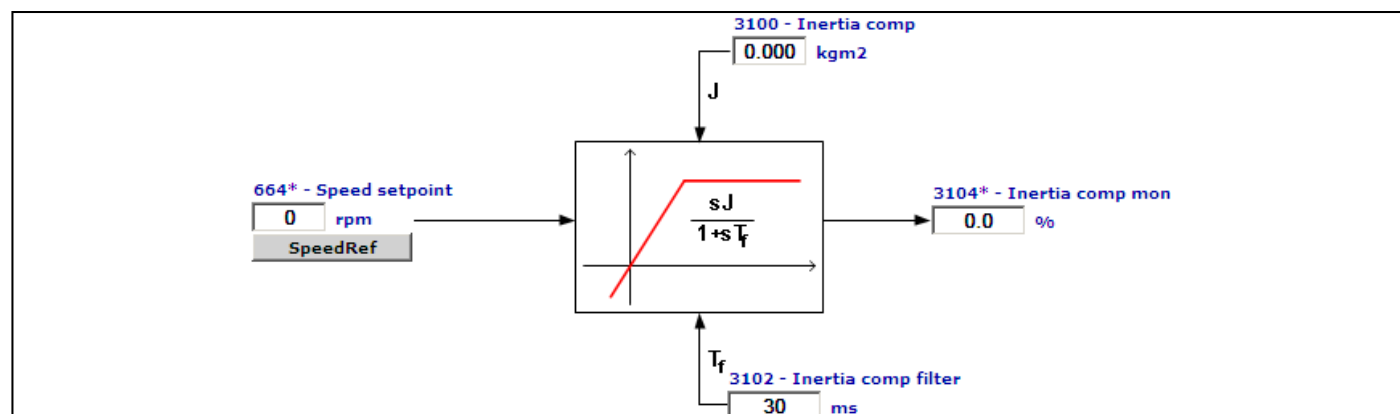
The current integral coefficient of the speed regulator is displayed as a percentage.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.13	2236	Speed reg P gain	N/rpm	FLOAT		CALCF	0.0	500.0	ERWS	F_S

Setting of the proportional coefficient of the speed regulator.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.14	2238	Speed reg I time	ms	FLOAT		CALCF	1.0	5000.0	ERWS	F_S

Setting of the integral coefficient of the speed regulator.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.15	2244	Speed reg I dis src		LINK	16/32	6000	0	16384	ERW	F_S

Selection of the origin (source) of the signal for Enabling/disabling of the Integral part of the Speed regulator (Null= enabled). The signal to be associated with this function can be selected from the "L_DIGSEL2" selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.16	2246	Speed reg P factor	perc	FLOAT	16/32	0	0	0	ER	F_S

Monitor of the proportional component value of the Speed regulator output. It is also available thru analog output.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.17	2248	Speed reg I factor	perc	FLOAT	16/32	0	0	0	ER	F_S

Monitor of the integral component value of the Speed regulator output. It is also available thru analog output.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.18	2240	Inertia	kgm ²	FLOAT		SIZE	0.001	100.0	RWZS	F_S

Setting of total inertia of the application with reference to the motor shaft.

Inertia is the tendency of a body at rest to remain at rest or of a body in straight line motion to stay in motion in a straight line unless acted on by an outside force;

Setting the total system inertia value (motor + mechanical transmission), the drive will set automatically the PAR 2236 **Speed reg P gain** proportional gain of the speed regulator in order to react immediately to the speed variations.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
18.19	2242	Bandwidth	rad/s	FLOAT		SIZE	1.0	500.0	RWZS	F_S

Setting of the bandwidth.

The bandwidth defines the dynamic performance in terms of capacity of follow the speed references or torque which are time variable .

Increasing the value, the drive response time will increase (automatically will increase PAR 2236 **Speed reg P gain** and decrease PAR 2238 **Speed reg I time**).

Higher value can be used in the case of "rigid" connections between the motor and the machine. Otherwise you may encounter instability of the system.

19 – REGULATOR PARAM

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.1	2250	Current reg P gain	V/A	FLOAT		CALCF	0.0	0.0	ERWS	F_S
Setting of the proportional coefficient of the current regulator.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.2	2252	Current reg I time	ms	FLOAT		CALCF	0.01	10000.0	ERWS	F_S
Setting of the integral coefficient of the current regulator.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.3	2260	Flux reg P gain	A/Wb	FLOAT		CALCF	0.0	0.0	ERWS	F__
Setting of the proportional coefficient of the flux regulator.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.4	2262	Flux reg I time	ms	FLOAT		CALCF	0.01	10000.0	ERWS	F__
Setting of the integral coefficient of the flux regulator.										

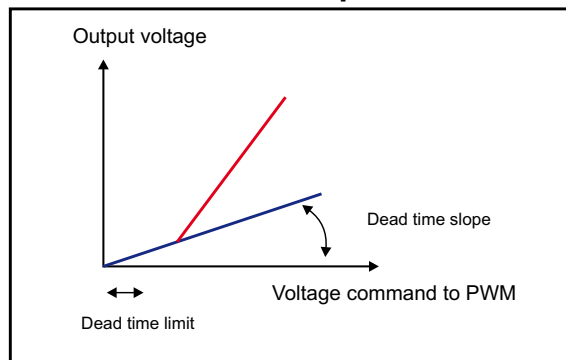
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.5	2264	Flux reg P gain OL	A/Wb	FLOAT		CALCF	0.0	0.0	ERWS	__S
Setting of the flux regulator proportional gain when the drive is used in Flux vector OL control mode. This parameter is set automatically by the self-tuning procedure.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.6	2266	Flux reg I time OL	ms	FLOAT		CALCF	0.01	10000.0	ERWS	__S
Setting of the flux regulator integral time when the drive is used in Flux vector OL control mode. This parameter is set automatically by the self-tuning procedure.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.7	2270	Voltage reg P gain	Wb/V	FLOAT		CALCF	0.0	0.0	ERWS	F_S
Setting of the proportional coefficient of the voltage regulator.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.8	2272	Voltage reg I time	s	FLOAT		CALCF	0.1	100.0	ERWS	F_S
Setting of the integral coefficient of the voltage regulator.										

Dead time compensation



The dead time compensation function (**Dead time compensation**), compensates the distortion of output voltage caused by the voltage drop on the IGBT devices and their switching characteristics. Distortion of output voltage could cause irregular motor rotation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.9	2280	Dead time limit	V	FLOAT		SIZE	0.0	50.0	ERWS	FVS
Setting of the dead time voltage compensation value.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.10	2282	Dead time slope	V/A	FLOAT		SIZE	0.0	200.0	ERWS	FVS
Setting of the dead time compensation slope value.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.11	2290	Voltage base	V	FLOAT		CALCF	50.0	690.0	ERWS	F_S
Setting of the voltage value that determines the threshold at which flux weakening starts (maximum drive output voltage). If this parameter is set to a value equal to the nominal speed of the motor, operation is at nominal flux in the constant torque region and weakened flux at higher frequencies. The default value is set to the voltage supply value.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.12	2292	Voltage margin	perc	FLOAT		5.0	0.0	10.0	ERWS	F_S
Setting of the voltage regulation margin according to the available voltage. In case of a Voltage base setting close to or equal to the actual mains value, Voltage margin represents the margin allowable by the voltage regulation to perform rapid current variations when load steps are suddenly applied. A value of 5% allows a very fast response to load steps but with a loss of output voltage and thus power output (reduced power output). The minimum value (1%) allows a maximum output voltage (around 98%) of the mains voltage to be achieved but with loss of quality of the dynamic response.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.13	2300	Minimum speed OL	rpm	INT16		30	0	CALCI	ERW	_S
Setting of the minimum speed threshold in the Flux vector OL control mode. Below this limit the sensorless regulator is disabled.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.14	2302	Min speed delay OL	ms	UINT16		200	0	5000	ERW	_S
Setting of the delay for disabling the sensorless regulator.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.15	2304	Speed filter OL	ms	FLOAT		5.0	0.1	20.0	ERWZ	_S
Setting of the time constant for the estimated speed in Flux vector OL mode. By increasing this parameter it is possible to reduce the level of disturbance of the estimated speed, but the speed control dynamics are also lowered.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.16	2306	Flux observ gainH OL		FLOAT		250.0	10.0	5000.0	ERW	_S
Gain value of the Flux observer at the high frequency/speed (Flux vector OL control mode).										
Note: Frequency value set in IPA2322 must be higher than the value set in IPA2324 (without sign). All the Flux gain values between the two frequency are obtained through linear interpolation. The default gain value set at the low frequency (IPA 2316) should guarantee smooth operation for all motor power sizes. For any possible issues during the speed starting phase is possible to improve the response of the motor by changing the value of the gain. Normally high gain values guarantee more stability, but could lead to errors on estimation Torque value. The gain at high frequency (IPA 2306) must be changed if speed fluctuations at high rpm are shown. By increasing the gain value it is possible to get better performance, however, too high values could lead to instability of the motor speed control.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.17	2322	Freq observ gainH OL	rad/s	FLOAT		50.0	0.0	5000.0	ERW	__S

Frequency value above which applies the gain of the Flux observer at the high frequency (Flux vector OL control mode).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.18	2316	Flux observ gainL OL		FLOAT		100.0	0.0	5000.0	ERW	__S

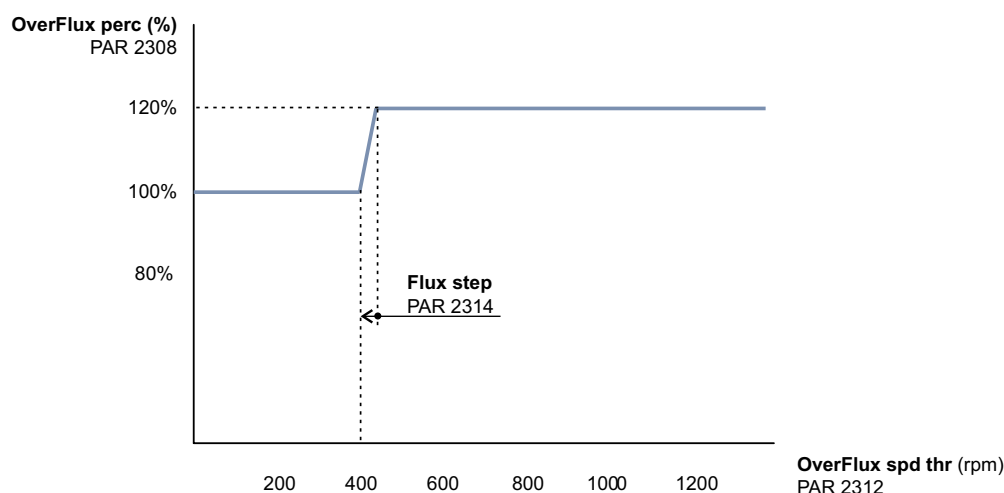
Gain value of the Flux observer at the low frequency/speed (Flux vector OL control mode).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.19	2324	Freq observ gainL OL	rad/s	FLOAT		1.0	0.0	5000.0	ERW	__S

Frequency value below which applies the gain of the Flux observer at the low frequency (Flux vector OL control mode).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.20	2308	OverFlux perc	perc	FLOAT		100.0	100.0	140.0	ERW	__S

The value is expressed as the percentage in excess of the rated flux.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.21	2310	Flux weakening OL		ENUM		Enable	0	1	ERWZ	__S

Enables or disables flux reduction in the open-loop flux vector control mode.

If set to Disable, the flux is not reduced when the speed of the motor exceeds the nominal speed. This results in loss of control and instability.

To prevent this problem, set the parameter to Enable.

In the open-loop mode a flux value of less than the nominal speed of the motor is advantageous in terms of stability.

0 Disable

1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.22	2312	OverFlux spd thr	rpm	FLOAT		400	10.0	1000.0	ERW	__S

Speed limit below which the overflux value set in PAR 2308 **OverFlux perc**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.23	2314	Flux step		FLOAT		20.0	1	2000	ERW	__S

Setting of the ramp time in the transition between the rated flux and the overflux value set in PAR 2308 **OverFlux perc**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.24	2320	Magnetization time	ms	UINT16		256	128	4096	ERWZ	FVS

This parameter is used to slow down the magnetisation transient and prevent the motor shaft from rotating due to the alignment of the stator and rotor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.25	2504	Torque comp offset	Nm	FLOAT		0.0	0	1000	ERW	F_S

Parameter managing torque offset compensation in Sensorless mode. The parameter is entered by means of a dedicated self-calibration procedure.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.26	2506	Measured motor temp	degC	FLOAT		20.0	-20.0	150.0	ERW	F_S

Motor temperature measured during self-calibration.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.27	2510	Motor temp comp en		ENUM		Disable	0	1	ERWZ	__S

Enables thermal compensation of the motor.

0 Disable

1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.28	2512	Torque offset speed	perc	UINT16		75	10	100	ERWZ	__S

Motor rotation speed during self-calibration of torque offset, as a percentage of nominal motor speed PAR 2004.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.29	2514	Torque offset ramp	s	FLOAT		10.0	10	100.0	ERWZ	__S

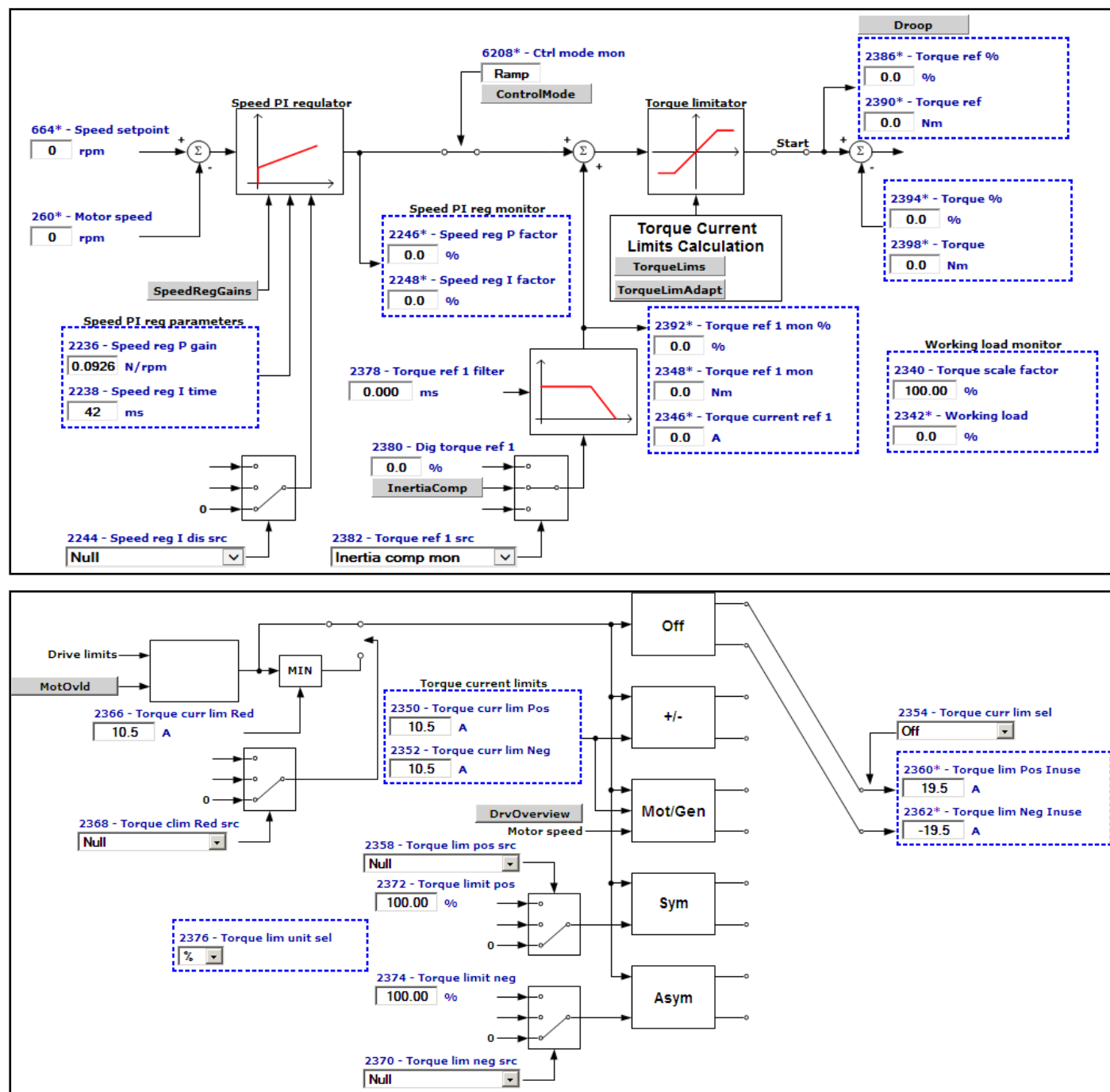
Time needed to go to **Torque offset speed** IPA 2512.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
19.30	2516	Torque offset tune		BIT		0	0	1	ERWZ	__S

Runs self-calibration procedure for automatic calculation of torque offset.

The drive has to be in Local mode: press the Local key and close the contact to enable hardware (terminals 7 and S3).

20 – TORQUE CONFIG



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.1	2350	Torque curr lim Pos	A	FLOAT	16/32	CALCF	0.0	CALCF	ERWS	FVS

Setting of the active torque limit of the drive for the positive current direction (clockwise rotation and anti-clockwise braking).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.2	2352	Torque curr lim Neg	A	FLOAT	16/32	CALCF	0.0	CALCF	ERWS	FVS

Setting of the active torque limit of the drive for the negative current direction (anti-clockwise rotation and clockwise braking).

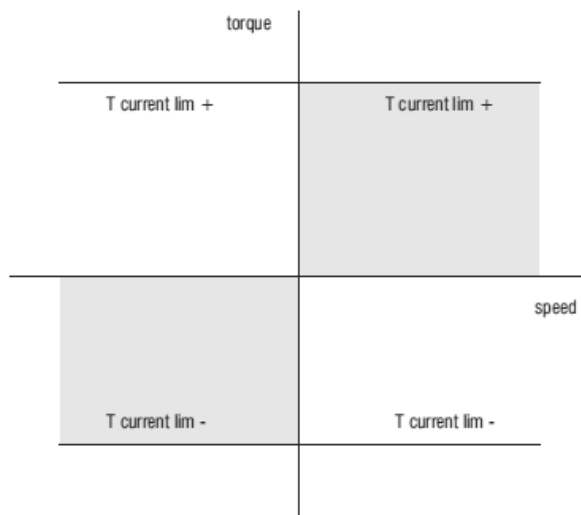
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.3	2354	Torque curr lim sel		ENUM		Off	0	4	ERWZ	FVS

Setting of the type of behaviour of the drive in the current limit condition.

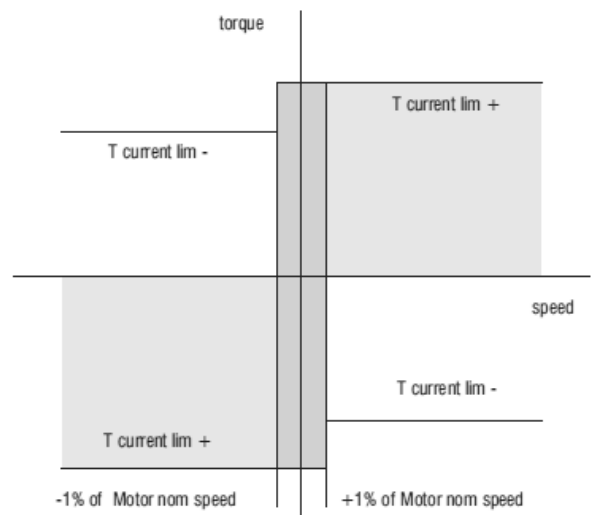
- 0 Off
- 1 T clim +/-
- 2 T clim mot/gen
- 3 T lim sym
- 4 T lim pos/neg

If set to **0** no specific type of current limitation is set.

If set to **1** the active positive torque limit is **Torque curr lim Pos** and the active negative torque limit is **Torque curr lim Neg**; the limit is provided on the torque current.



Torque limits with **Torque curr lim Sel = 1**



Torque limits with **Torque curr lim sel = 2**

If set to **2** three conditions are possible:

- 1 - If the motor speed is $> +1\%$ of **Rated speed** the active positive torque limit is **Torque curr lim Pos** and the active negative torque limit is **Torque curr lim Neg**.
- 2 - If the motor speed is $< -1\%$ of **Rated speed** the active positive torque limit is **Torque curr lim Neg** and the active negative torque limit is **Torque curr lim Pos**.
- 3 - If -1% of Motor non speed $<$ motor speed $<$ $+1\%$ of **Rated speed** the active positive torque limit is **Torque curr lim Pos** and the active negative torque limit is **Torque curr lim Neg**

If set to **3** the torque limits are symmetrical. The torque reference is the value of parameter **2358 Torque lim pos src**. This mode is not managed in the V/f control mode. The limit is provided on the torque current.

If set to **4** the torque limits are assigned independently, setting the value of parameter **2358 Torque lim pos src** as the positive torque reference and the value of parameter **2370 Torque lim neg src** as the negative torque reference. The torque reference is the value of parameter **2370 Torque lim neg src**. This mode is not managed in the V/f control mode. The limit is provided on the torque current.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.4	2358	Torque lim pos src		LINK	16/32	6000	0	16384	ERWZ	F_S

Selection of the origin (source) to be used to set the torque limit:

If parameter **2354 Torque curr lim sel** is set to 3 the torque limit is symmetrical

If parameter **2354 Torque curr lim sel** is set to 4 the torque limit is positive

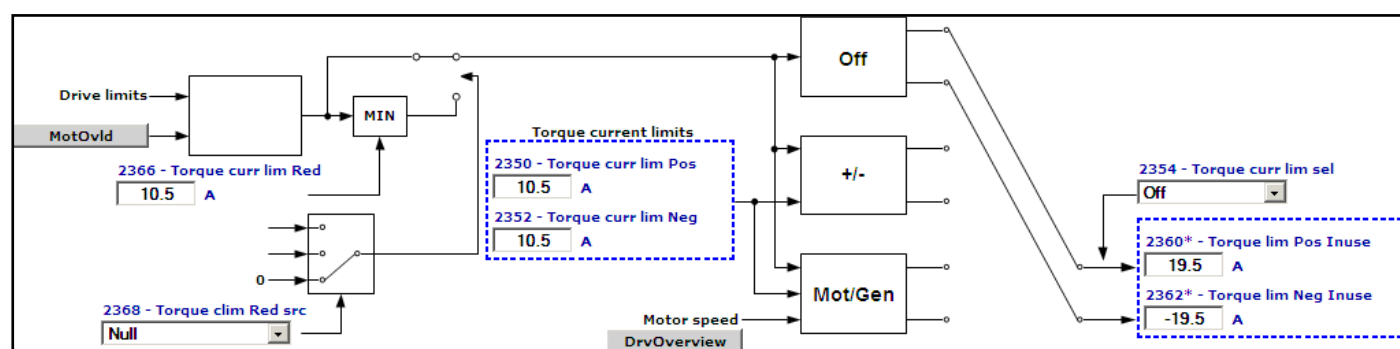
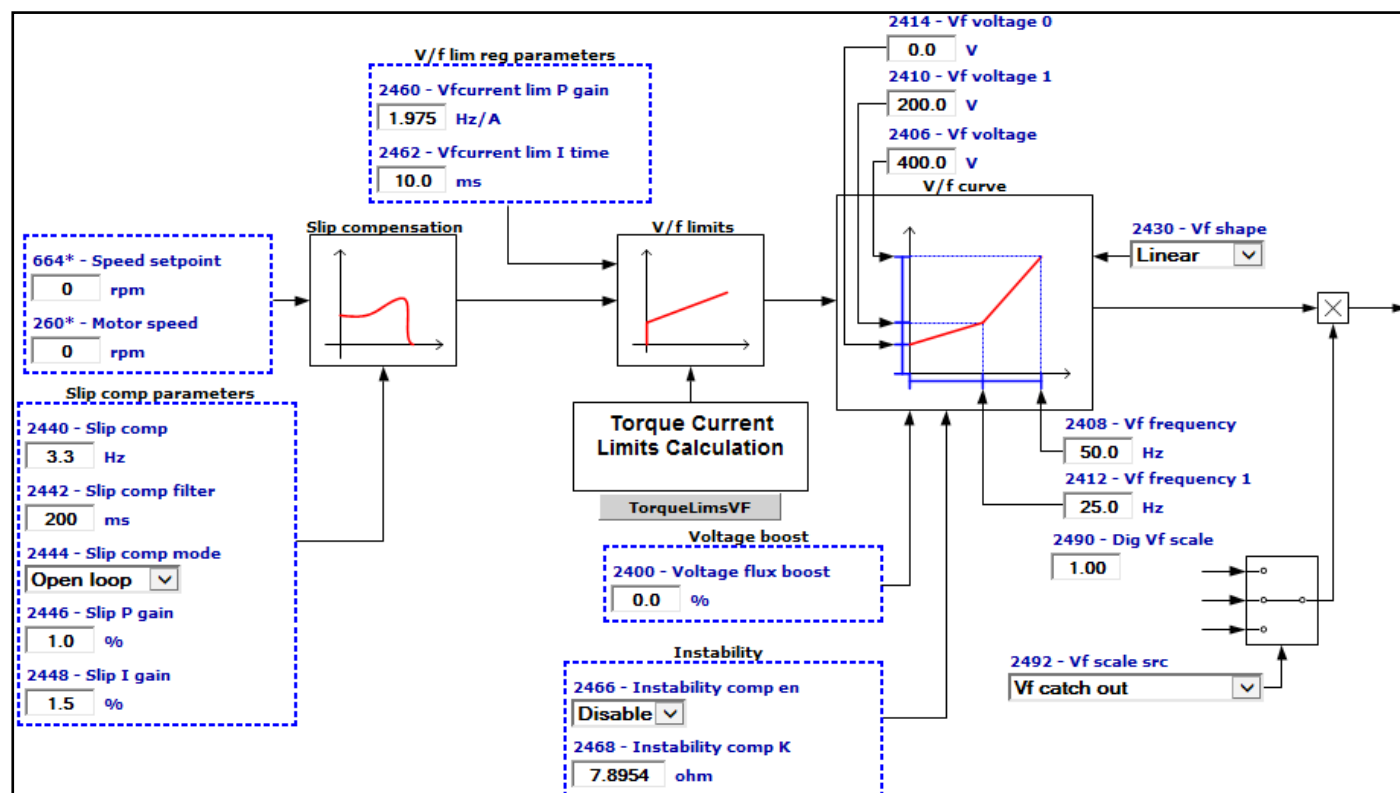
The signals that can be associated with the function can be selected from the “**L_PLIM**” selection list.

Parameter IPA 2338 **Torque lim adapt** can be selected (from the “**L_PLIM**” selection list) if parameter IPA 2354 **Torque curr lim sel** is set to [3] **T lim sym** to manage symmetrical torque limits.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.5	2370	Torque lim neg src		LINK	16/32	6000	0	16384	ERWZ	FVS
Selection of the origin (source) to be used for the negative torque limit. The signals that can be associated with the function can be selected from the “ L_LIM ” selection list										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.6	2372	Torque limit pos	perc	FLOAT	16/32	CALCF	0.0	CALCF	ERW	F_S
Setting of the positive limit for torque limitation.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.7	2374	Torque limit neg	perc	FLOAT	16/32	CALCF	0.0	CALCF	ERW	F_S
Setting of the negative limit for torque limitation.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.8	2376	Torque lim unit sel		ENUM		%	0	1	ERW	F_S
Setting of the unit of measure for torque limits.										
0 % 1 Nm										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.9	2360	Torque lim Pos Inuse	A	FLOAT	16/32	0.0	0.0	0.0	ER	FVS
The positive torque limit value currently being used is displayed. When parameter 2354 is set to [3] T lim sym or [4] T lim pos/neg , the unit of measure of parameter 2360 is Nm.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.10	2362	Torque lim Neg Inuse	A	FLOAT	16/32	0.0	0.0	0.0	ER	FVS
The negative torque limit value currently being used is displayed. When parameter 2354 is set to [3] T lim sym or [4] T lim pos/neg , the unit of measure of parameter 2362 is Nm.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.11	2378	Torque ref 1 filter	ms	FLOAT		0.0	0.0	1000.0	ERW	F_S
Setting of filter on Torque Feed forward filter monitoring. If IPA2378=0, disabled.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.12	2380	Dig torque ref 1	perc	FLOAT	16/32	0.0	-300.0	300.0	ERW	F_S
Setting of a digital torque reference. The current reference value is proportional to the active motor current and determines the torque value. The sign determines the torque direction.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.13	2382	Torque ref 1 src		LINK	16/32	3104	0.0	16384	ERWZ	F_S
Selection of the origin (source) of the signal to be used for the torque reference. The signals that can be associated with the function can be selected from the “ L_VREF ” selection list.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.14	2392	Torque ref 1 mon %	perc	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
Torque ref 1 monitor in %										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.15	2346	Torque current ref 1	A	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
Monitoring of the torque current reference 1 in Amps. Monitoring is always active both when the drive is enabled or disabled.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.16	2348	Torque ref 1 mon	Nm	FLOAT		1.0	0.125	10.0	ER	FVS
Torque ref 1 monitor in Nm.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.17	2384	Torque ref filter	ms	FLOAT		1.000	0.125	10.000	ERW	F_S
Setting of a filter on the torque reference monitoring.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.18	2386	Torque ref %	perc	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
Monitoring of the torque reference value in %.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.19	2390	Torque ref	Nm	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
Monitoring of the torque reference value in Nm.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.20	2394	Torque %	perc	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
Monitoring of the % value of the motor nominal Torque. Values are available thru analog outputs.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.21	2398	Torque	Nm	FLOAT		0.0	0.0	0.0	ER	F_S
Monitoring of the Nm value of the motor nominal Torque. Values are available thru analog outputs.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.22	2366	Torque curr lim Red	A	FLOAT	16/32	CALCF	0.0	CALCF	ERWS	F_S
Setting of the torque current limit when the 2368 Torque clim Red src command is enabled. The default value and maximum value are automatically calculated by the drive whenever any changes are made to the motor plate data and after autotuning.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.23	2368	Torque clim Red src		LINK	16	6000	0	16384	ERW	F_S
Selection of the origin (source) to be used to reduce the torque current limit. When this command is enabled the torque limit passes to the level set in parameter 2366 Torque curr lim Red . The signals that can be associated with the function can be selected from the “ L_DIGSEL2 ” selection list.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.24	2340	Torque scale factor	perc	FLOAT		100.00	1.00	200.00	ERW	F_S
Scale factor of nominal motor torque in % (Torque % , IPA 2394) to let the user display motor torque in the required scale. Scaled torque % = Torque % (IPA 2394) * 100 / Torque scale factor (IPA 2340).										

21 – FV PARAMETERS



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.1	2404	Voltage torque boost		ENUM		Disable	0	1	ERWZ	V

Enables the automatic voltage boost. The automatic boost should be enabled in case of heavy loads or high inertias applied to the motor shaft (for example, large fans).

The default drive setting is to pure V/f control.

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.2	2406	Vf voltage	V	FLOAT		CALCF	10.0	690.0	ERWZS	V

Setting of the maximum voltage value to be applied at the motor terminals (usually set according to the motor data plate).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.3	2408	Vf frequency	Hz	FLOAT		CALCF	10.0	2000.0	ERWZS	V

Setting of the motor rated frequency (indicated on the motor data plate)

This is the frequency at which the drive output voltage reaches the maximum output voltage (**Vf voltage**) on the motor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.4	2410	Vf voltage 1	V	FLOAT		CALCF	CALCF	CALCF	ERWZS	V

Setting of an intermediate voltage value for the custom V/f characteristic curve.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
215	2412	Vf frequency 1	Hz	FLOAT		CALCF	0.0	CALCF	ERWZS	V

Setting of an intermediate frequency value for the custom V/f characteristic curve.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.6	2414	Vf voltage 0	V	FLOAT		CALCF	0.0	CALCF	ERWZS	V

Compensation of IR voltage drop at 0 Hz. This parameter must be increased in case of pure V/f control. The increase depends on the size of the motor. Values that are too high could cause an overcurrent and motor saturation.

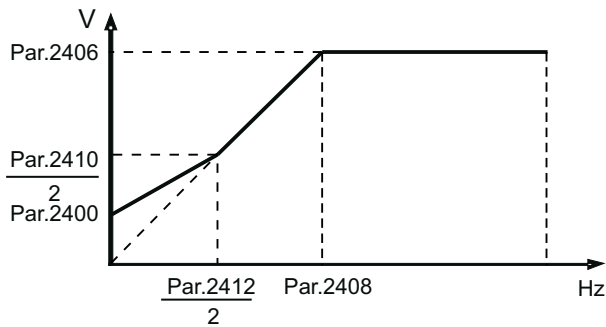
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.7	2430	Vf shape		ENUM		Linear	0	2	ERWS	V

Selection of the type of V/f characteristic curve

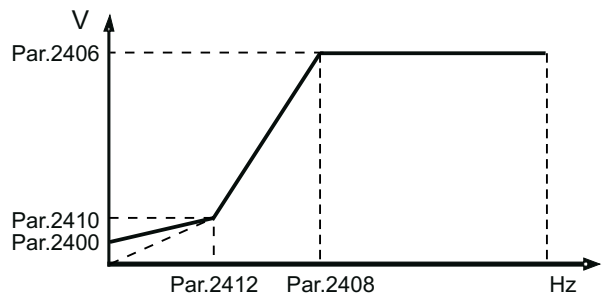
- 0 Linear
- 1 Custom
- 2 Quadratic

Set **0 (Linear)** to obtain a linear V/f characteristic curve, on which the intermediate points are reset to a value that is equal to half those of parameters **2406** and **2408**.

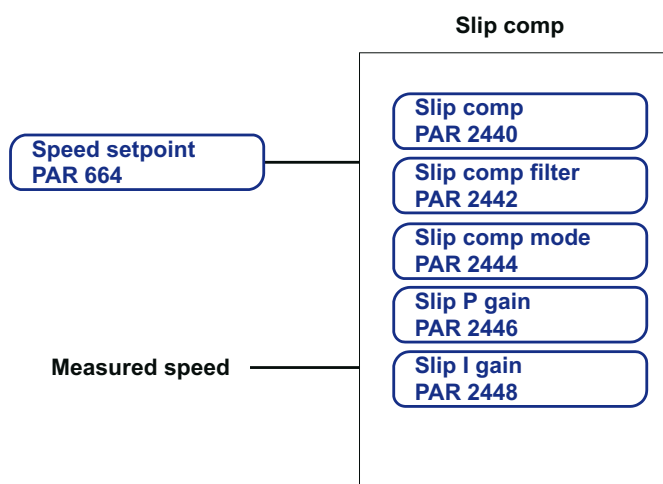
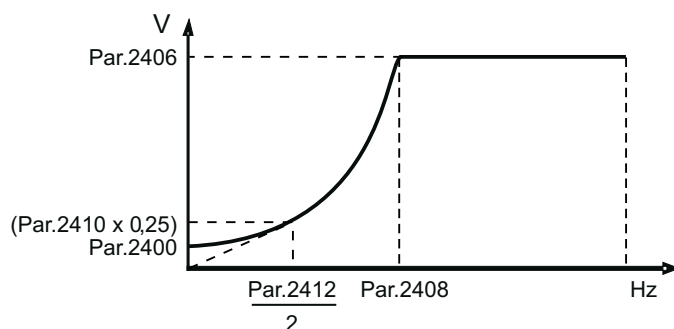
The Boost joins the curve automatically.



Set **1 (Custom)** to obtain a customized V/f characteristic curve, in which the intermediate voltage and frequency values are defined by parameters **2410** and **2412**, as is the point at which the Boost joins the characteristic curve.



Set **2 (Quadratic)** to obtain a quadratic V/f characteristic curve, useful for controlling pumps and fans, where torque is proportional to the square of the speed. When this type of curve is selected, the median voltage point is fixed at 0.25% of the maximum output voltage (par.2406), and the median frequency point at 50% of the basic frequency (par.2408).



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.8	2440	Slip comp	Hz	FLOAT		CALCF	0.0	10.0	RWS	V

Setting of the slip compensation. When the asynchronous motor is loaded, the mechanical speed of the motor shaft varies according to the electric slippage, which affects torque generation. The slip compensation function can be used to maintain a constant motor shaft speed. Compensation is performed by varying the drive output frequency as a function of its output current and the motor parameters. Thus, to obtain the best effect, the motor plate data must be set appropriately, and the correct stator resistance value (Par.2050) must be set or measured using the self-tuning function. The slip compensation value is calculated automatically during the self-tuning procedure or set manually in this parameter.

During slip compensation tuning the drive must not be in the current limit condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.9	2442	Slip comp filter	ms	UINT16		200	50	5000	ERW	V

Setting of the slip compensation filter. The value set in this parameter determines the slip compensation function reaction time. The lower this parameter is set, the greater the slip compensation reaction. If this parameter is too low, it could cause undesirable oscillations in speed after sudden variations to the applied load.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.10	2444	Slip comp mode		ENUM		Open loop	0	1	ERW	V

Setting of the slip compensation mode.

- 0 Open loop
- 1 Closed loop

When set to **0 (Open loop)** the slip compensation value is that set manually in parameter 5210 or calculated by the self-tuning procedure.

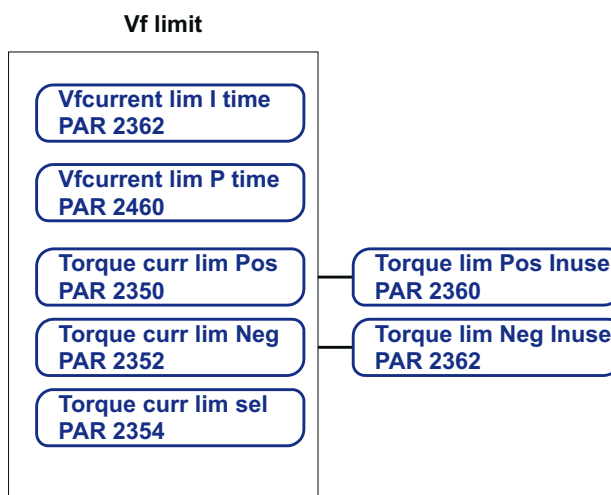
If set to **1 (Closed loop)** the slip compensation value is measured by the reading of the signals by a digital encoder keyed to the motor shaft. The EXP-DE-I1R1F1-ADV expansion card must be installed in the drive in order to acquire encoder signals.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.11	2446	Slip P gain	perc	FLOAT		1.0	0.0	100.0	ERWS	V

Setting of the slip compensation proportional gain.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.12	2448	Slip I gain	perc	FLOAT		1.5	0.0	100.0	ERWS	V

Setting of the slip compensation integral gain.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.13	2460	Vfcurrent lim P gain	Hz/A	FLOAT		CALCF	0.0	1000.0	ERWS	V

Setting of the proportional gain limit in V/f mode. This is calculated automatically if the self-tuning procedure is performed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.14	2462	Vfcurrent lim I time	ms	FLOAT		CALCF	1.0	50.0	ERWS	V

Setting of the proportional gain limit in V/f mode. This is calculated automatically if the self-tuning procedure is performed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.15	2466	Instability comp en		ENUM		Disable	0	1	ERWZ	V

This parameter enables/disables the current stabilization of an asynchronous motor controlled in V/F. It may happen that in certain operational situations the motor could show unstable behavior (excessive oscillations of the current) in conditions of zero load (low values of load) and at low speeds. If active, this function is able to control these oscillations making the system stable.

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.16	2468	Instability comp K	ohm	FLOAT		CALCF	0	200.0	ERWS	V

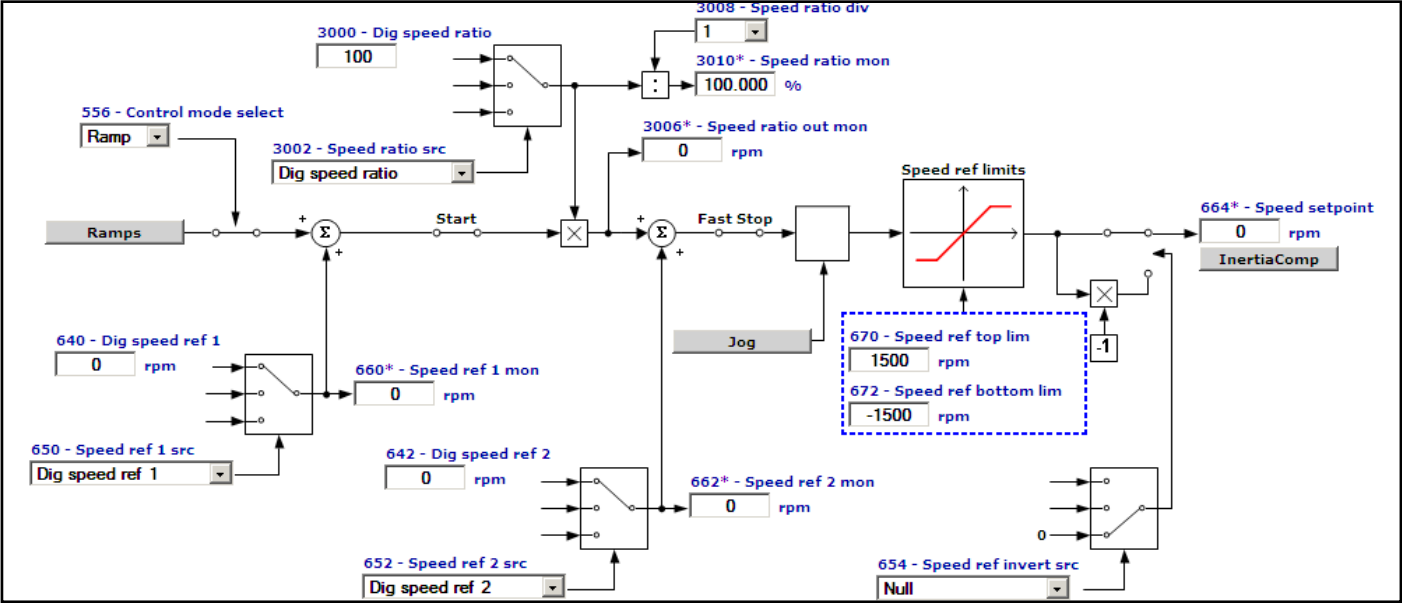
This parameter defines the gain value of the instability compensator. The value is automatically calculated by the drive when the motor data are inserted and the **Take parameters** command (PAR 2020) is executed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.17	2480	Vf min frequency	Hz	FLOAT		1.0	0.2	5.0	ERW	V

Setting of the minimum frequency in the V/f control mode. This represents the minimum output frequency, below which frequency regulations are ineffective. It is not possible to go below this value, regardless of the reference that has been set.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.18	2482	Vf min freq delay	ms	UINT16		800	0	5000	ERW	V
Setting of the delay for the minimum frequency signal in the V/f control mode.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.19	2490	Dig Vf scale		FLOAT	16/32	1.0	0.0	1.0	ERWZ	V
Setting of a digital multiplier factor for the drive output voltage in the V/f mode.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
21.20	2492	Vf scale src		LINK	16/32	3374	0	16384	ERW	V
Selection of the origin (source) of the signal to be used to set a multiplier factor for the drive output voltage. The associable functions are listed in the “ L_VREF ” selection list.										

22 – FUNCTIONS



22.1 – FUNCTIONS/SPEED RATIO

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.1.1	3000	Dig speed ratio	perc	INT16	16/32	100	CALCI	CALCI	ERW	FVS

This function allows a configurable speed ratio (Speed ratio) to be applied to the main reference and determines the speed ratio percentage. This setting can be performed in digital form, via fieldbus, or through an analog input. This function is useful in “multi drive” systems where a slip value is required between the various motors being used. The resulting speed value can be read through the Speed ratio mon parameter on a programmable analog output.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.1.2	3002	Speed ratio src		LINK	16/32	3000	0	16384	ERW	FVS

Selection of the origin (source) of the signal that determines the speed ratio percentage value. The terminal to be associated with this function can be selected from the “L_VREF” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.1.3	3008	Speed ratio div		ENUM		1	1	1000	ERW	FVS

This parameter defines the number of decimal positions for setting PAR 3000 **Dig speed ratio**. Possible values are shown in the table below:

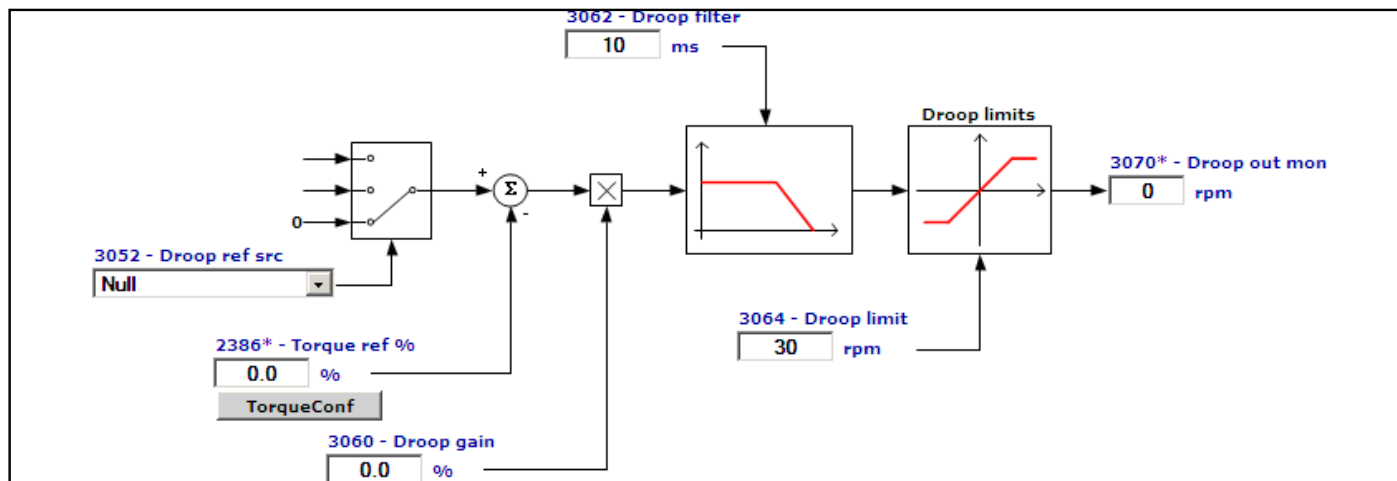
Speed ratio divider	Values that can be set in PAR 3000 Dig speed ratio	Corresponding % value
1	0-200	0-200
10	0-2000	0-200.0
100	0-20000	0-200.00
1000	0-32000	0-32.000

1	1
10	10
100	100
1000	1000

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.1.4	3010	Speed ratio mon	FLOAT	INT16		0	0	0	ER	FVS

The speed ratio value to apply to the selected speed reference signal value is displayed.

22.2 – FUNCTIONS/DROOP



The Droop function is only active in **Regulation mode = Flux vector OL or Flux vector CL**.

The block consists of:

- a node of comparison between **Droop ref src** connected to the **Analog inp** of the master drive torque reference (set Torque ref nofilter on the master analog output) and slave drive torque reference (**Torque ref nofilter** produced by the speed regulator).
- a proportional regulator the output of which is added to or subtracted from the reference of the slave drive speed regulator. Set **Speed ref 1 src** equal to **Droop out mon**.

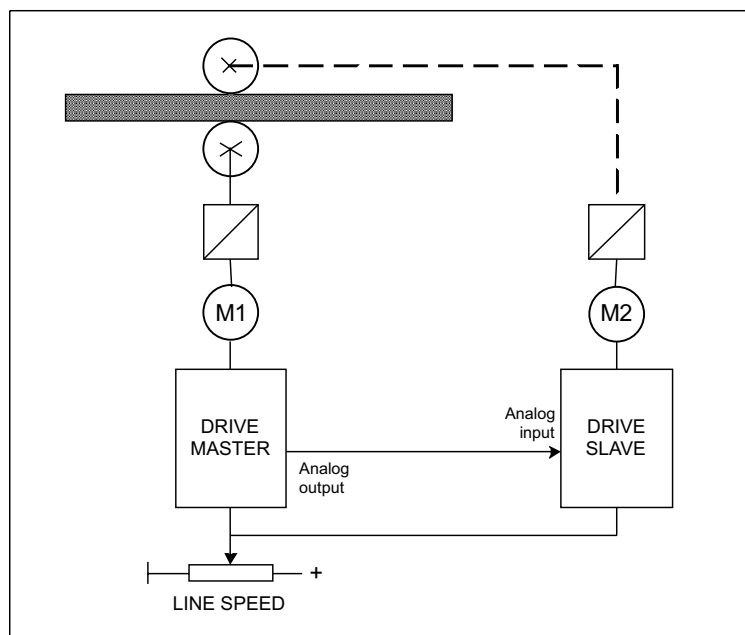
Before it is applied to the reference of the slave drive speed regulator, the adjustment passes through a low-pass filter and a limit.

The Droop function is used to control two coupled motors.

The advantage of using the Droop block is that the speed regulator can remain enabled on both drives. If using the Droop function, it can be adjusted to avoid speed regulator saturation on one of the two drives. Should there be a loss of load by one of the two drives, the adjustment provided by the Droop block is limited by the dedicated parameter.

This function is used to scale the current. This block is typically used when two motors are coupled mechanically to one another (for example if they are connected to the same shaft). They must turn at the same speed. If one of the two motors tends to turn faster, the result is a difference in the load conditions which leads to an Overload condition. The second motor acts as a brake. This causes a current unbalance, which can be eliminated by using the Droop function. An adjustment is added to or subtracted from the reference of the slave drive speed regulator (proportional to the load difference) to re-balance the two currents.

Example of machine on which the droop function can be used.



Parameter configuration:

Master drive:

Analog out x src connected to **Torque ref nofilter**

Slave drive:

Droop ref src connected to **Analog inp.**

Speed ref 1 src connected to **Droop out mon.**

Set "**Droop gain**", **Droop limit**, **Droop filter**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.2.1	3052	Droop ref src		LINK	16/32	6000	0	16384	ERW	F_S

This parameter can be used to select the origin (source) of the **Droop ref src** signal. The signal to be associated with this function can be selected from the "**L_LIM**" selection list. Select an analog input to which an analog signal from the master drive with information about the torque reference level will be connected.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.2.2	3060	Droop gain	perc	FLOAT		0.0	0.0	100.0	ERW	F_S

Use the **Droop gain** parameter to tune the proportional regulator gain. Setting this parameter to 0.0 forces the output of the Droop block to 0.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.2.3	3062	Droop filter	ms	UINT16		10	1	100	ERW	F_S

The **Droop filter** parameter can be used to tune the filter time constant.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.2.4	3064	Droop limit	rpm	INT16	16/32	30	0	CALCI	ERWZ	F_S

The **Droop limit** parameter can be used to tune the absolute value of the maximum adjustment applied by the Droop block to the speed reference.

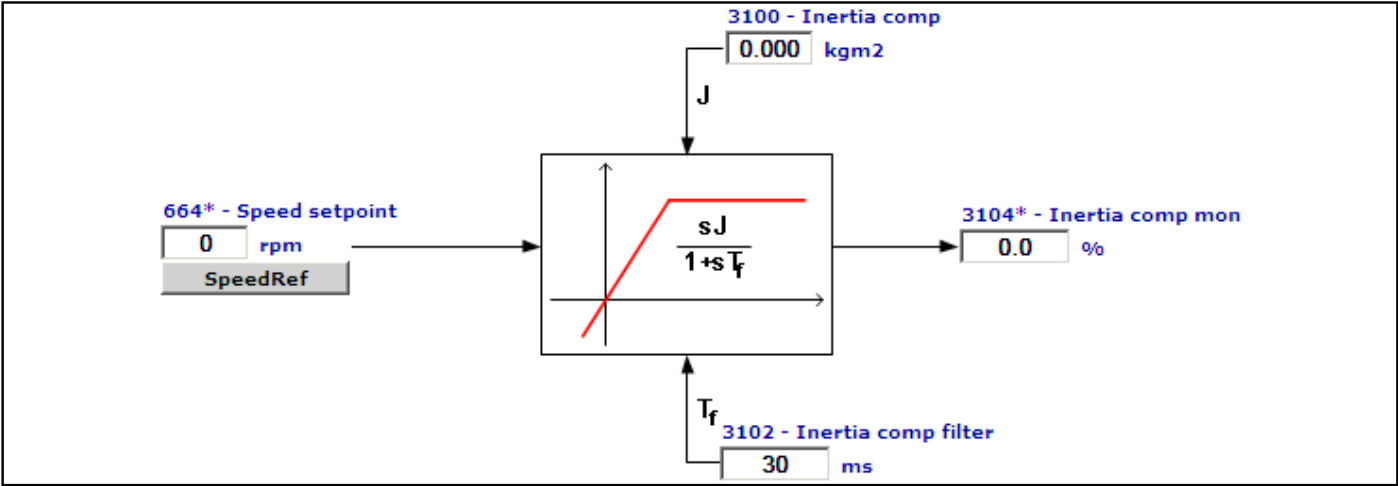
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.2.5	3070	Droop out mon	rpm	INT16	16/32	0	0	0	ER	F_S

The **Droop out mon** parameter can be used to read the size of the adjustment applied by the Droop block.

This variable is typically connected to **Speed ref 1 src** to add or substrat the adjustment by the Droop function to or from the speed reference.

This parameter is available in the speed reference, analog output, slave->master and compare selection lists.

22.3 – FUNCTIONS/INERTIA COMP



An increase in the dynamic response of the speed regulator with a variation in the reference, can be modified by varying the current value during the acceleration/deceleration phase, to counter the applied inertia of the machine.

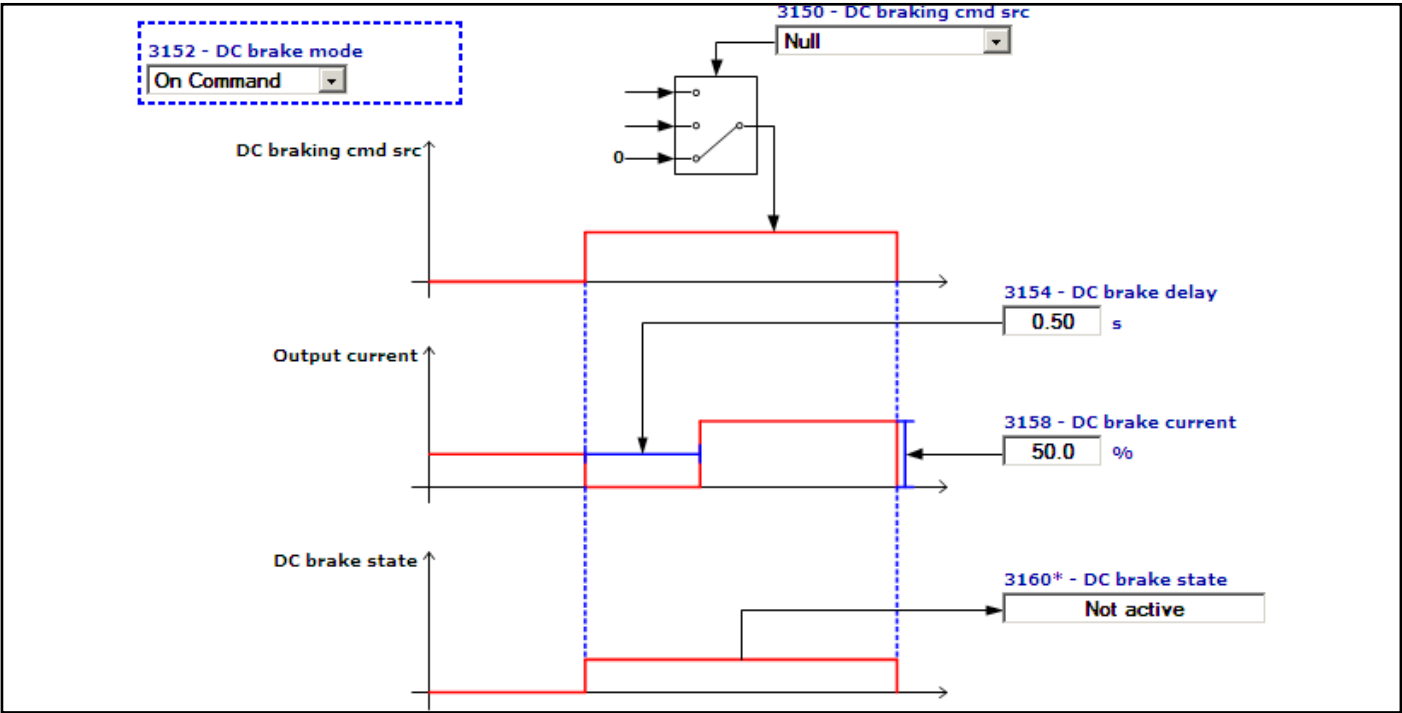
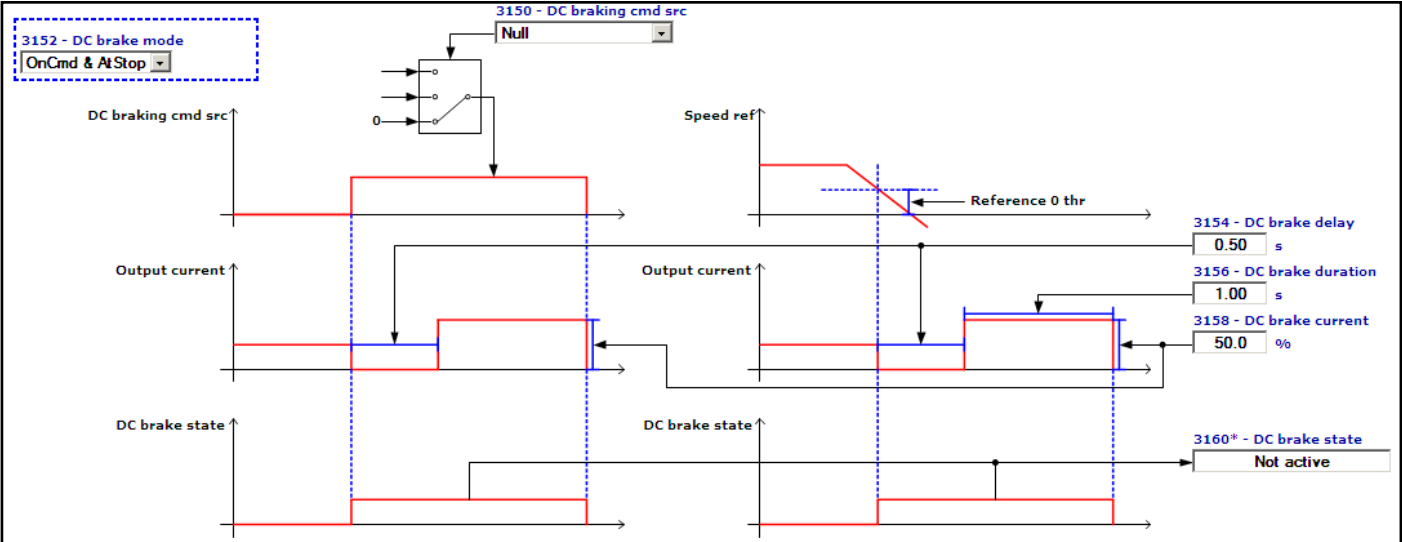
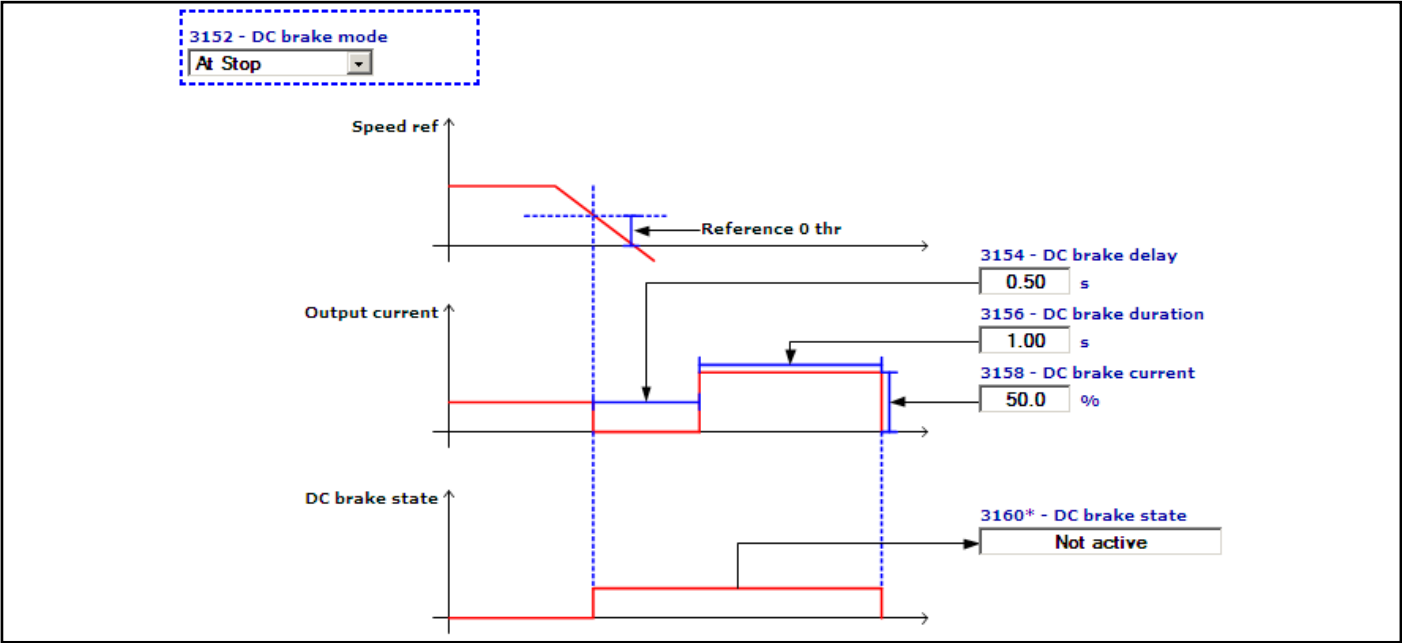
These parameters can be set manually by the user.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.3.1	3100	Inertia comp	kgm ²	FLOAT		0.0	0.0	100.0	ERWS	F_S
Inertia compensation value at motor shaft. Increasing this value can speed up the speed setpoint search. However, if the system inertia value set in PAR 2240 is incorrect, it could cause instability of speed.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.3.2	3102	Inertia comp filter	ms	UINT16		30	1	100	ERW	F_S
Setting of a filter on the torque compensation. The filter reduces noise due to speed differentiation in the inertia block.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.3.3	3104	Inertia comp mon	perc	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
The value of inertia compensation on the function block output is displayed.										

22.4 – FUNCTIONS/DC BRAKING



The drive is capable of managing a direct current injection phase. During this phase a braking torque is generated that can be used to stop the motor or block the rotor.

The following characteristics can be configured:

- signal used to activate the direct current injection phase
- direct current injection phase activation mode
- delay between activation of request for DC braking and start of direct current injection
- duration of direct current injection phase
- intensity of injected direct current

This function is useful for:

- slowing the motor running at any speed to zero speed
- slowing a motor driven by the load before applying the start command
- keeping the rotor blocked at the end of a deceleration ramp following a stop command.

This function cannot be used for intermediate braking as the motor speed must be brought to zero.

During the direct current injection phase the kinetic energy of the motor is dissipated as heat in the motor.

The following parameters allow complete control of the function.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.4.1	3150	DC braking cmd src		LINK	16	6000	0	16384	ERW	FVS

This parameter is used to select the origin (source) of the **DC braking cmd** signal. The signal to be associated with this function can be selected from the "L_DIGSEL2" selection list.

If the command is activated (=1) DC braking is enabled.

In the default condition the origin of the **DC braking cmd** signal is 6000 (disabled).

Note!

During the injection phase in DC on control, the ramp reference is set to zero to prevent any excessively rapid restarts at the end of the phase.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.4.2	3152	DC brake mode		ENUM		Off	0	1	ERW	FVS

Setting of the direct current braking mode.

- 0 Off
- 1 Stop
- 2 Cmd
- 3 Cmd&Stop
- 4 Start
- 5 Start&Stop
- 6 Cmd&Start
- 7 Cmd&Start&Stop

If set to **0** the direct current injection phase is never executed.

If set to **1** the direct current injection phase is executed when the stop command is sent and the speed reference threshold = zero has been reached.

In "**Cmd**" mode **2** the direct current injection phase is executed when the **DC braking cmd** configured using parameter PAR **3150 DC braking cmd src** is sent.

In "**Cmd&Stop**" **3** modes the direct current injection phase is executed when one of the two conditions described in the "**Stop**" or "**Cmd**" modes is present.

In "**Start**" mode **4** the direct current injection phase is executed when the start command is sent

In "**Start&Stop**" mode **5** the direct current injection phase is executed when the start command is sent and when the stop command is sent and the speed reference threshold = zero has been reached.

In "**Cmd&Start**" mode **6** the direct current injection phase is executed when one of the two conditions described in the "**Cmd**" or "**Start**" modes is present.

In "**Cmd&Start&Stop**" mode **7** the direct current injection phase is executed when one of the three conditions described in the "**Cmd**" or "**Start**" or "**Stop**" modes is present.

Note:

During DC braking injection, ramp reference is set to zero

When DC injection is required with start command, is executed when speed reference threshold = zero has been reached

Mode 1 Example:

With the motor running at any speed, when the stop command is enabled the ramp output decreases according to the selected ramp time. When the speed reference threshold = zero is reached **PAR 934 Riferimento = 0** the direct current injection phase is enabled and direct current injection starts after a delay set in **PAR 3154 DC brake delay**. **PAR 3156 DC brake duration** is used to configure the duration of the injection phase and **PAR 3158 DC brake current** is used to configure the intensity of the injection phase current.

Mode 2 Example:

Motor running driven by load. When the drive is enabled and the **DC braking cmd** is sent the direct current injection phase is activated. When the command is enabled and after the delay configured in **PAR 3154 DC brake delay** direct current injection starts. **PAR 3156 DC brake duration** is used to configure the duration of the injection phase and **PAR 3158 DC brake current** is used to configure the intensity of the injection phase current.

If the command is an impulse shorter than the time set with **PAR 3156 Durata frenatura DC**, the direct current injection phase continues at least for the time set in parameter **3156 DC brake duration**.

If the command is an impulse longer than the time set with **3156 DC brake duration**, the direct current injection phase continues for as long as the command is present.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.4.3	3154	DC brake delay	s	FLOAT		0.5	0.00	30.0	ERW	FVS

This parameter is used to configure the delay in seconds between the moment DC braking is requested and the moment direct current injection starts. This delay enables the motor to demagnetise, and thus avoid an overcurrent due to the electromotive force of the motor (e.f.m.).

The value of this parameter, added to parameter **3156 DC brake duration**, must be lower than the value of parameter **1006 Speed 0 disable dly**, otherwise direct current injection will stop when the drive is disabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.4.4	3156	DC brake duration	s	FLOAT		1.0	0.01	30.0	ERW	FVS

This parameter is used to configure the duration of direct current injection in the stator windings.

The value of this parameter, added to parameter **3154 DC brake delay**, must be lower than the value of parameter **1006 Speed 0 disable dly**, otherwise direct current injection will stop when the drive is disabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.4.5	3158	DC brake current	perc	FLOAT		50.0	0.0	150.0	ERW	FVS

This parameter is used to configure the value of the injected direct current.

It is expressed as a percentage of the drive continuous current (**PAR 488 Drive cont current**).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.4.6	3160	DC brake state		ENUM	16	Non active	0	1	ER	FVS

The status of direct current braking is displayed.

0 Non active

1 Active

Note !

During the direct current injection phase the **Enable** command should not be enabled. If the **Enable** command is sent to the drive, the ramp output starts following the set reference; direct current output is produced in any case. The moment the **DC braking cmd** is removed there is immediately a speed step without performing a change in the ramp.

During the direct current injection phase, for the **Jog** command follow the instructions provided for the **Enable** command.

22.5 – FUNCTIONS/AC BRAKING

The AC braking is a technique of stopping the motor in a very efficient way for motors power up to 160 kW. Its effectiveness is reduced with higher power ratings. Because the energy is dissipated as heat in the motor, It does not replace the standard dynamic braking (braking chopper) or regenerative solutions, however, it can be used as an alternative in certain applications such as fans and centrifugal.

The minimum deceleration ramp (stopping time) achieved depends on the load conditions, the operating conditions (speed of the motor) and by the masses (total moment of inertia related to the motor shaft). The torque of the load, for its braking action, can be taken into consideration as favourable for the motor to stop.

Note ! This feature is active on V/f control Regulation mode only. It is not recommended if the operative conditions require frequent working duty Cycles.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.5.1	2484	AC braking		ENUM		Disable	0	1	ERWZ	_V_

This parameter enables/disables the function.

0 Disable

1 Enable

Setting the parameter to 0, AC Braking is disabled. Setting to 1 the parameter is enabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.5.2	2486	AC brake Kp	V/A	FLOAT		CALCF	0.0	100.0	ERWS	_V_

This parameter defines the proportional gain of the PI controller used in the AC braking. Its value is based on the motor data entered by the user and it is automatically calculated by the drive. Increasing manually the obtained value, it increases its execution but could cause motor speed oscillations.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.5.3	2488	AC brake Ti	ms	FLOAT		CALCF	1.0	1000.0	ERWS	_V_

This parameter defines the value of the integral component of the PI controller used in the AC braking. Its value is based on the motor data entered by the user and it is automatically calculated by the drive. Reducing manually the obtained value, it increases its execution but could cause motor speed oscillations.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.5.4	2478	AC brake active ref	perc	FLOAT		-2	-10	10	ERWS	_V_

This parameter defines the threshold value of the active component of the motor current to below which enables the function to dissipate as heat the energy regenerated by the motor during its deceleration. It is defined as a percentage of the rated drive current. Values close to zero or greater than zero anticipate the intervention of the braking and increase the dissipation of energy, but can generate unnecessary activations in conditions of zero load or light load. Values less than zero produce the opposite effect.

Application Example:

The following example is referred to a constant torque application. The values used allow to roughly calculate the minimum ramp braking time (decTime) using the AC Braking function.

Necessary Data:

P_n	Motor Nominal Power
ω_{max}	Max Motor Speed
ω_0	Initial braking Speed
η_{mot}	Motor Efficiency
η_{inv}	Inverter Efficiency
J	Total moment of inertia related to the motor shaft
T_{load}	Torque value of the applied Load

$$P_n = 160 \text{ kW}$$

$$\text{Max Speed} = 1500 \text{ rpm } (\omega_{\max} = 1500 * 2\pi / 60 = 157.08 \text{ rad/s})$$

$$\text{Initial speed} = 70\% (\omega_0 = 1050 * 2\pi / 60 = 110 \text{ rad/s})$$

$$\eta_{\text{mot}} = 0.96$$

$$\eta_{\text{inv}} = 0.98$$

$$J = 5 \text{ kgm}^2$$

$$T_{\text{load}} = \text{Negligible for Constant Torque app}$$

0,5 = Internal Coefficient

$$P_{\text{loss_max}} = 0.5 * (1 - \eta_{\text{mot}}) * P_n + (1 - \eta_{\text{inv}}) * P_n$$

$$P_{\text{loss_max}} = 0.5 * (1 - 0.96) * 160000 + (1 - 0.98) * 160000 = 6400 \text{ W}$$

$$\text{decTime} > (J * \omega_{\max} * \omega_0) / (P_{\text{loss_max}})$$

Considering negligible T_{load} value for constant torque applications, the resulting minimum deceleration value will be:

$$\text{decTime} > (5 * 157.08 * 110) / (6400) = 13.5 \text{ s}$$

Nota!

The braking action of the applied load and friction can contribute to reduce the minimum time of deceleration. This further reduction depends on the characteristics of the load. For variable torque application, the reduction could be substantial. Contact Gefran for application support.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Maxi	Acc	Mod
22.5.5	2494	AC brake with UVRT		ENUM		Enable	0	1	ERW	_V_
	0	Disable								
	1	Enable								

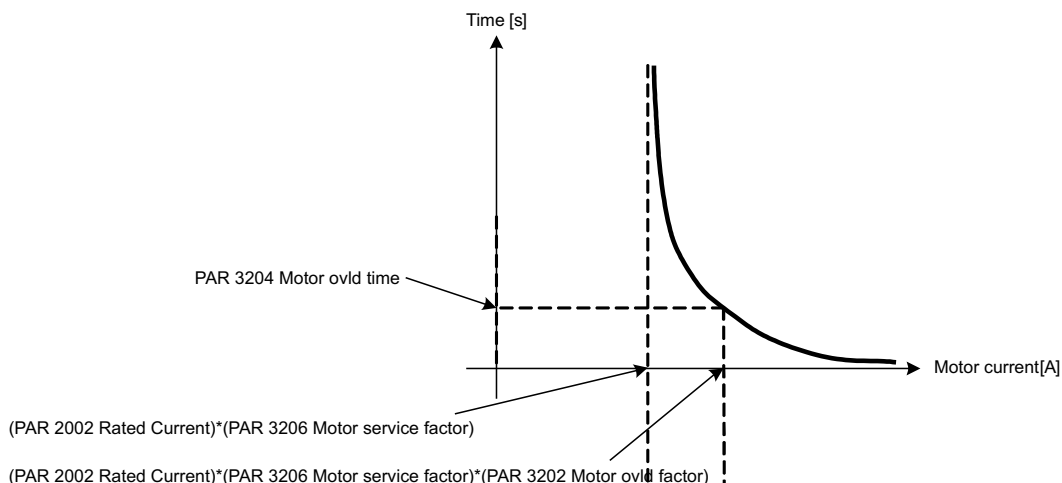
This parameter allows to disable AC braking during activation of UV RT (see “22.11 - FUNCTIONS/UV RIDE THROUGH” on page 135).

- PAR 2494 = 1 (default) and PAR 3280 = 1 (UV Ride Through function enabled): in case of mains voltage dip, the AC brake stay enabled.
- PAR 2494 = 0 and PAR 3280 = 1: in case of mains voltage dip, the AC brake is disabled

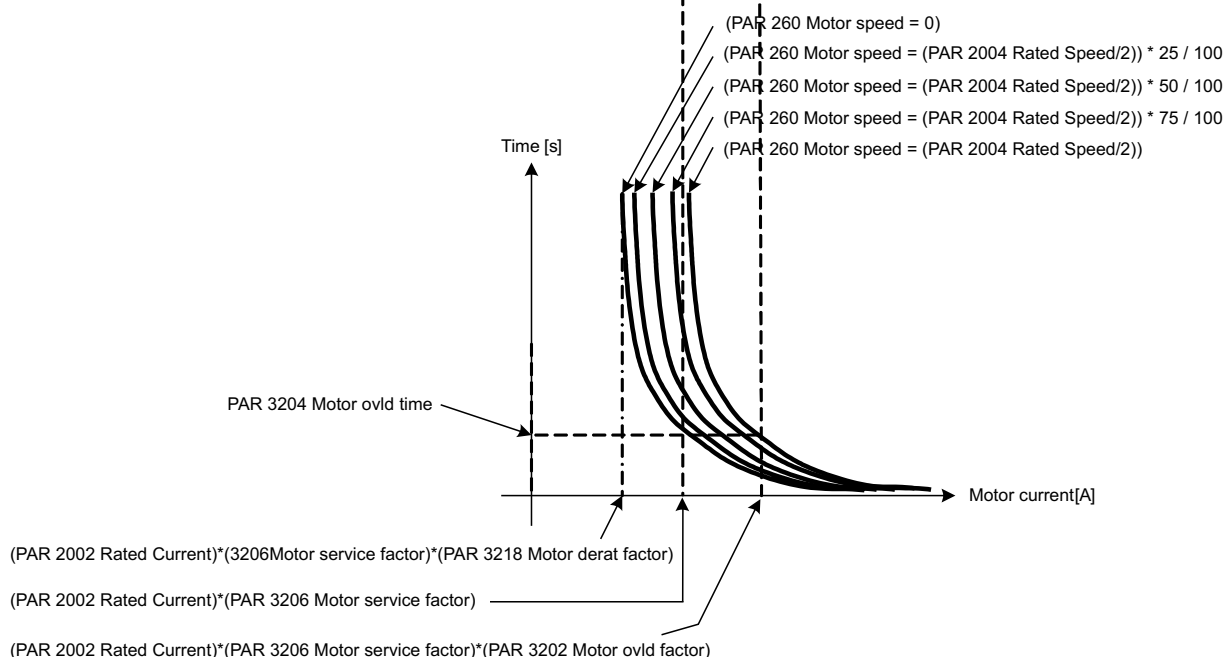
22.6 – FUNCTIONS/MOTOR OVERLOAD

The overload control function provides integrator logic to protect the motor against thermal overload. This protection presents the characteristic I^2t behaviour and is an emulation of the thermal relay of the motor controlled by the ADV drive. When the function is enabled, the value reached by the integrator is stored each time the drive is switched off. The saved value is restored each time the drive is switched on.

I2tm Overload time – PAR 3216 Motor Fan type = (1) Servo fan
I2tm Overload time - PAR 3216 Motor Fan type = (0) Auto fan - PAR 260 Motor speed > PAR 2004 Rated Speed



I2tm Overload time – PAR 3216 Motor Fan type = (1) Servo fan
I2tm Overload time - PAR 3216 Motor Fan type = (0) Auto fan - PAR 260 Motor speed > PAR 2004 Rated Speed



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.6.1	3200	Motor ovlid enable		BIT		0	0	1	ERW	FVS

Enabling of the motor overload control.

- 0** Disable
- 1** Enable

If set to **0** the MOTOR OVERLOAD function is disabled.

If set to **1** the MOTOR OVERLOAD function is enabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.6.2	3202	Motor ovid factor	perc	FLOAT		150.0	100.0	300.0	ERWS	FVS

Setting of the motor overload value. The value is expressed as a percentage of **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206).

The current obtained from **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206) * **Motor ovid factor** (PAR 3202) is the maximum current that can circulate in the motor.

If the MOTOR OVERLOAD function is enabled the drive automatically sets the torque current limit so that lout max. does not exceed this value. The MOTOR OVERLOAD function can be used to deliver current to the motor at the overload value for a time set in **Motor ovid time** (PAR 3204). After the set time, the MOTOR OVERLOAD function automatically sets the torque current limit so that lout max. does not exceed **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206).

If the value of parameter 3202 **Motor ovid factor** is 100 % the overload current of the Motor Overload function is equal to the continuous current of the Motor Overload function. In this case the drive behaves as if the overload cycle has been executed and so sets the torque current limit so that lout max is not more than the continuous current, i.e. **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.6.3	3204	Motor ovid time	s	FLOAT		30.0	10.0	300.0	ERWS	FVS

Setting of the motor overload duration in seconds.

With the MOTOR OVERLOAD function a current equal to the level of **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206) * **Motor ovid factor** (PAR 3202) is supplied to the motor for the time set in **Motor ovid time** (PAR 3204).

The MOTOR OVERLOAD protection intervention time depends on the level of current circulating in the motor, a current equal to the overload level is allowed for the time set in **Motor ovid time** a current at below the overload level is allowed for longer.

This alarm can be assigned to a programmable digital output (**Motor overload trip**).

The trip time depends on the motor current value, see figure on previous page.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.6.4	3206	Motor service factor	perc	FLOAT		100.0	25.0	200.0	ERWS	FVS

Setting of the motor service factor. The value is expressed as a percentage of **Rated current** (PAR 2002).

Rated current (PAR 2002) * **Motor service factor** (PAR 3206) is the point at which the integrator logic is enabled.

The current obtained from **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206) * **Motor ovid factor** (PAR 3202) is the maximum current that can circulate in the motor.

If the MOTOR OVERLOAD function is enabled the drive automatically sets the torque current limit so that lout max. does not exceed this value. The MOTOR OVERLOAD function can be used to deliver current to the motor at the overload value for a time set in **Motor ovid time** (PAR 3204). After the set time, the MOTOR OVERLOAD function automatically sets the torque current limit so that lout max. does not exceed **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.6.5	3216	Motor fan type		ENUM		Servo fan	0	1	ERW	F_S

This parameter is used to set the type of motor cooling system.

0 Auto fan

1 Servo fan

Auto fan indicates the presence of a fan unit mounted on the motor shaft that therefore turns at a speed proportional to the motor speed. Cooling is not very effective at low motor speeds.

Servo fan indicates the presence of an independent fan unit that therefore always runs at the rated speed. It ensures optimum cooling efficiency at all motor speeds.

When the current motor speed is below (PAR 2004 **Rated speed** / 2) and PAR 3216 **Motor fan type** = Auto fan; , the MOTOR OVERLOAD protection intervention time must be reduced as cooling is insufficient.

At below (PAR 2004 **Rated speed** / 2) the protection intervention time is reduced by reducing the direct current of the MOTOR OVERLOAD function.

When the motor speed is equal to (PAR 2004 **Rated speed** / 2) the direct current of the MOTOR OVERLOAD function is equal to PAR 2002 **Rated current** * PAR 3206 **Motor service factor**, , whereas below that limit it is modified following a linear pattern until PAR 2002 **Rated current** * 3206 **Motor service factor** * PAR 3218 **Motor derat factor** when the motor speed reaches zero.

The overload current of the MOTOR OVERLOAD function is obtained by PAR 2002 **Rated current** * 3206 **Motor service factor** * PAR 3202 **Motor ovoid factor** and is the maximum current that can circulate in the motor. If the MOTOR OVERLOAD function is enabled the drive automatically sets the torque current limit so that lout max. does not exceed this value.

With the MOTOR OVERLOAD function a current equal to the Overload level is supplied to the motor for the maximum time set in PAR 3204 **Motor ovoid time**, The slower the motor speed, the shorter the time allowed (see figure at beginning of chapter).

After the set time, the MOTOR OVERLOAD function automatically sets the torque current limit so that lout max. does not exceed the direct current of the MOTOR OVERLOAD function.

When the motor current speed exceeds (PAR 2004 **Rated speed** / 2) and PAR 3216 **Motor fan type** = Auto fan, the direct current is not reduced as cooling is sufficient.

When PAR 3216 **Motor fan type** = Servo fan, the direct current is not reduced as cooling is sufficient.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.6.6	3218	Motor derat factor	perc	FLOAT		50.0	0.0	100.0	ERWS	F_S

This parameter is used to set the derating factor. The value is expressed as a percentage of PAR 2002 **Rated current** * PAR 3206 **Motor service factor**.

When the current motor speed is below (PAR 2004 **Rated speed** / 2) and PAR 3216 **Motor fan type** = Auto fan, the protection intervention time must be reduced as cooling is insufficient.

At below (PAR 2004 **Rated speed** / 2) s the protection intervention time is reduced by reducing the direct current of the MOTOR OVERLOAD function.

When the motor speed is equal to (PAR 2004 **Rated speed** / 2)) the direct current of the MOTOR OVERLOAD function is equal to PAR 2002 **Rated current** * PAR 3206 **Motor service factor**, whereas below that limit it is modified following a linear pattern until PAR 2002 **Rated current** * PAR 3206 **Motor service factor** * PAR 3218 **Motor derat factor** when the motor speed reaches zero.

The overload current of the MOTOR OVERLOAD function is obtained by PAR 2002 **Rated current** * PAR 3206 **Motor service factor** * PAR 3202 **Motor ovoid factor** and is the maximum current that can circulate in the motor. If the MOTOR OVERLOAD function is enabled the drive automatically sets the torque current limit so that lout max. does not exceed this value.

With the MOTOR OVERLOAD function a current equal to the Overload level is supplied to the motor for the maximum time set in PAR 3204 **Motor ovoid time**, The slower the motor speed, the shorter the time allowed (see graphs).

After the set time, the MOTOR OVERLOAD function automatically sets the torque current limit so that lout max. does not exceed the direct current of the MOTOR OVERLOAD function.

When the motor current speed exceeds (PAR 2004 **Rated speed** / 2) and PAR 3216 **Motor fan type** = Auto fan, the direct current is not reduced as cooling is sufficient.

When PAR 3216 **Motor fan type** = Servo fan, the direct current is not reduced as cooling is sufficient.

If the value of parameter 3202 **Motor ovoid factor** is 100 % the overload current of the Motor Overload function is equal to the continuous current of the Motor Overload function. In this case the drive behaves as if the overload cycle has been executed and so sets the torque current limit so that lout max is not more than the continuous current, i.e. **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206) * **Motor derat factor** (PAR 3218).

We recommend setting parameter 3218 **Motor derat factor** to a value so that **Rated current** (PAR 2002) * **Motor service factor** (PAR 3206) * **Motor derat factor** (PAR 3218) produces a result that is more than the motor magnetisation current.

22.7 – FUNCTIONS/BRES OVERLOAD



Warning

Braking resistors may be subject to sudden overloads following failures.

Always protect resistors by using thermal protection devices.

These devices do not have to interrupt the circuit where the resistor is installed, but their auxiliary contact must interrupt the power supply of the drive power section. If the resistor requires the presence of a protection contact, this must be used together with the one belonging to the thermal protection device.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.1	3250	Bres control		BIT		0	0	1	ERWZS	FVS

Enabling of the overload control of the external braking resistor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.2	3252	Bres value	ohm	FLOAT		SIZE	5.0	1000.0	ERWS	FVS

Setting of the ohm value of the external braking resistor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.3	3254	Bres cont power	kW	FLOAT		SIZE	0.1	100.0	ERWS	FVS

Setting of the power that can be continuously dissipated by the external braking resistor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.4	3256	Bres overload factor		FLOAT		SIZE	1.5	10.0	ERWS	FVS

Setting of the external resistor overload factor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.5	3258	Bres overload time	s	FLOAT		SIZE	0.5	50.0	ERWS	FVS

Setting of the intervention time of the external braking resistor overload.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.6	3272	Bres enable src		LINK	16	6002	0	16384	ERW	FVS

Parameters IPA 3272 **Bres enable src** and IPA 3274 **Bres enable inv** manage enabling/disabling (by digital input) of the internal BU connected to a braking resistance with or without protective klickson.

The internal BU must be enabled with parameter IPA 3250 **Bres control**.

It can be used two ways:

- 1) If you use a resistance with klickson, the protection contact can be linked to a digital input by appropriately configuring IPA 3272 from selection list L_DIGSEL1. The digital input will enable the braking when the temperature of the resistance is below the protection threshold or disable it when the temperature exceeds the threshold.
- 2) If you use a resistance without klickson, you can use the state of an alarm such as (for example) [15] **Bres overload** to enable the braking unit when the alarm is inactive:
 - configure IPA 3272 **Bres enable src** = IPA 4708 **Alm dig out mon 1** (from selection list L_DIGSEL1),
 - set IPA 4700 **Alarm dig sel 1** = [15] **Bres overload**,
 - set IPA 3274 **Bres enable inv** = 1 to invert the logic state.

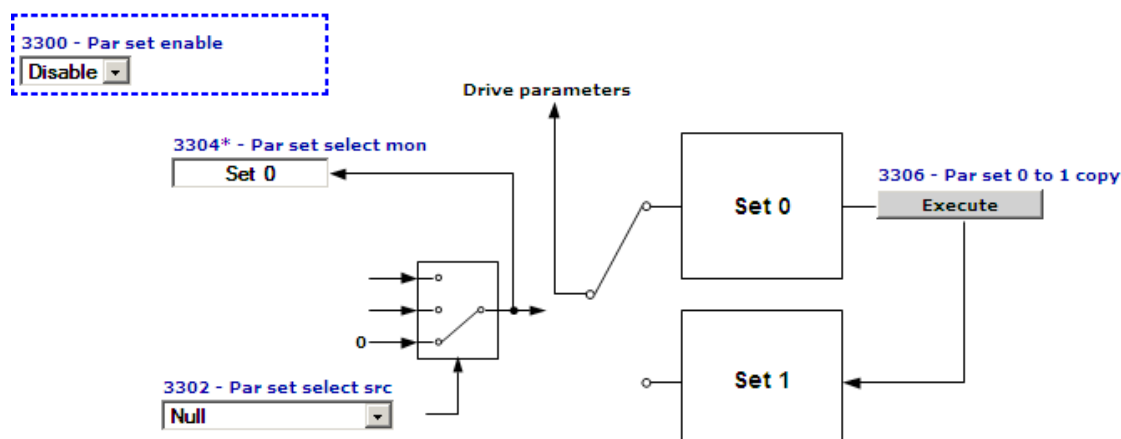
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.7.7	3274	Bres enable inv		BIT		0	0	1	ERW	FVS

Inverts the logic state of the BU enable command from IPA 3272 **Bres enable src**.

0 Off: inversion disabled

1 On: inversion enabled

22.8 – FUNCTIONS/DOUBLE PAR SET



Two independent sets of parameters can be stored in the ADV200 drive. These can be selected via the keypad or by using an external command.

This makes it possible to change all the drive parameters quickly and automatically according to the various operating requirements. For example, two motors with different characteristics can be controlled alternately.

MDPLC application parameters are not included in the two sets of parameters. This makes it possible to switch between all drive parameters in two separate groups, while having a single set of parameters for the application.

With the GF_eXpress configurator this function can be managed using the commands in the program toolbar.

R0|1 -> "read set 0/1"

This command is used to read set 0 (and store set 1 in a .gfe file) or vice versa, depending on which set is currently active

W0|1 -> "write set 0/1"

This command is used to load both sets of parameters to the drive

The toolbar commands **"Copy set 0"** and **"Copy set 1"** are used, after opening a .gfe file where the two sets have been stored, to load set 0 and set 1, respectively, to the parameter grid, without interacting with the drive. The previous contents of the parameter grid (which will not necessarily have coincided with either set 0 or set 1) are lost. Use this command to find out which values will actually be sent to the drive.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.8.1	3300	Par set enable		ENUM		Disable	0	1	ERW	FVS

Enabling of management of two parameter sets

0 Disable

1 Enable

When set to **0** only one parameter set is managed (the one used as the default set).

If set to **1** two separate parameter sets can be configured. These can be selected using a command signal on a digital input of the terminal strip.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.8.2	3302	Par set select src		LINK	16	6000	0	16384	ERWZ	FVS

Selection of the origin (source) of the signal to be used to select the parameter set. The terminal or digital command that can be associated with this function can be selected from among those available in the **"L_DIG-SEL2"** selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.8.3	3304	Par set select mon		ENUM	16	Set 0	0	0	ER	FVS

The parameter set currently in use is displayed.

0 Set 0

1 Set 1

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.8.4	3306	Par set 0 to 1 copy		BIT		0	0	1	ERW	FVS

Procedures for setting up and managing the double parameter set

Creating the second set:

This function copies parameter set 0 onto set 1. Before enabling management of the double parameter set, the first set should be programmed with the correct values.

When the first set is ready, the second can be activated as follows:

- 1 Activate management of the double parameter set by enabling parameter **3300 Par set enable**.
- 2 Copy set 0 onto set 1 using command **3306 Par set 0 to 1 copy**.
This creates an initial parameter base in set 1 to which changes can be made.
Save the parameters.
- 3 Activate set 1 using parameter **3302 Par set select src**.
To select set 1 manually, set this parameter to "One".
Otherwise select the desired source.
- 4 Modify the parameters in set 1 as necessary.
- 5 Save the parameters.

You can change the set being used by changing the source selected in parameter **3302 Par set select src**. This can only be changed with the drive disabled.

When the double parameter set is active, the number of the set being used is shown next to the number of each parameter on the keypad.

Modifying and saving parameters:

When the double parameter set is active, any parameters that need to be the same in the two sets must be modified in each set separately.

Parameters are only saved in the set that is active at the time. To save both sets, you must first save one and then select and save the other.

Note ! Any changes to the parameters regarding the "parameter sets", performed when enabled, will be lost at the next switching unless a **Par set 0 to 1 copy** command is sent. To save data permanently (even when the drive is switched off), send the **Save parameters** command (DRIVE CONFIG menu).

22.9 – FUNCTIONS/SPEED CAPTURE

This function allows the drive to capture a motor running due to inertia or driven by the load. The function is also enabled in case of an automatic restart after an alarm condition.

Main fields of application:

- Capturing a motor set in motion by the load (for example pump motors driven by the fluid)
- Capturing a motor connected directly to the power mains
- Capturing a motor running due to temporary disabling of the drive
- Capturing a motor that is running in the case of an automatic restart after an alarm

Note ! If the drive is enabled with the motor running and this function disabled, the drive could be blocked due to the intervention of the Overcurrent or Undercurrent protections

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.1	3350	Speed capture		ENUM		Disable	0	1	ERW	FV_

This parameter is used to enable the function to capture a motor that is running.

- 0 Disable
- 1 Alarm restart
- 2 Enable&restart

If set to **0** the capture running motor function is disabled. The output frequency starts from 0 and passes to the set reference value using the ramp. If the drive is enabled with the motor running and this function disabled, the drive could be disabled due to the intervention of the **Overcurrent** or **Undercurrent** protections.

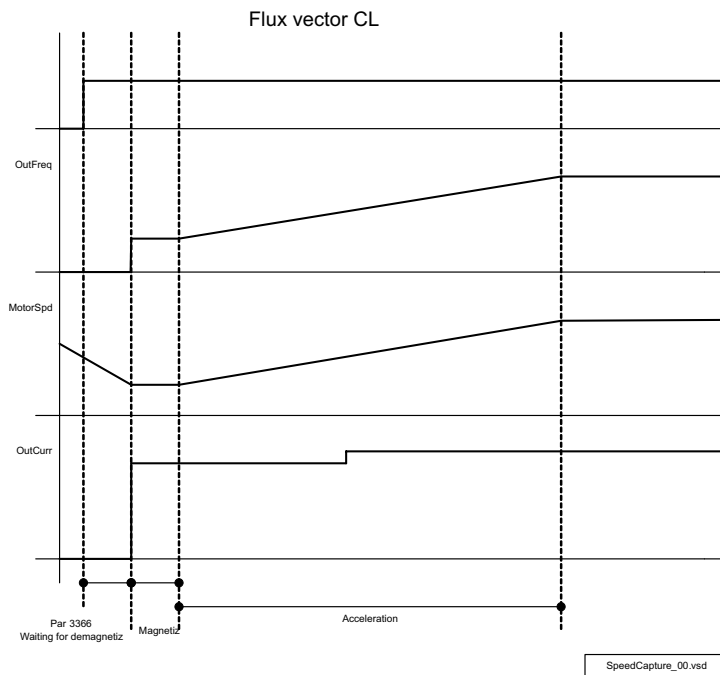
If set to **1** the capture running motor function is executed at restart each time an alarm is automatically reset.

If set to **2** the capture running motor function is executed each time the drive is enabled and each time an alarm is automatically reset.

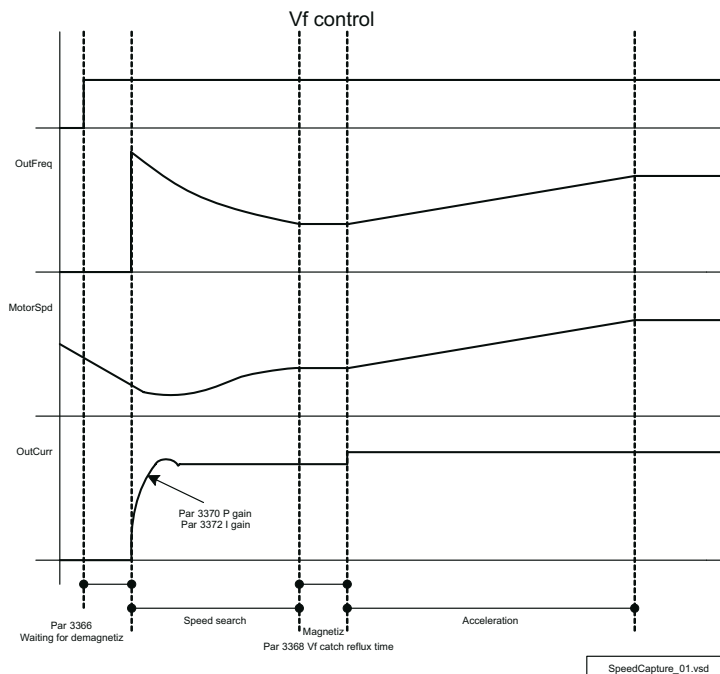
This function is available with **Regulation mode = Flux vector CL** (asynchronous and synchronous motors) or **V/f control** (asynchronous motors).

This function is not available with **Regulation mode = Flux vector OL**.

With **Regulation mode = Flux vector CL** the capture procedure consists of forcing the output frequency to the value measured by the encoder, and then bringing the motor speed to the reference value using the ramp.



With **Regulation mode = V/f control** the capture procedure consists of altering the inverter output frequency until the actual motor speed is detected, then increasing the motor speed to the reference value using the ramp. The procedure can take several seconds, depending on the type of load and parameter settings. If this function is enabled on a motor at speed = 0 and drive speed reference = 0, the motor might start running until the moment the drive detects the actual motor speed, after which the motor speed passes to the speed reference setting, i.e. 0. The initial value of the output frequency after restart and/or enable depends on the setting of parameters PAR 3350 **Speed capture**, PAR 3364 **Vf catch start freq**, PAR 3376 **Vf catch lastref dly**.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.2	3364	Vf catch start freq	Hz	FLOAT		(*)	-500.0	500.0	ERWZ	V

(*) Default: EU=50,0; USA = 60.0 (PAR 486 **Drive region**, 0 = EU; 1 = USA)

This parameter is used to configure the frequency at which the procedure to capture a motor that is running starts. This parameter is used in the case of PAR 3350 **Speed capture** is set to 2 (Enable&restart) and it is expired the time set in PRA 3376 **Vf catch lastref dly**.

This parameter must be set to a frequency that is higher than the frequency at which the motor is running at the beginning of the capture procedure. If the conditions are not always identical the maximum frequency or a few Hz below this must be set. The reference sign setting must be the same as the sign of the frequency at which the motor is running.

If a frequency value close to the actual frequency is set, the capture time is short. If there is a big difference between the frequency value setting and the actual frequency, the capture time is longer.

The recommended setting for this parameter is 0 if the function is enabled for use to capture a motor running due to a temporary disabling of the drive or to capture a motor running in the case of an automatic restart after an alarm; or in case of enabling after power-on or after prolonged periods of disabling, the motor speed is certainly 0.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.3	3366	Vf catch enable dly	ms	UINT16		CALCF	10	30000	ERWZ	V

This parameter is used to configure the time to wait for demagnetisation of the motor before executing the procedure to capture the motor that is running. The waiting time for demagnetisation is measured starting from the moment the drive detects that the conditions are OK to execute the capture procedure. This parameter is useful for automatic restarts after an alarm.

If the motor flux is not zero when the enable command is sent the drive might generate the **Overcurrent** alarm.

The value is pre-calculated by the drive according to the motor data entered. Large motors have a high rotor time constant and therefore require a long demagnetisation time.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.4	3368	Vf catch reflux time	s	FLOAT		CALCF	0.1	100.0	ERW	V

It is the time the inverter takes to ramp the output voltage from 0% to 100% during the magnetizing phase

Its value is automatically calculated by the inverter itself once the motor data (indicated in the nameplate of the motor) has been introduced. If the motor is magnetized too quickly, there is the risk the inverter trips due to high currents.

Usually the magnetizing time for a 5,5kW motor is about 600-800 ms . For a 630 kW motor it is about 9-10 seconds

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.5	3370	Vf catch Kp gain	perc	FLOAT		CALCF	0.0	100.0	ERW	V

This is the proportional gain of the PI regulator which performs the searching of the synchronism frequency by monitoring the active component of motor current

Its value is calculated by the drive during the commissioning phase. The correct motor data are needed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.6	3372	Vf catch Ti time	ms	UINT16		CALCI	10	10000	ERW	V

This is the integral time of the PI regulator which performs the searching of the synchronism frequency by monitoring the active component of the motor current.

Its value is calculated by the drive during the commissioning phase. The correct motor data are needed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.7	3376	Vf catch lastref dly	ms	UINT16		0	0	30000	ERWZ	V

This parameter is needed only when PAR 3350 = 2 Enable&Restart.

This parameter is used to set the time within which the drive must be enabled in order to start the capture procedure at the output frequency present before disabling the drive. If the time that elapses from the moment the drive is disabled exceeds the time set in this parameter, the capture procedure starts from the frequency set in parameter **3364 Vf catch start freq**. This parameter value has to be set > IPA3366 value to start the capture procedure at the output frequency present before disabling the drive.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.8	3388	Vf catch search volt	perc	UINT16		10	1	20	ERW	V

It defines the reduction level applied to the output voltage during the speed searching phase. Typical value are in the range 5 ... 15% . Low values allows to perform a smother synchronization but with longer search time.

High values allows to perform a faster synchronization but with unwanted braking effects and higher current. The catch on fly may fail if the search voltage is too low.

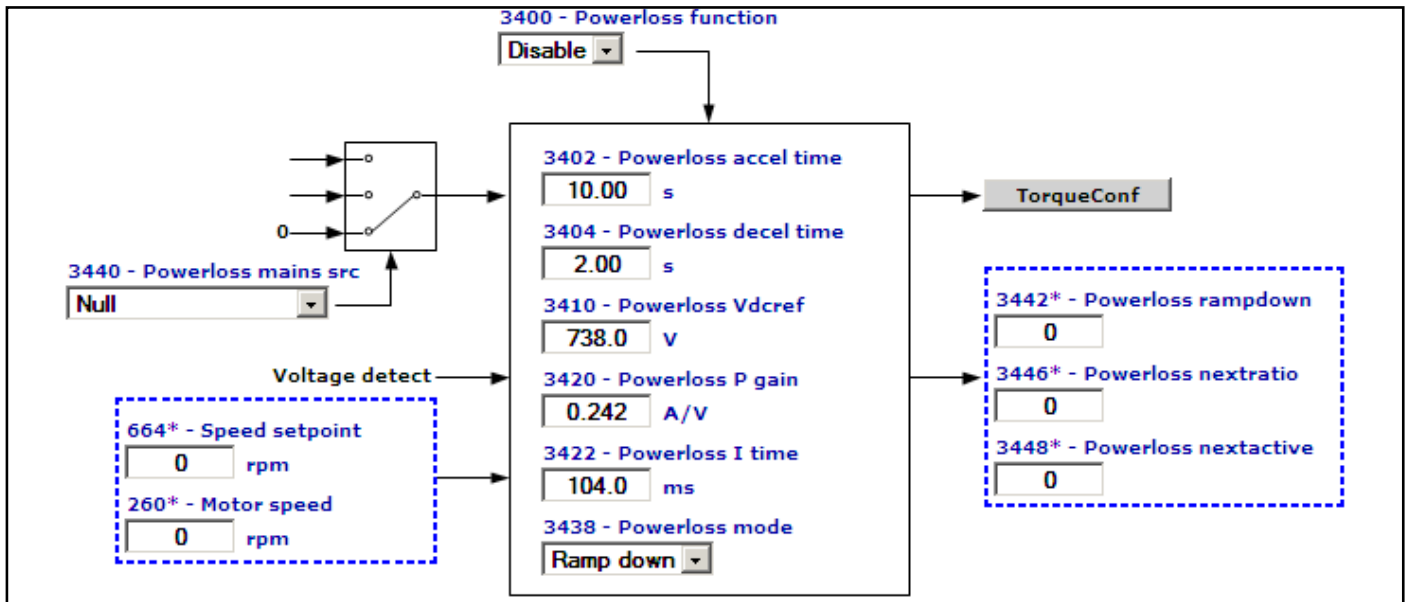
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.9	3390	Vf catch search curr	perc	FLOAT		0.6	-1.0	10.0	ERWS	V

In the speed searching phase the drive compares the active component of the motor current with this threshold to detect the achievement of the motor speed. It is expressed as percentage of the rated current . Its default value is equal to 0.5%. A higher value reduces the search time of the motor speed but the braking effect becomes more relevant during the operation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.9.10	3392	lactive filter	ms	FLOAT		20.0	1.0	150.0	ERWZ	V

This parameter defines the time constant of filter applied to the active component of the motor current.

22.10 – FUNCTIONS/POWER LOSS



This function controls a loss of power or temporary mains failure.

When the function is enabled the system stops with the controlled ramp; the power regenerated by the load sustains the DC link power supply so that the motor speed can be controlled. The speed of the motor is controlled for as long as power can be recovered (motor speed almost zero but not zero), after which the **Undervoltage** alarm is generated and the motor performs an uncontrolled stop due to inertia.

The function is only effective with loads that accumulate sufficient energy (typically loads with a high moment of inertia and which the moment the power loss occurs have a speed of rotation not close to zero). The function cannot be used for passive loads.

The function can only be used with **Regulation mode = Flux vector CL** (asynchronous and synchronous motors) and **Regulation mode = V/f control** (asynchronous motors).

The Powerloss function is enabled when the DC link voltage falls below a threshold configured internally as a function of the mains voltage at a value that is higher than the **Undervoltage** threshold. When the function is enabled the drive controls a stop with a user-definable deceleration ramp. In this phase the current limit is controlled by a regulator on the DC link voltage and the setpoint is a threshold configured internally as a function of the mains voltage at a value below the **Overvoltage** threshold.

The regulator envisages two setting parameters (proportional and integral) calculated in advance by the drive as a function of the size of the motor and plate data. If the regulator acts on the current limit the motor speed does not follow the set deceleration ramp. The function continues for as long as power can be recovered, after which the **Undervoltage** alarm is generated. If the mains supply is restored during the deceleration ramp phase, the user can configure how the drive should behave. The following options are available: continue in any case until reaching zero speed or stop the deceleration ramp and pass to the set reference.

The drive does not automatically recognise the fact that the mains supply has been restored. This information must be supplied from the outside via the **Powerloss mains src** digital input.

The presence of the braking unit prevents the intervention of the **Overvoltage** alarm and the function has the advantage of being able to stop the motor while guaranteeing the set time.

As the setpoint of the Powerloss function regulator is higher than the brake activation threshold, it is not enabled and the current limit is not altered to allow compliance with the set deceleration ramp time. The intervention of the braking unit dissipates the energy of the motor in the resistor, reducing the amount of power available to sustain the DC link and the time available to control stopping of the motor. The presence of the braking unit could mean that the speed of the motor from which no power can be recovered is higher than that with no braking unit. The function can be used on machines with a single drive as well as on machines with several drives, the speeds of which must always be synchronised.

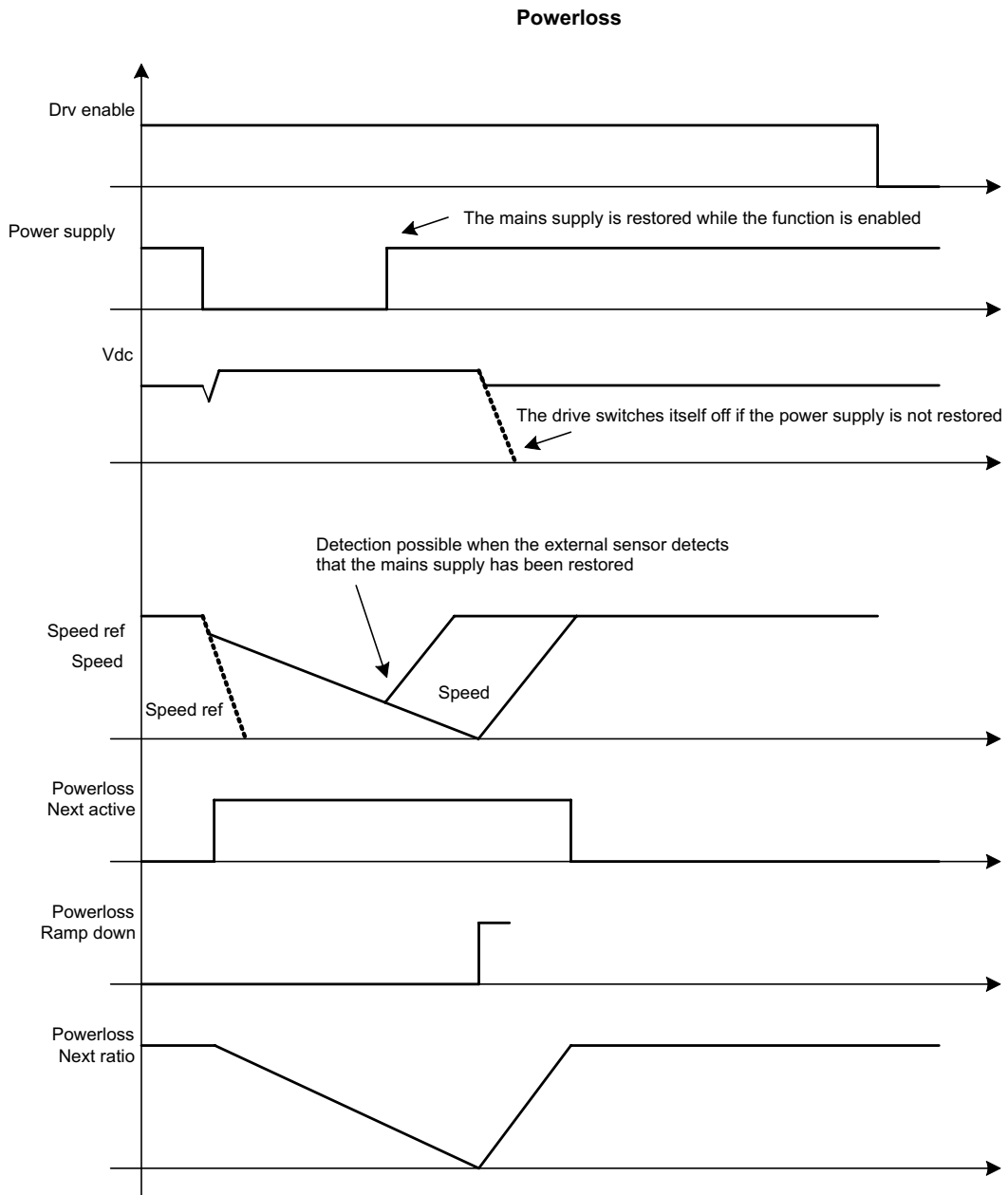
For machines with a single drive, enabling the Powerloss function is sufficient.

For machines with several drives, the DC links must be connected: the Powerloss function must only be enabled on the drive identified as the master and not on the slaves. The master drive is normally the one that controls the load with the highest inertia. The master drive sends the **Powerloss nexratio** signal with the ratio

between the motor speed and the speed reference. Line synchronisation can be achieved by connecting the **Powerloss nextratio** output of the master to the **Speed ratio src** input (selection list L_VREF) of the slave drives. The master => slave connection can be achieved via analog signals or fieldbus.

To ensure correct operation of the Powerloss function, the following alarms must be configured as described below:
 Since the speed reference and current limit are controlled internally by the Powerloss function, a difference could occur between the speed reference and motor speed with subsequent activation of the **Perd Riferim** alarm: to avoid this, set Par **4552 SpdRefLoss activity = Ignore**

During the power failure, the power supply phase loss detection system might not work properly with subsequent activation of the **Phaseloss** alarm: to avoid this, set Par **4660 PhLoss activity=Ignore**.



PowerLoss_01.vsd

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.1	3400	Powerloss function		ENUM		Disable	0	1	ERWZ	F__

This parameter is used to enable the Powerloss function.

- 0** Disable
- 1** Enable

If set to **0** the Powerloss function is disabled. The Undervoltage alarm is generated in the event of a power failure.

If set to **1** the Powerloss function is enabled. In case of a power failure the function is enabled to try to control the motor speed and prevent the intervention of the **Undervoltage** alarm.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.2	3402	Powerloss accel time	s	FLOAT		10.0	0.01	100.0	ERW	F__

Setting of the acceleration time used in the Powerloss operating mode. The acceleration ramp time is used when **Powerloss mode = Restart** has been selected and must be adjusted to suit machine requirements.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.3	3404	Powerloss decel time	s	FLOAT		2.0	0.01	100.0	ERW	F__

Setting of the deceleration time used during Powerloss operating mode.

The deceleration ramp time must be short enough (in case of low speeds) to allow the drive to enter regeneration mode quickly, otherwise the **Undervoltage** alarm is generated. If the deceleration ramp time setting is too short, when the drive enters regeneration mode it might not be able to control the DC link voltage and the **Overvoltage** alarm would be generated.

Longer deceleration times are necessary at high motor speeds to prevent the **Overvoltage** alarm from being generated.

This parameter must be adjusted so as to reach a compromise between low speed and high speed motor operation.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.4	3410	Powerloss Vdcref	V	FLOAT		CALCF	0.0	CALCF	ERWZS	FV__

Setting of the voltage control limit on the DC-link during a controlled stop with loss of supply voltage. The maximum value that can be set is the drive overvoltage limit.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.5	3420	Powerloss P gain	A/V	FLOAT		CALCF	0	100.000	ERWS	F__

Setting of the proportional gain during the Powerloss function.

Increase in case of **Overvoltage** error; the **Undervoltage** alarm can also be prevented by increasing the deceleration time.

Increase if the DC link voltage is set to a value other than the setpoint.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.6	3422	Powerloss I gain	ms	FLOAT		CALCF	1.0	1000.0	ERWS	F__

Setting of the integral gain during the Powerloss function.

Reduce if the DC link voltage is set to a value other than the setpoint.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.7	3438	Powerloss mode		ENUM		Ramp down	0	1	ERWZ	F__

This parameter is used to configure the behaviour of the Powerloss function when the mains supply is restored.

It is possible to set whether the drive should continue at zero speed or return to the setpoint when the mains supply is restored. The drive does not automatically recognise the fact that the mains supply has been restored. This information must be supplied from the outside via the **Powerloss mains src** digital input.

- 0 Ramp down
- 1 Restart

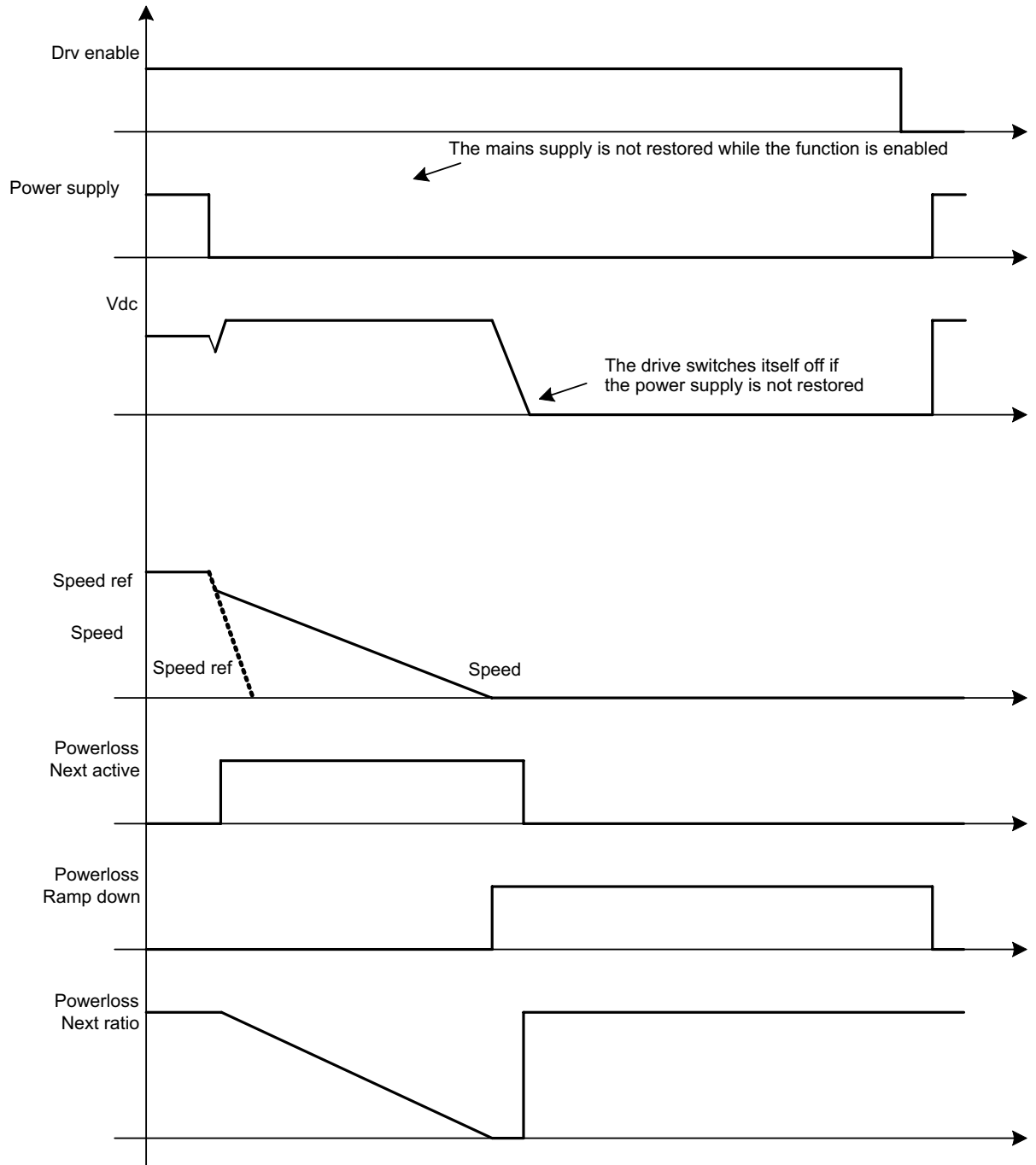
Example 1) End of ramp and mains supply not restored

The drive controls a deceleration with the ramp set in **Powerloss decel time**.

The drive automatically controls the DC link voltage and prevents the **Overvoltage** alarm.

If the mains supply is not restored close to a speed of zero, when there is insufficient regenerated power, the **Undervoltage** alarm is generated and the drive may switch itself off.

Ramp down and mains supply not restored



PowerLoss_02.vsd

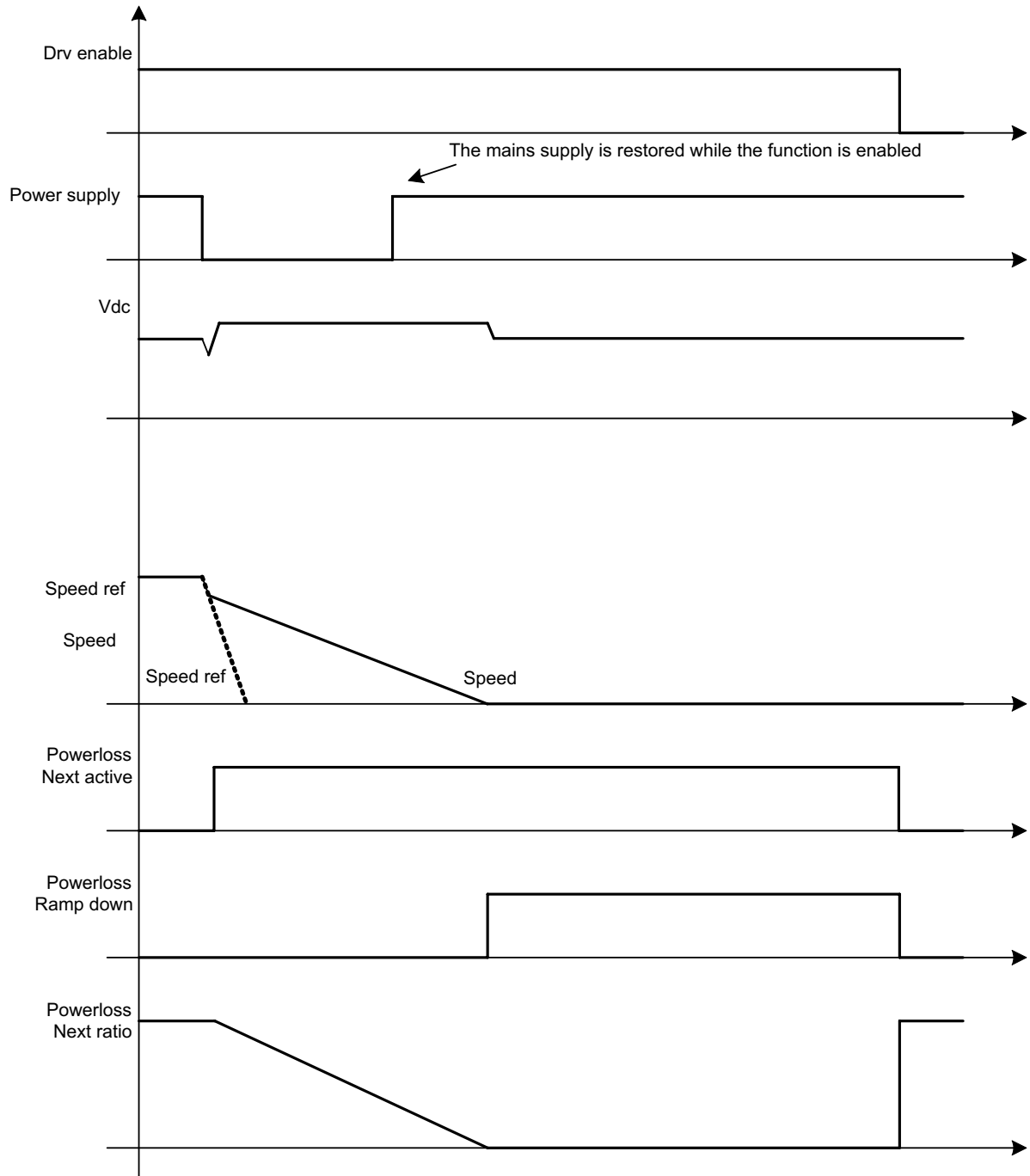
Example 2) End of ramp and mains supply restored

The drive controls a deceleration with the ramp set in **Powerloss decel time**.

The drive automatically controls the DC link voltage and prevents the **Overvoltage** alarm.

If the mains supply is restored and the **Mains voltage OK** signal is applied, the drive passes to zero speed and remains enabled at zero speed. To restart disable and enable the drive.

Ramp down and mains supply restored



PowerLoss_03.vsd

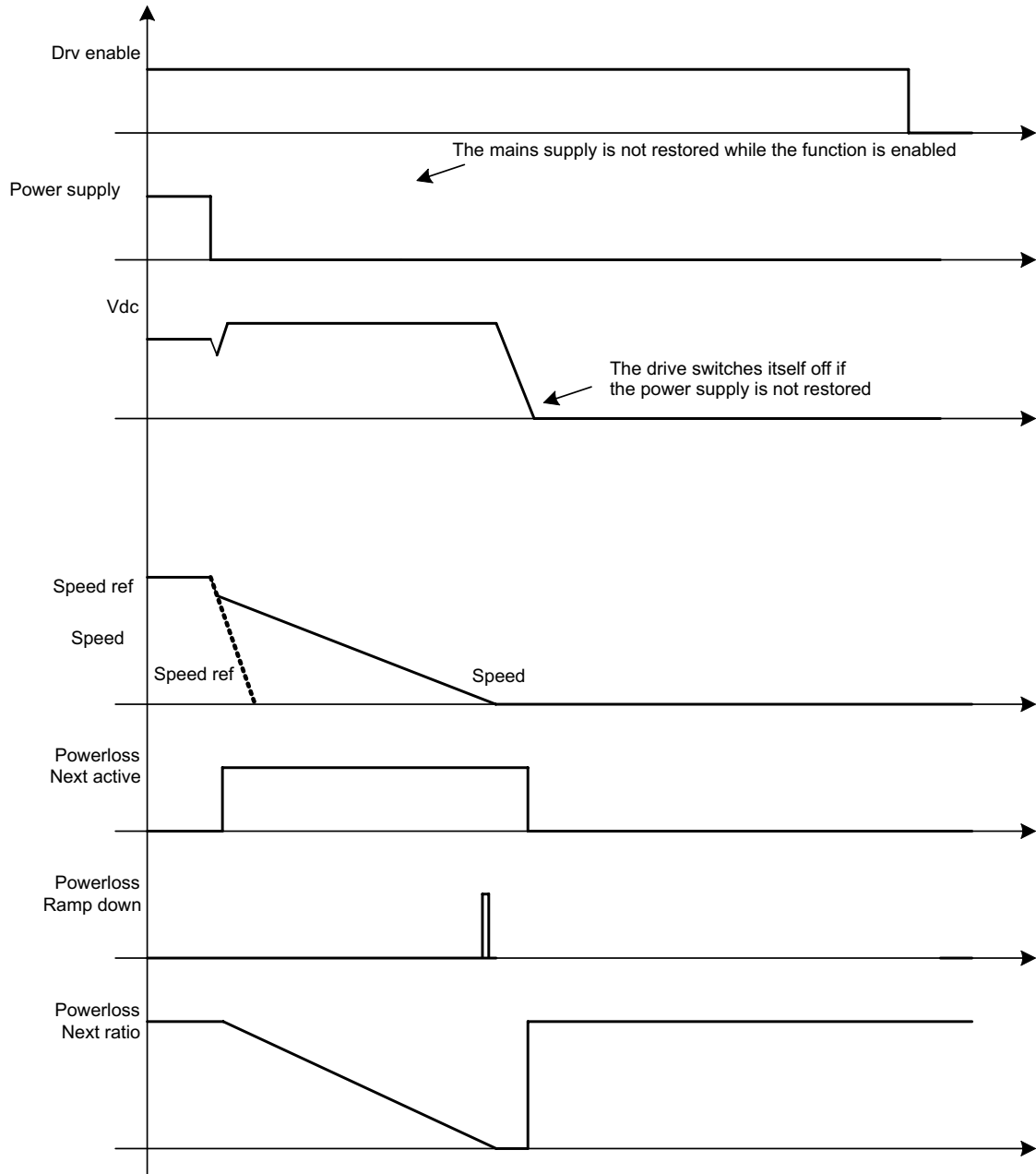
Example 3) Restart and mains supply not restored

The drive controls a deceleration with the ramp set in **Powerloss decel time**.

The drive automatically controls the DC link voltage and prevents the **Overvoltage** alarm.

If the mains supply is not restored close to a speed of zero, when there is insufficient regenerated power, the **Undervoltage** alarm is generated and the drive may switch itself off.

Restart and mains supply not restored



PowerLoss_04.vsd

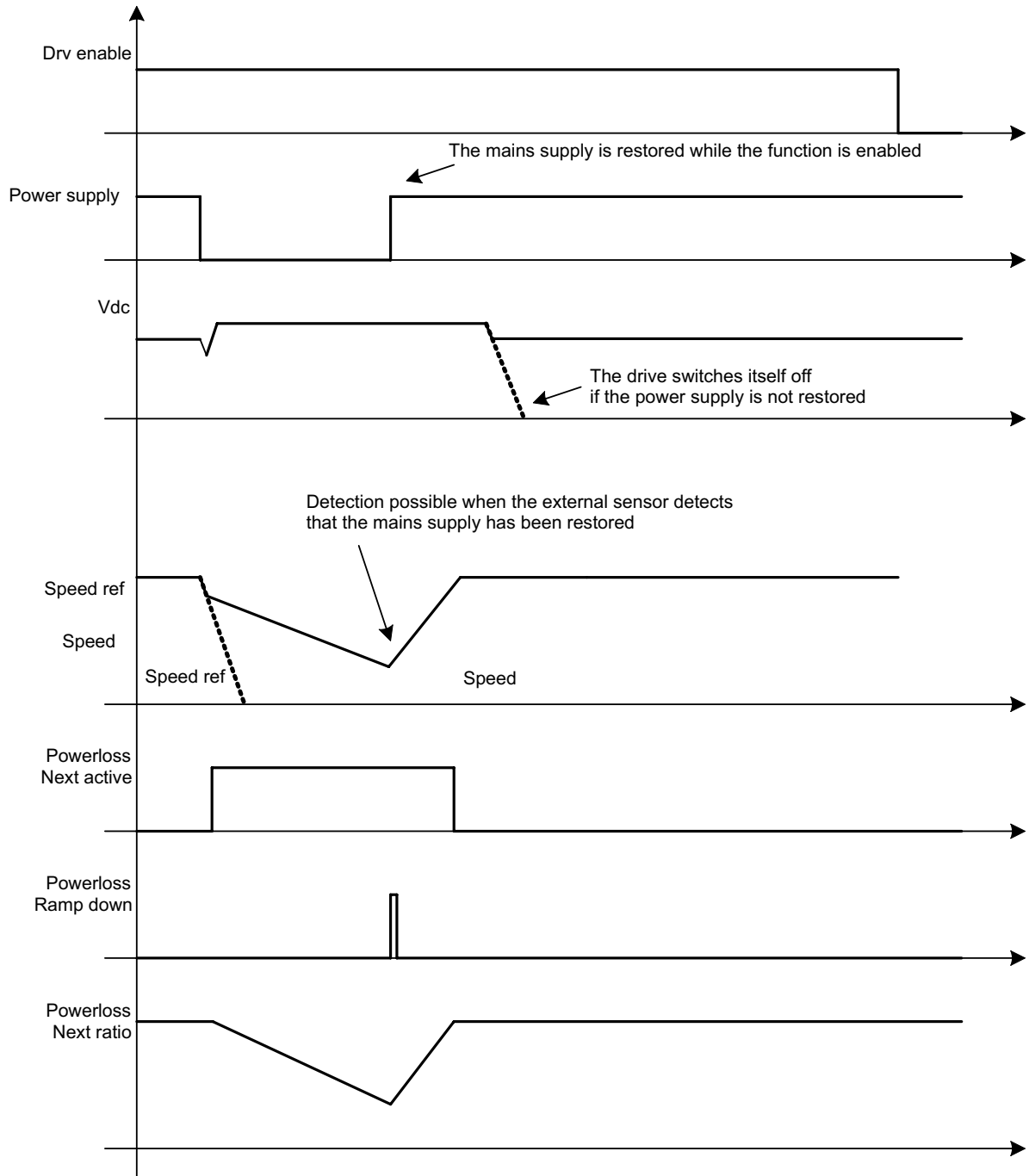
Example 4) Restart and mains supply restored

The drive controls a deceleration with the ramp set in **Powerloss decel time**.

The drive automatically controls the DC link voltage and prevents the **Overvoltage** alarm.

If the mains supply is restored and the **Mains voltage OK** signal is applied, the drive immediately stops the deceleration ramp and executes the acceleration ramp set in **Powerloss accel time** to pass to the set reference.

Restart and mains supply restored



PowerLoss_05.vsd

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.10.8	3440	Powerloss mains src		LINK	16	6000	0	16384	ERWZ	F__

This parameter is used to select the origin (source) of the **Mains voltage OK** signal. The signal to be associated with this function can be selected from the "L_DIGSEL2" selection list.

If the signal is not enabled it means the power supply is not present (**Mains voltage not OK**), whereas if the signal is enabled it means the power supply is present (**Mains voltage OK**).

In the default condition the origin of the **Powerloss mains src** signal is **Zero**.

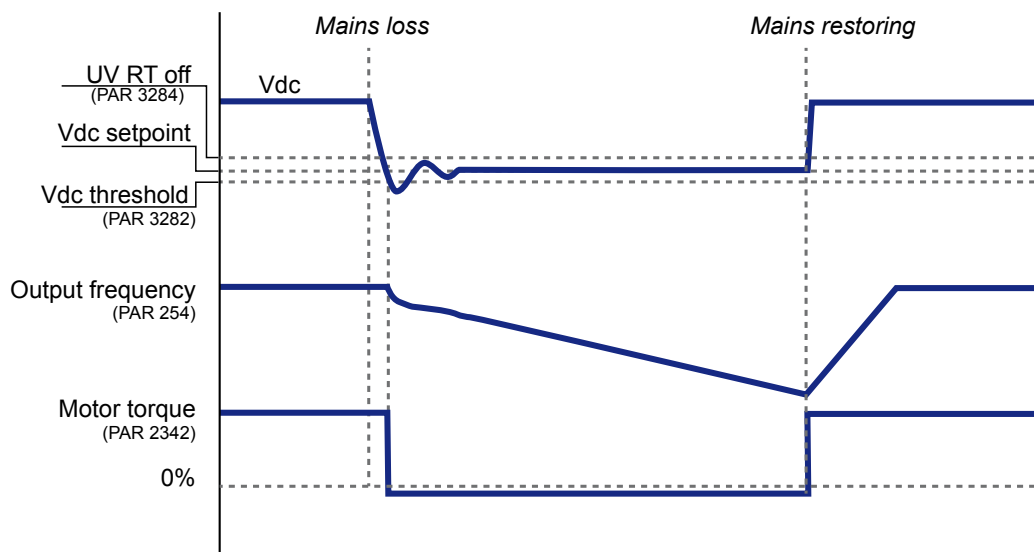
The user must connect an external sensor to inform the drive of the mains supply status.

If the function is configured as **Powerloss mode = Restart**, when the **Mains voltage OK** signal is enabled the drive stops the deceleration ramp and passes to the set reference.

For machines with several drives the external sensor signal must only be connected to the master drive.

22.11 - FUNCTIONS/UV RIDE THROUGH

In case mains voltage dip, the UV Ride-Through function (available on V/f mode only) operates by the way to recover the kinetic energy of the load into the DC link of the drive. The DC link is kept at a sustainable level as long as possible. In case the mains voltage is restored, the drive will get back to its normal operation according to PAR 3286 setting.



After an input power loss (*Mains loss*), the DC link voltage (*Vdc*) drops. When the DC voltage gets below the *Vdc threshold*, the drive decreases the speed reference.

The torque of the motor change its sign moving from positive to slightly negative (generator) recovering the kinetic energy into the DC link.

The UV Ride-Through controller decreases the output frequency as needed to keep the DC link voltage at an appropriate level (*Vdc setpoint*).

When the mains voltage is restored to its rated value, the DC link voltage rise up over the *Vdc setpoint* and the drive output frequency returns to follow the speed reference.

Mains voltage restore can be identified automatically or by external digital signal.

When the mains voltage is restored to its rated value, the drive recognizes the situation and the output frequency returns to follow the speed reference using the acceleration time as for the customer setting.

During the Ride-Through operation, the drive detects a "Warning" condition (without opening the Drive OK relay).

Otherwise if the mains voltage is not restored, the controller further decreases the drive output frequency till the motor stops. At this point the drive detect an "**Undervoltage**" alarm opening the Drive OK relay.

It is possible to set a UV RT time out. In case the mains voltage is not restored within this time, the function stops to control the DC link voltage and the drive detect an "**Undervoltage**" alarm opening the Drive OK relay.

The UV RT controller decreases the speed reference with a rate that depends on the inertia, friction and load with the goal to keep the DC link level at the *Vdc setpoint*.

According to this rate, the longer is the time of power loss, the greater is the decrease of speed.

This behavior may eventually negatively affect the material production.

To optimize the function, it is recommended to change the drive's minimum operating voltage setting from the default value to the minimum value (see PAR 450 **Undervoltage**, 4 – DRIVE CONFIG menu).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.1	3280	UV RT enable		ENUM		Disable	0	1	ERW	_V_

This parameter enable the UV RIDE THROUGH function.

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.2	3282	UV RT on	V	FLOAT		CALCF	0.0	0.0	ERWS	_V_

This parameter defines the value of the DC link voltage (*V_{dc} threshold* on figure) below which the UV Ride Through function starts. The default is $V_{ON} = (\sqrt{2} \times V_{mains}) \times 0.83$.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.3	3284	UV RT off	V	FLOAT		CALCF	0.0	0.0	ERWS	_V_

This parameter defines the value of the DC Link over which the mains voltage is considered restored. Above this value the drive stops managing the output frequency in order to maintain the value of the DC Link to *V_{dc} setpoint* and restores the previous value before the power loss.

The default is $V_{OFF} = (\sqrt{2} \times V_{mains}) \times 0.92$.

The *V_{dc} setpoint* value is calculated as $(PAR\ 3282 + PAR\ 3284) / 2$ (see figure).

This parameter works IPA when IPA 3286 **UV RT restore** is set to (0) Auto.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.4	3290	UV RT feed fwd		FLOAT		CALCF	0	20	ERW	_V_

During the initial phase of the UV RT operation, this parameter allows to prevent the Undervoltage alarm by braking the motor with the purpose to increase DC link voltage.

When the DC link voltage drops below *V_{dc} threshold*, a frequency step reduction is applied, according to the result of the following formula: $(PAR\ 3290 + 1) \times S$, where:

- S is the asynchronous motor slip value
- PAR 3290 is automatically initialized according to the nameplate data of asynchronous motor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.5	3292	UV RT timeout	s	FLOAT		0	0.0	120	ERWS	_V_

This parameter defines the time between the interruption of the output frequency reduction and the generation of the **Undervoltage** alarm in case the mains voltage is not restored ($V_{dc} < PAR\ 3284\ \text{UV RT off}$).

The behavior of the **Undervoltage** alarm generated in this case is different compared to the normal Undervoltage alarm. In this case the alarm stops when the DC link exceeds the value of PAR 3284 **UV RT off**.

If the parameter PAR 4640 **UnderV restart** = (1) Enable, when the timeout expires **UV Wng&Restart** signal is generated, in the same mode of the management of a normal undervoltage alarm. If the undervoltage alarm condition ends within the time specified in the parameter PAR 4642 **UnderV restart time**, modulation is reactivated.

If the parameter value is zero no timeout is used.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.6	3294	UV RT Kp	Hz/V	FLOAT		CALCF	0.0	0.0	ERWS	_V_
22.11.7	3296	UV RT Ti	ms	FLOAT		CALCF	0.0	0.0	ERWS	_V_

These parameters are the proportional and integral gains of the PI regulator that control the output frequency in order to prevent that the drive goes in **Undervoltage**. The PI input is the difference between *V_{dc} setpoint* and the value of DC link and generates the frequency reference. The parameter values are automatically calculated according to the motor data.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.8	3276	UV RT ext restor src		LINK	16	6000	0	16384	ERWZ	_V_
				L_DIGSEL2						

This parameter can be used to select the origin (source) of the **UV RT restore** (PAR 3286) signal.

The signal to be associated with this function can be selected from the “L_DIGSEL2” selection list. It could be used only if PAR 3286 **UV RT restore** = (1) External.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.9	3286	UV RT restore		ENUM		Auto	0	1	ERW	_V_

This parameter defines the detection mode of the mains voltage restore:

- 0 Auto** the drive makes a self-detection of voltage restore based on the value of the actual DC link voltage, that has to be greater than PAR 3284 **UV RT off**.
- 1 External** detection mode of voltage restore from external digital signal, see PAR 3276.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.10	3288	UV RT ext restor dly	ms	UINT16		80	0	65535	ERW	_V_

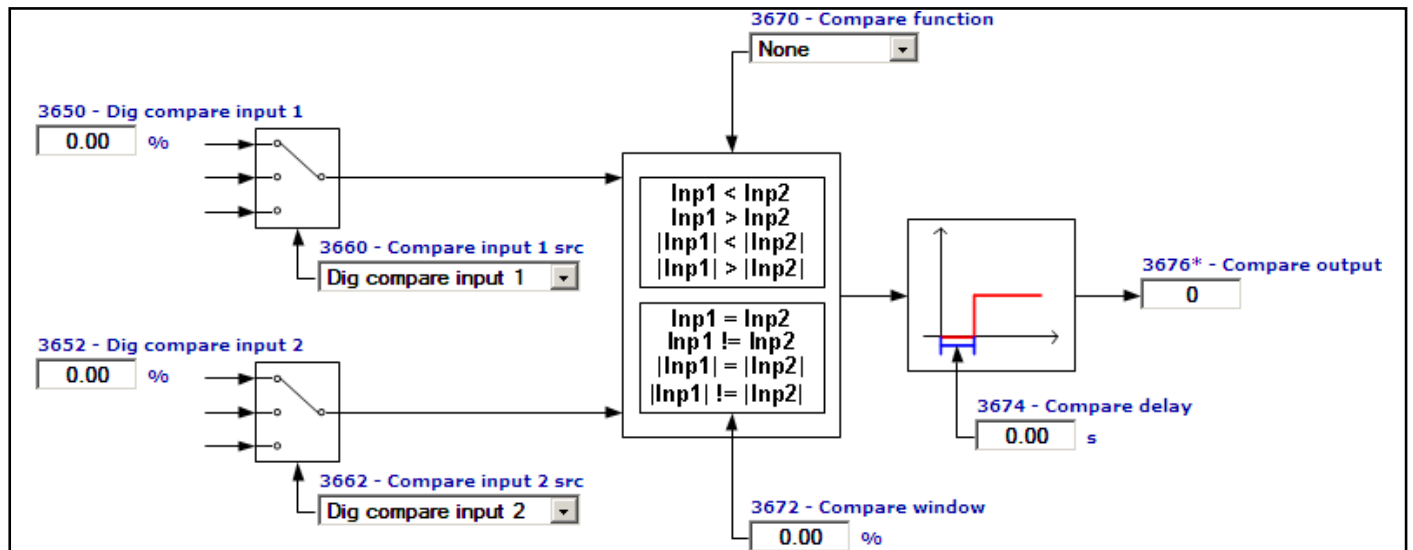
The response action to the external voltage restore signaling can be delayed by the value defined in this parameter. It can be used to compensate the closing delay of a contactor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11.11	3312	UV RT state		ENUM	16	Not active	0	1	ER	_V_

- 0 Not active**
- 1 Active**

Monitor of the state of UV RT function, also available for digital output selection list.

22.12 – FUNCTIONS/COMPARE



This function allows the comparison among two signals or values.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.1	3650	Dig compare input 1	perc	FLOAT	32	0.0	-100.0	100.0	ERW	FVS

Setting of the digital value of the first element of comparison.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.2	3652	Dig compare input 2	perc	FLOAT	32	0.0	-100.0	100.0	ERW	FVS

Setting of the digital value of the second element of comparison.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.3	3660	Compare input 1 src		LINK	32	3650	0	16384	ERW	FVS

Selection of the origin (source) of the signal to be used as the first term of comparison. The values that can be selected in the compare function are listed in the “**L_CMP**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.4	3662	Compare input 2 src		LINK	32	3652	0	16384	ERW	FVS

Selection of the origin (source) of the signal to be used as the second term of comparison. The values that can be selected in the compare function are listed in the “**L_CMP**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.5	3670	Compare function		ENUM		None	0	8	ERW	FVS

Setting of the compare function between **Compare input 2** and **Compare input 1** to enable **Compare output** PAR 3676.

- 0 None
- 1 Inp1=Inp2
- 2 Inp1!=Inp2
- 3 Inp1<Inp2
- 4 Inp1>Inp2
- 5 |Inp1|=|Inp2|
- 6 |Inp1|!=|Inp2|
- 7 |Inp1|<|Inp2|
- 8 |Inp1|>|Inp2|

If set to **0** the comparator is not enabled

If set to **1** the comparator output is enabled when the value of **Compare digital inp 1** is inside the window resulting from the value of **Compare digital inp 2** $\pm$ the tolerance set via the **Comparator Window**.

If set to **2** the comparator output is enabled when the value of **Compare digital inp 1** is not inside the window resulting from the value of **Compare digital inp 2** $\pm$ the tolerance set via the **Comparator Window**.

If set to **3** the comparator output is enabled when **Compare input 1** is less than **Compare input 2**.

If set to **4** the comparator output is enabled when **Compare input 1** is greater than **Compare input 2**.

If set to **5** the comparator output is enabled when the value of **Compare digital inp 1** is inside the window resulting from the absolute value of **Compare digital inp 2** $\pm$ the tolerance set via the **Comparator Window**.

If set to **6** the comparator output is enabled when the absolute value of **Compare digital inp 1** is not inside the window resulting from the absolute value of **Compare digital inp 2** $\pm$ the tolerance set via the **Comparator Window**.

If set to **7** the comparator output is enabled when the absolute value of **Compare digital inp 1** is less than the absolute value of **Compare digital inp 2**.

If set to **8** the comparator output is enabled when the absolute value of **Digital compar inp1** is more than the absolute value of **Digital compar inp2**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.6	3672	Compare window	perc	FLOAT		0.0	0.0	100.0	ERW	FVS

Setting of the tolerance window for comparing the **Compare input 1** and **Compare input 2** signals.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.7	3674	Compare delay	s	FLOAT		0.0	0.0	30.0	ERW	FVS

Setting of the delay for signalling the result of the comparison.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.12.8	3676	Compare output		BIT	16	0	0	1	ER	FVS

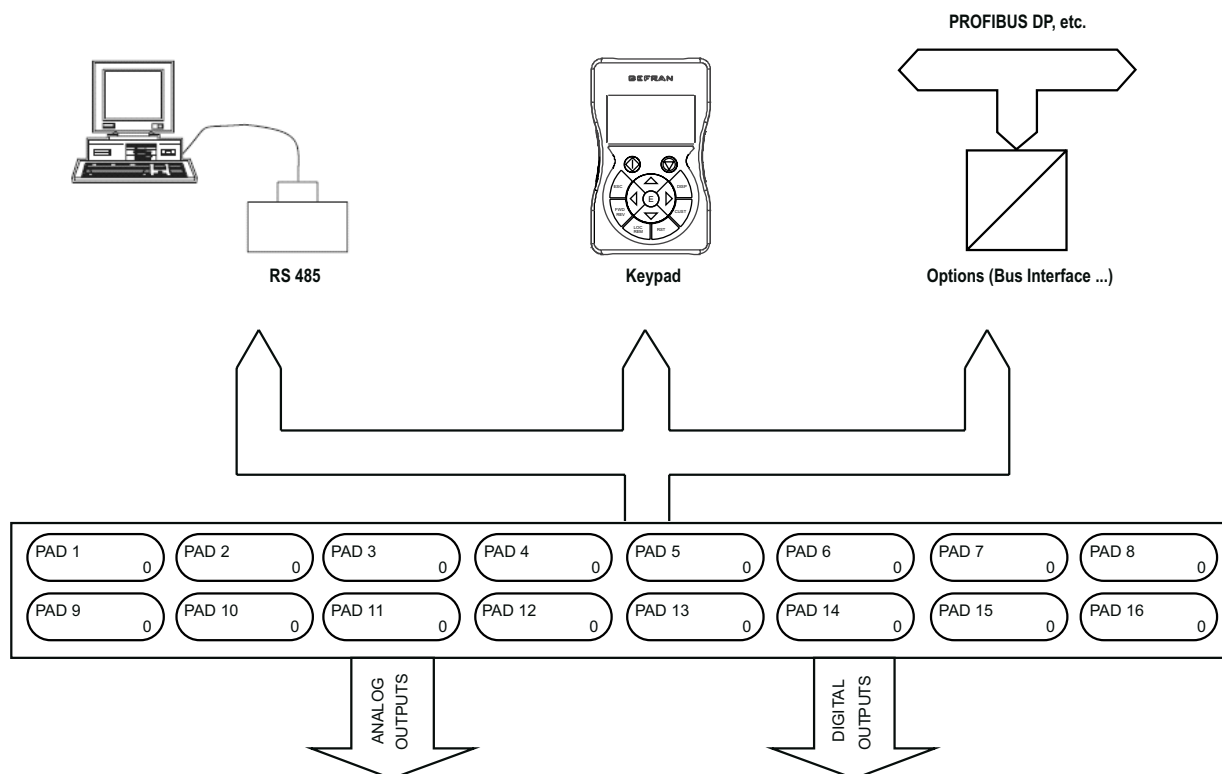
The status of the comparator output is displayed:

- 0** The result of the set comparison is negative
- 1** The result of the set comparison is positive

22.13 – FUNCTIONS/PADS

The general variables are used to exchange data between the various components of a Bus system. They are similar to the variables of a PLC. The basic structure of the system is illustrated below. Pads can be used, for example, to send information from a fieldbus to an optional card. All Pads can be read and written.

The Pads can also be used to exchange data with an MDPic application installed in the drive. See the MDPic manual for more details.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.13.1	3700	Pad 1		INT32	32	0	0	0	ERW	FVS
22.13.2	3702	Pad 2		INT32	32	0	0	0	ERW	FVS
22.13.3	3704	Pad 3		INT32	32	0	0	0	ERW	FVS
22.13.4	3706	Pad 4		INT32	32	0	0	0	ERW	FVS
22.13.5	3708	Pad 5		INT32	32	0	0	0	ERW	FVS
22.13.6	3710	Pad 6		INT32	32	0	0	0	ERW	FVS
22.13.7	3712	Pad 7		INT32	32	0	0	0	ERW	FVS
22.13.8	3714	Pad 8		INT32	32	0	0	0	ERW	FVS
22.13.9	3716	Pad 9		INT32	32	0	0	0	ERW	FVS
22.13.10	3718	Pad 10		INT32	32	0	0	0	ERW	FVS
22.13.11	3720	Pad 11		INT32	32	0	0	0	ERW	FVS
22.13.12	3722	Pad 12		INT32	32	0	0	0	ERW	FVS
22.13.13	3724	Pad 13		INT32	32	0	0	0	ERW	FVS
22.13.14	3726	Pad 14		INT32	32	0	0	0	ERW	FVS
22.13.15	3728	Pad 15		INT32	32	0	0	0	ERW	FVS
22.13.16	3730	Pad 16		INT32	32	0	0	0	ERW	FVS

Setting of general, 32 Bit variables. PAD parameters can be used as supporting parameters to send values written by the fieldbus, serial line, etc. to analog or digital outputs.

22.14 - FUNCTIONS/VDC CONTROL

This function is used to control the voltage and power recovered in the DC link during regeneration (e.g. during braking ramp). When this function is enabled, if the power regenerated by the load during braking increases the DC link voltage, the drive prevents triggering of the **Overvoltage** alarm by limiting the regenerated current.

The **Vdc control function** is enabled automatically (if parameter **3450 Vdc control function** is set to 1) when the DC link voltage exceeds a preset threshold, depending on the mains voltage and lower than the **Overvoltage** threshold.

This threshold is also used for the regulator that controls the regenerated current limit.

If the **Vdc control function** is enabled, the motor speed need not follow the set ramp.

If the regulator is unable to limit the regenerated power during the deceleration ramp and prevent the **Overvoltage** alarm from being generated, the ramp can be temporarily blocked by setting parameter **754 Ramp freeze src** using the information in **Vdc ctrl ramp freeze**.

The function remains enabled until the power regenerated by the load is cancelled and the DC link voltage falls below the disable threshold (below the enable threshold).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.14.1	3450	Vdc control function		ENUM		Disable	0	1	ERWZ	FVS

This parameter is used to enable the **Vdc control function**.

0 Disable

1 Enable

If set to **0** the function is disabled: in case of power recovery the Sovratensione alarm is generated.

If set to **1** the function is enabled: in case of power recovery the function is enabled and attempts to control the current regenerated by the motor and prevent the **Overvoltage** alarm from being generated.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.14.21	3470	Vdc control P gain	A/V	FLOAT		CALCF	0.0	100.000	ERWS	FVS

Setting of the proportional gain used during the **Vdc control function**. The set value must be increased if the **Overvoltage** alarm is generated. The Sovratensione alarm can also be prevented by lengthening the deceleration ramp. The value of this parameter must also be increased if the DC link voltage is set to a value other than the setpoint

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.14.3	3472	Vdc control I time	ms	FLOAT		CALCF	1.0	1000.0	ERWS	FVS

Setting of the integral time used during the **Vdc control function**. The set value must be reduced if the DC link voltage is set to a value other than the setpoint.

22.15 - FUNCTIONS/BRAKE CONTROL

This function is used to control the motor parking brake.

Do not use the **Brake control** and the **Speed Capture** functions together, as the latter, if enabled before the Start command, attempts to execute synchronisation with the motor speed and with the brake closed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.1	3170	Brake control funct		ENUM		Disable	0	3	ERWZ	FVS

This parameter is used to enable the **Brake control funct**.

- 0 Disable
- 1 Standard
- 2 Hoist mode 1
- 3 Hoist mode 2

If set to **0** the function is disabled:

If set to **1** the function is enabled.

Set to **2** to enable the Hoist mode 1 function for hoisting applications using the standard drive.

Set to **3** to enable the Hoist mode 2 function for hoisting applications using the drive with the special "Positioner" application.

In "**Hoist mode 1**" all the parameters between PAR 3170 and PAR 3186 are used, whereas in "**Hoist mode 2**" PAR 3188 and 3190 are also used, but parameter 3182 is ineffective (since it is the "torque" value that is considered, not the "current").

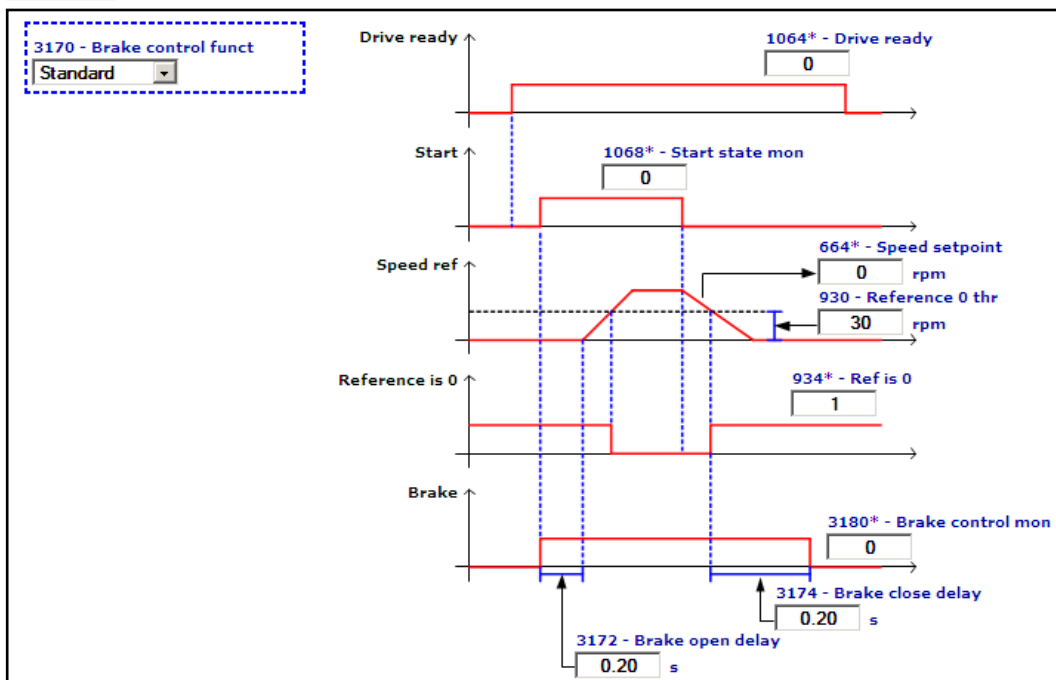
If the drive is in "V/f" control mode, the only possible selection is "**Standard**" and "**Hoist mode 1**".

If "**Hoist mode 2**" is enabled and the drive is thus in "**Flux vector CL**" or "**Flux vector OL**" mode, when switching to "**V/f control**" the brake control mode (PAR 3170) is automatically set to "**Disable**".

The following can be selected, depending on the control mode used:

- 1) **V/f control** -> "Standard" ; "Hoist mode 1" (for asynchronous motors)
- 2) **Flux vector CL** -> "Standard" ; "Hoist mode 1" ; "Hoist mode 2"
- 3) **Flux vector OL** -> "Standard" ; "Hoist mode 1" ; "Hoist mode 1"

Standard



Opening phase:

When the drive receives the **Start** command it releases the brake immediately. To make sure that the brake has actually been released, the references are disabled for a time that can be set in parameter 3172 **Brake open delay**.

Closing phase:

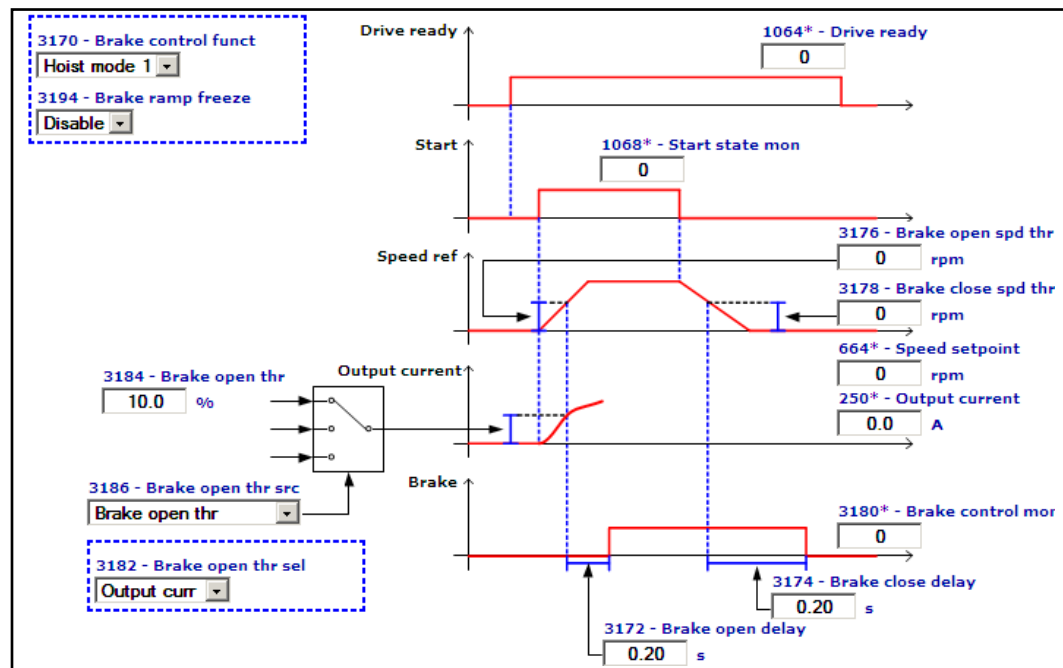
When the drive receives a stop command and the **Ref is 0** signal, it applies the parking brake after a time that can be set in parameter 3174 **Brake close delay**. Set parameter 3174 **Brake close delay** to a high enough value to be sure the motor has actually stopped before enabling the brake.

If this function is enabled, the brake is applied immediately if one or more alarms occur or if the drive is disabled.

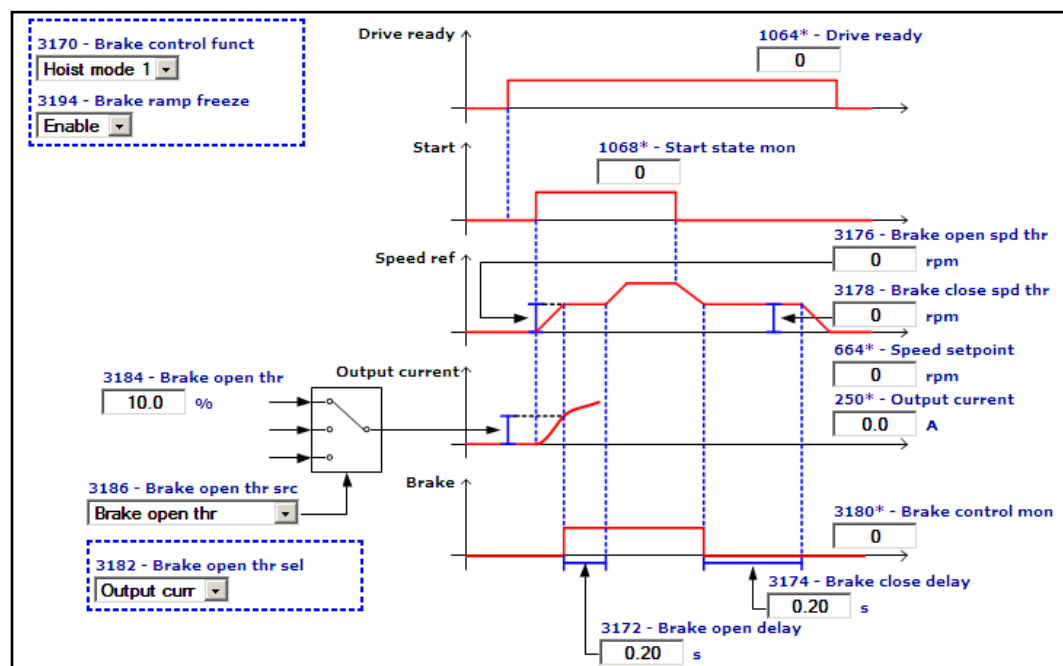
“Hoist mode 1”

With parameter PAR 3194 **Brake ramp freeze** you can freeze the velocity reference during the brake opening and closing phases.

If PAR 3194 = “Disable,” “Hoist mode 1” does not use velocity reference freezing.



If PAR 3194 = “Enable,” “Hoist mode 1” uses velocity reference freezing (diagram shown below).



Opening phase:

Setting of parameters 3172, 3176, 3182, 3184, 3186.

When the drive is in the “**Drive ready**” and “**Start**” conditions (following the enable and start commands) the brake is opened (i.e. the signal corresponding to PAR 3180 **Brake control mon**, which must in turn be assigned to a digital output, is raised) provided a further condition, defined by setting parameters 3182, 3184, 3186, is met once the **Speed setpoint** (PAR 664, considered as an absolute value) has reached the value set in PAR 3176 **Brake open spd thr**.

Parameter 3182 **Brake open thr sel** is used to establish whether the comparison is to be made with the drive output current (value 1, **Output curr**) or with the torque supplied (value 0, “**Torque ref%**”).

Parameters 3184 **Brake open thr** and 3186 **Brake open thr src** are used to define the value of the threshold at which the comparison is made (this can also be set via analog input, fieldbus, Pad, FastLink...).

If the value of parameter 3182 **Brake open thr sel** is equal to **Output curr**, the brake is opened provided one of the following 3 conditions is met:

- The threshold defined by parameters 3184/3186 is positive, and the value of parameter 250 **Output current** is higher than the threshold.
- The threshold defined by parameters 3184/3186 is negative, and the value of parameter 250 **Output current** is less than the threshold.
- The threshold is zero, therefore the brake is always opened.

If the value of parameter 3182 **Brake open thr sel** is equal to “**Torque ref%**”, the brake is opened provided one of the following 3 conditions is met:

- The threshold defined by parameters 3184/3186 is positive, and the value of parameter 2386 **Torque ref %** is higher than the threshold.
- The threshold defined by parameters 3184/3186 is negative, and the value of parameter 2386 **Torque ref %** is less than the threshold.
- The threshold is zero, therefore the brake is always opened.

Threshold values are expressed as a percentage and refer to the rated current or torque values of the drive.

Parameter 3172 **Brake open delay** can be set to define the delay between the moment the double opening condition occurs (speed reference + current or torque) and the time the open command is actually sent by the drive.

If the speed reference condition is met but not the current or torque condition, the drive enters a **Brake fault** alarm condition, which can be managed via parameter 4684 **Brake fault activity**, (set by default to Disable).

Closing phase:

If the drive is disabled (also due to any alarms that are capable of disabling it) the close brake command is sent immediately, regardless of the operating condition.

For normal closing, set parameters 3174, 3178.

When the brake has been opened, it waits for the “**Stop**” command, then sends the close command when the speed reference is less than the value set in parameter 3178 **Brake close spd thr**. Parameter 3174 **Brake close delay** can be used to enter a delay between the moment the closing condition occurs and that in which the close command is actually sent by the drive. After the closing condition, it is also possible to restart the drive within the time set in **Brake close delay**, by sending the normal “**Start**” command. In that case the timer is reset and the drive waits for the closing condition again, which starts when a new “**Stop**” command is sent.

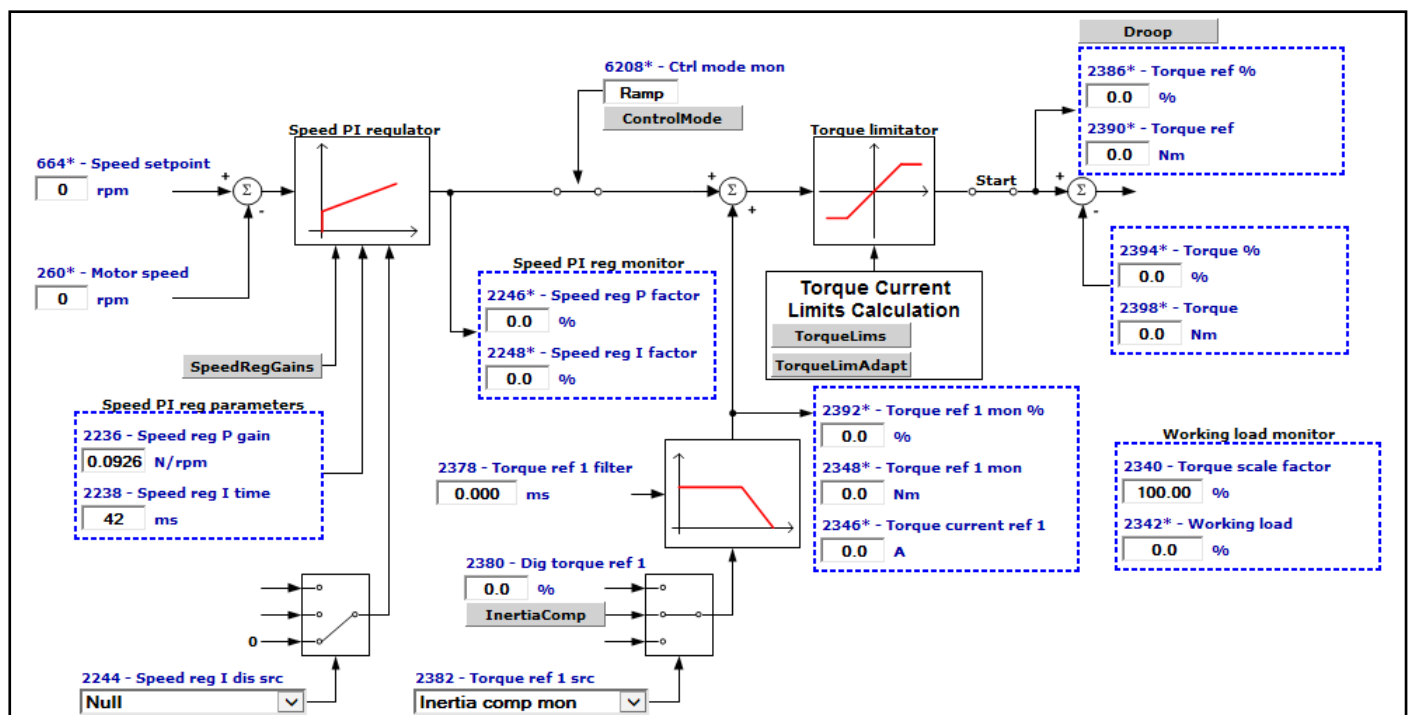
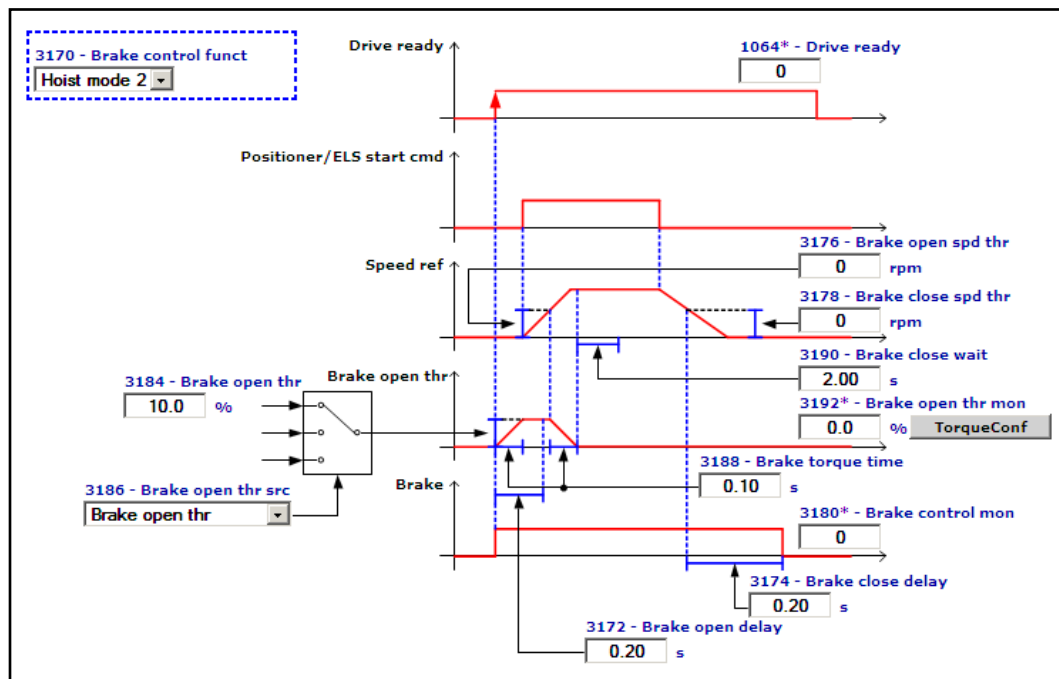


Avvertenza

In V/f control mode, since there is no precise control of the actual speed and torque, the ‘Speed ref loss’ alarm is not managed, which means that external controls must be used to detect any possible loss of a suspended load.

“Hoist mode 2”:

This mode can only be used when the “Positioner” application is installed in the drive.



Opening phase:

Setting of parameters 3172, 3176, 3184, 3186, 3188 and 2382.

Parameter 2382 **Torque ref 1 src** (menu 20 - TORQUE CONFIG) must be set to PAR 3192 **Brake open thr mon**.

Parameter 3182 **Brake open thr sel** is not considered, in that regardless of its value, the values considered are always to be taken as “torque” and not “current” (since the positioner can only be used in **Flux vector CL** mode).

When the “**Drive ready**” (enable drive) signal switches from 0->1 the open brake command is sent immediately. At the same time, parameter 3192 **Brake open thr mon**, added to the **TORQUE CONFIG** block, starts to increase in value from 0 up to the threshold value defined on the output of the selector associated with the pair of parameters 3184/3186. This value increases over a ramping up time settable in parameter 3188 **Brake torque time**. Parameter 3188 must be set to a value close to the brake open delay (i.e. the time it takes for the brake to be opened after the open command is sent). This ramp can be monitored via parameter 2392 **Torque**

ref 1 mon, visible in the diagrams of GF_eXpress.

When the **Start** positioner command (in the list of commands of the “Positioner” application) is sent, the value of parameter 664 **Speed setpoint** is increased. When this speed reference reaches the threshold defined by parameter 3176 **Brake open spd thr** (and in any case not before a time equal to PAR 3172 **Brake open delay**, which is always measured from the moment the brake opens) the pre-torque value injected (**Brake open thr mon**) after opening is reset to 0 with a ramping down time that is always equal to the value of 3188 **Brake torque time**.

In the transient opening phase the “positioner” could generate a speed reference value that is higher than the “**Brake open spd thr**” threshold. This, in turn, could result in the removal of the pre-torque due to the incorrect assumption that a positioner has started. To prevent this, parameter 3172 **Brake open delay** can be set so that the comparison with the speed reference is only performed after a certain delay.

In this mode the “**Brake fault**” alarm can never be triggered as it is not envisaged in “**Hoist mode 2**”.

Closing phase:

When the drive is disabled (also due to any alarms that are capable of disabling it) a close brake command is sent immediately, regardless of the operating condition.

For normal closing, set parameters 3174, 3178 and 3190.

When the brake opening phase is complete and after a delay equal to at least the value of 3190 **Brake close wait** (measured from the moment pre-torque removal ends) it waits for the speed reference to fall below the value set in 3178 **Brake close spd thr**.

Parameter 3174 **Brake close delay** can be used to enter a delay between the moment the closing condition occurs and that in which the close command is actually sent by the drive.

After the brake closing condition has occurred (within the time set in Brake close delay) it is also possible to restart the drive by sending a new positioning command. In that case the timer is reset and the drive waits for the closing condition again, which occurs when the speed reference falls to below the value of **Brake close spd thr** and after the delay set in **Brake close wait**.

Parameter 3190 **Brake close wait** can thus reasonably be set to a value that is slightly less than the positioning time. It ensures that within the set time the speed reference can also fall below the **Brake close spd thr** value without the close command being sent.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.2	3172	Brake open delay	s	FLOAT		0.20	0.0	60.0	ERW	FVS

Setting of the delay for opening an external mechanical brake.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.3	3174	Brake close delay	s	FLOAT		0.20	0.0	60.0	ERW	FVS

Setting of the delay to reach the motor zero speed before closing the brake.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.4	3176	Brake open spd thr	rpm	INT16		0	0	CALCI	ERW	FVS

Setting of the brake opening speed threshold value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.5	3178	Brake close spd thr	rpm	INT16		0	0	CALCI	ERW	FVS

Setting of the brake closing speed threshold value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.6	3194	Brake ramp freeze		ENUM		Disable	0	1	ERWZ	FVS

With this parameter you can freeze the velocity reference during brake opening and closing in “**Hoist Mode 1**”.

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.7	3182	Brake open thr sel		ENUM		Output curr	0	1	ERWZ	FVS

Selecting of the type of comparison between the threshold value of open brake torque and the torque value or output current of the drive.

- 0 Torque ref%
- 1 Output curr

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.8	3184	Brake open thr	perc	FLOAT		10	-200.0	200.0	ERWZS	FVS

Threshold value at which the comparison is made.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.9	3186	Brake open thr src		LINK	16/32	3184	0	16384	ERWZ	FVS

Selection of the origin (source) of the signal to be used.

The values that can be selected in the compare function are listed in the “ **L_TCREF**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.10	3188	Brake torque time	s	FLOAT		0.10	0.01	60.0	ERWZ	FVS

Ramp time of parameter 3192 **Brake open thr mon** to move from the value up to the threshold value defined by PAR 3184 / 3186 (only if **Hoist mode 2** is selected).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.15.11	3190	Brake close wait	s	FLOAT		2	0.0	60.0	ERW	FVS

Delay before measuring the speed reference (equal to the time from opening the brake + the time up until removal of the pre-torque). Only if **Hoist mode 2** has been selected.

22.16 - FUNCTIONS/DIMENSION FACT

The function factor allows the drive speed to be expressed in a unit of measure other than rpm, generally referred to as user units. A conversion factor is used to convert the value from rpm to user units. This can be set as a fraction using two parameters:

PAR 3900 **Dim factor num** and PAR 3902 **Dim factor den**.

The conversion formula is $\text{rpm} = \text{Dim factor num} / \text{Dim factor den} * \text{user unit}$

The unit of measure displayed for parameters expressed in user units is user definable, but requires the use of the keypad or GF-eXpress configurator. The text of the unit of measure is set in PAR 3904 **Dim factor text**. Since this is a UINT32 it can contain a maximum of 4 characters.

The default values of the parameters that define the function factor are:

PAR 3900 **Dim factor num** = 1; PAR 3902 **Dim factor den** = 1; PAR 3904 **Dim factor text** = “rpm”

The following parameters expressed by default in rpm can be displayed in user units:

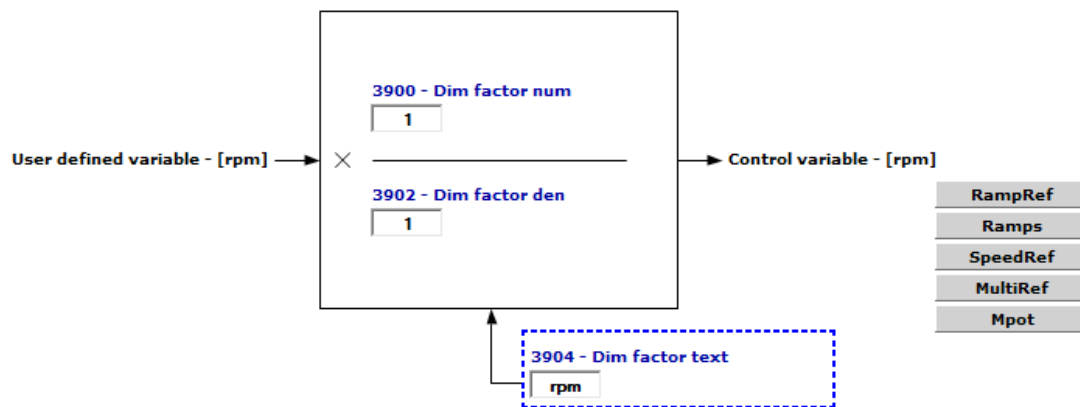
PAR	Description	UM	UU
628	Ramp setpoint	rpm	X
664	Speed setpoint	rpm	X
260	Motor speed	rpm	X
600	Dig ramp ref 1	rpm	X
602	Dig ramp ref 2	rpm	X
604	Dig ramp ref 3	rpm	X
620	Ramp ref 1 mon	rpm	X
622	Ramp ref 2 mon	rpm	X
624	Ramp ref 3 mon	rpm	X
626	Ramp ref out mon	rpm	X
634	Ramp ref top lim	rpm	X
636	Ramp ref bottom lim	rpm	X
630	Reference skip set	rpm	
632	Reference skip band	rpm	
640	Dig speed ref 1	rpm	X

PAR	Description	UM	UU
810	Multi reference 5	rpm	X
812	Multi reference 6	rpm	X
814	Multi reference 7	rpm	X
816	Multi reference 8	rpm	X
818	Multi reference 9	rpm	X
820	Multi reference 10	rpm	X
822	Multi reference 11	rpm	X
824	Multi reference 12	rpm	X
826	Multi reference 13	rpm	X
828	Multi reference 14	rpm	X
830	Multi reference 15	rpm	X
852	Multi ref out mon	rpm	X
870	Mpot setpoint	rpm	X
876	Mpot top lim	rpm	X
878	Mpot bottom lim	rpm	X

642	Dig speed ref 2	rpm	X
660	Speed ref 1 mon	rpm	X
662	Speed ref 2 mon	rpm	X
670	Speed ref top lim	rpm	X
672	Speed ref bottom lim	rpm	X
680	Full scale speed	rpm	
760	Ramp outmon	rpm	X
800	Multi reference 0	rpm	X
802	Multi reference 1	rpm	X
804	Multi reference 2	rpm	X
806	Multi reference 3	rpm	X
808	Multi reference 4	rpm	X

894	Mpot output mon	rpm	
910	Jog setpoint	rpm	
920	Jog output mon	rpm	
930	Reference 0 thr	rpm	
940	Speed 0 thr	rpm	
950	Speed threshold 1	rpm	
952	Speed threshold 2	rpm	
962	Set speed error	rpm	
968	Dig set speed ref	rpm	
970	Speed threshold 3	rpm	
972	Speed thr hysteresis	rpm	

If a function factor is set, all the parameters in the above table are converted into user units.



Calculation of the minimum and maximum values of parameters “Dim factor num” and “Dim factor den”

Calculation of the minimum and maximum values of parameters “Dim factor num” and “Dim factor den”.

Limits must be included when setting the values of PAR 3900 **Dim factor num** and PAR 3902 **Dim factor den** to prevent the internal variables of the drive moving out of range.

Fixed limits for each of the two parameters cannot be defined since it is the ratio between the two that must be limited and because this limit also depends on parameter 680 **Full scale speed**.

There is the possibility of an overflow depending on the order in which the two parameters PAR 3900 **Dim factor num** and PAR 3902 **Dim factor den** are set and their initial value.

The conditions in which an overflow could occur are described in the table below.

Initial value	Values to be set	Order	Overflow
Den = 1 Num = 1	Den 30 – Num 10	Num – Den	No
Den = 1 Num = 1	Den 30 – Num 10	Den – Num	Si
Den = 30 Num = 10	Den 1 – Num 1	Num – Den	Si
Den = 30 Num = 10	Den 1 – Num 1	Den – Num	No

If an overflow occurs when setting one of the two parameters, the other parameter is automatically set to the same value so that the conversion value is equal to 1.

Sent via the configurator

If the parameters are sent by the GF-eXpress configurator, they are written in a set order and an intermediate overflow could occur while setting valid values.

If the value of the first parameter sent by the configurator generates an overflow, the second parameter is set to the same value as the first (this temporarily forces the dimension factor to 1); when the second parameter is written the dimension factor returns to the correct value.

Changing the end of scale speed

When modifying PAR 680 **Full scale speed**, parameters PAR 3900 **Dim factor num** and PAR 3902 **Dim factor den** are forced to 1.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.16.1	3900	Dim factor num		UINT16		1	1	65535	ERW	FVS

Numerator dimension factor

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.16.2	3902	Dim factor den		UINT16		1	1	65535	ERW	FVS

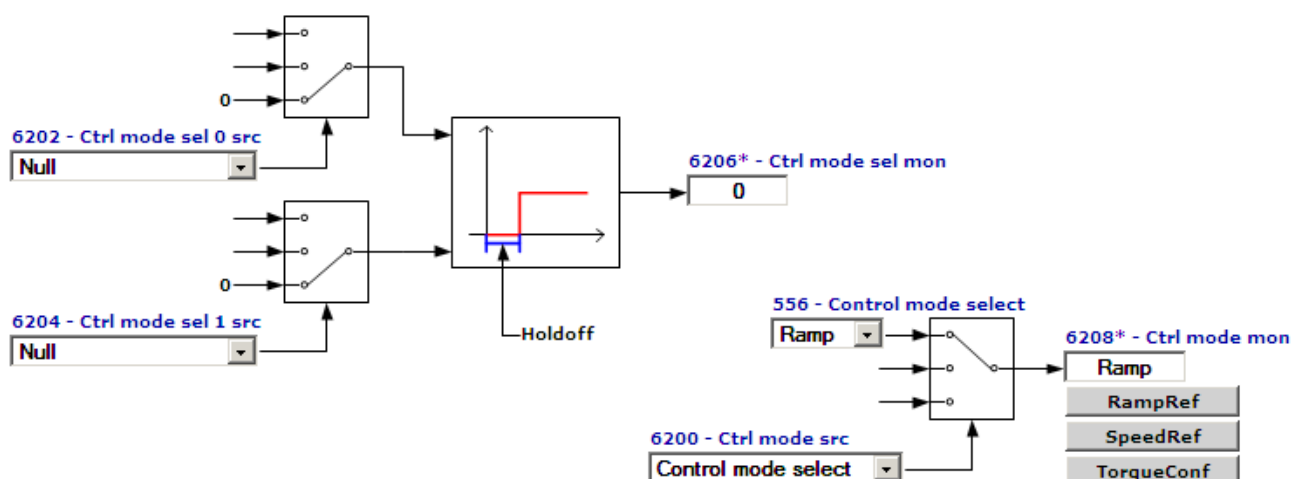
Denominator dimension factor

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.16.3	3904	Dim factor text		UINT32		7172210	0	0	ERW	FVS

The unit of measure displayed for parameters expressed in user units is user definable but requires the use of the configurator. The text of the unit of measure can contain up to a maximum of 4 characters.

22.17 - FUNCTIONS/CONTROL MODE

Note! Function available only when PAR 552 **Control mode select** is set [1] **Flux Vector CL** or [2] **Flux Vector OL**.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.17.1	556	Control mode select		ENUM		Ramp	0	2	ERWZ	F_S

Selection of the drive control mode.

- 0 Torque
- 1 Speed
- 2 Ramp

In **torque control (0 - Torque)** the reference and load of the motor determine its speed and direction of rotation. Symmetrical torque limits can be set, for each direction of rotation and for motor/generator operation. This type of control is only available in the **Flux vector CL** control mode. In this mode the **Ramp** function is not used to generate the drive speed reference so it can be used in stand-alone mode.

In **speed control (1 - Speed)** the reference arrives straight after the ramp circuit, enabling an extremely rapid response to signal variations. This is ideal for applications that require a highly dynamic response. This type of control is available in the **Flux vector CL** and **Flux vector OL** control modes. In this mode the **Ramp** function is not used to generate the drive speed reference so it can be used in stand-alone mode.

In **control with ramp (2 - Ramp)** the speed reference is applied to the input of the "Ramp" block and is produced by the "Ramp ref" block. This allows setting of both the acceleration/deceleration times and the ramp time (linear or S-shaped with customizable jerks). This type of control is available in all control.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.17.2	6200	Ctrl mode src		LINK	16	556	0	16384	ERWZ	F_S

Selection of source of **Control Mode** function. The parameter to be assigned to this function is selected from the "**L_CTRLMODE**" selection list.

If IPA 6200 = **Control mode select**, IPA6208 value is set thru IPA556.

If IPA 6200 = **Ctrl mode sel mon**, IPA6208 value is set thru IPA6206.

If IPA 6200 is a **PAD X**, the PAD value will be considered.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.17.3	6202	Ctrl mode sel 0 src		LINK	16	6000	0	16384	ERWZ	F_S
22.17.4	6204	Ctrl mode sel 1 src		LINK	16	6000	0	16384	ERWZ	F_S

Selection of the drive control mode thru digital inputs

Ctrl mode sel 0 src	Ctrl mode sel 1 src		
0	0	0	Torque
0	1	1	Speed
1	0	2	Ramp

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.17.5	6206	Ctrl mode sel mon		UINT32		0	0	3	ER	F_S

Monitoring of the selection done thru the IPA6202 **Ctrl mode sel 0 src** and IPA6204 **Ctrl mode sel 1 src**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.17.6	6208	Ctrl mode mon		ENUM		Torque	0	0	ER	F_S

Torque-Speed-Ramp selection done thru the IPA6200 "Ctrl mode src, IPA6202 **Ctrl mode sel 0 src** and IPA6204 **Ctrl mode sel 1 src**.

0 Torque

1 Speed

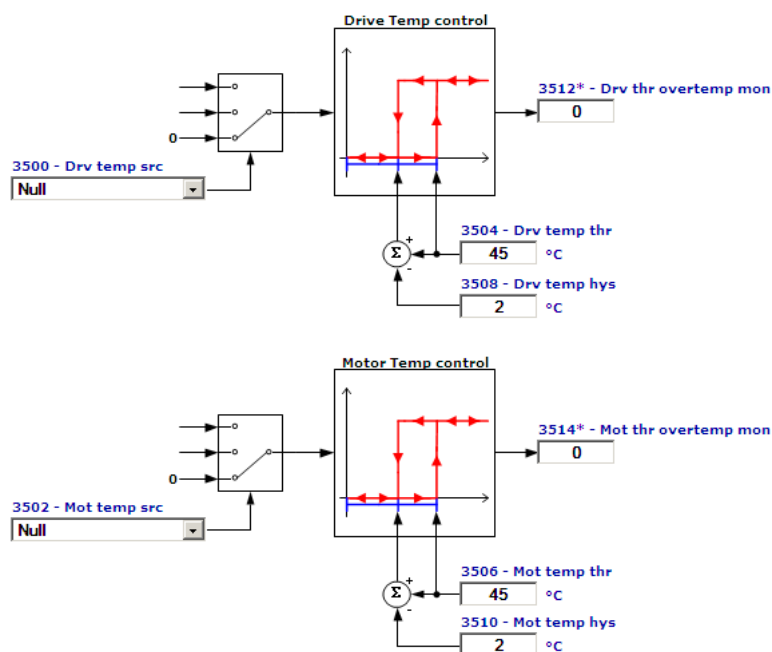
2 Ramp

22.18 - FUNCTIONS/TEMP CONTROL

This function basically includes two comparators with hysteresis.

By managing temperature sensors such as the PTC, PT100 or KTY84, you can command (via the drive's digital outputs) external solenoids to activate drive and/or motor cooling systems.

The TEMP CONTROL function works only on the basis of the temperature measured by its sensor and consequently commands the digital output. It does not run any check of the system's safety conditions (formation of condensation, over-humidity). The user has to employ systems outside the inverter to check that working conditions are safe.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.18.1	3500	Drv temp src		LINK	32	6000	0	16384	ERW	FVS

Selection of signal origin (source) for management of a temperature signal. The parameter to be assigned to this function is selected from the “**L_TEMPCTRL**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.18.2	3504	Drv temp thr	degC	INT32		45	1	100	ERW	FVS

Setting the hysteresis comparator setpoint.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.18.3	3508	Drv temp hys	degC	INT32		2	0	CALCI	ERW	FVS

Setting of a tolerance band for the trip threshold set in PAR 3504.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.18.4	3502	Mot temp src		LINK	32	6000	0	16384	ERW	FVS

Selection of signal origin (source) for management of a temperature signal. The parameter to be assigned to this function is selected from the “**L_TEMPCTRL**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.18.5	3506	Mot temp thr	degC	INT32		45	1	100	ERW	FVS

Setting the hysteresis comparator setpoint.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.18.6	3510	Mot temp hys	degC	INT32		2	0	CALCI	ERW	FVS

Setting of a tolerance band for the trip threshold set in PAR 3506.

22.19 - FUNCTIONS/LC CONTROL

The LC function runs the Condensation check on a water-cooled drive (ADV200-LC).

It lets you check if working conditions are safe, command the cooling circuit solenoid and, if necessary, specify what the allowed cooling liquid temperature should be.

Based on the humidity and ambient temperature measured by the built-in sensors, the dew point is calculated and compared to the cooling liquid temperature measured by the sensor on the drive plate near the input manifold or by an external sensor.

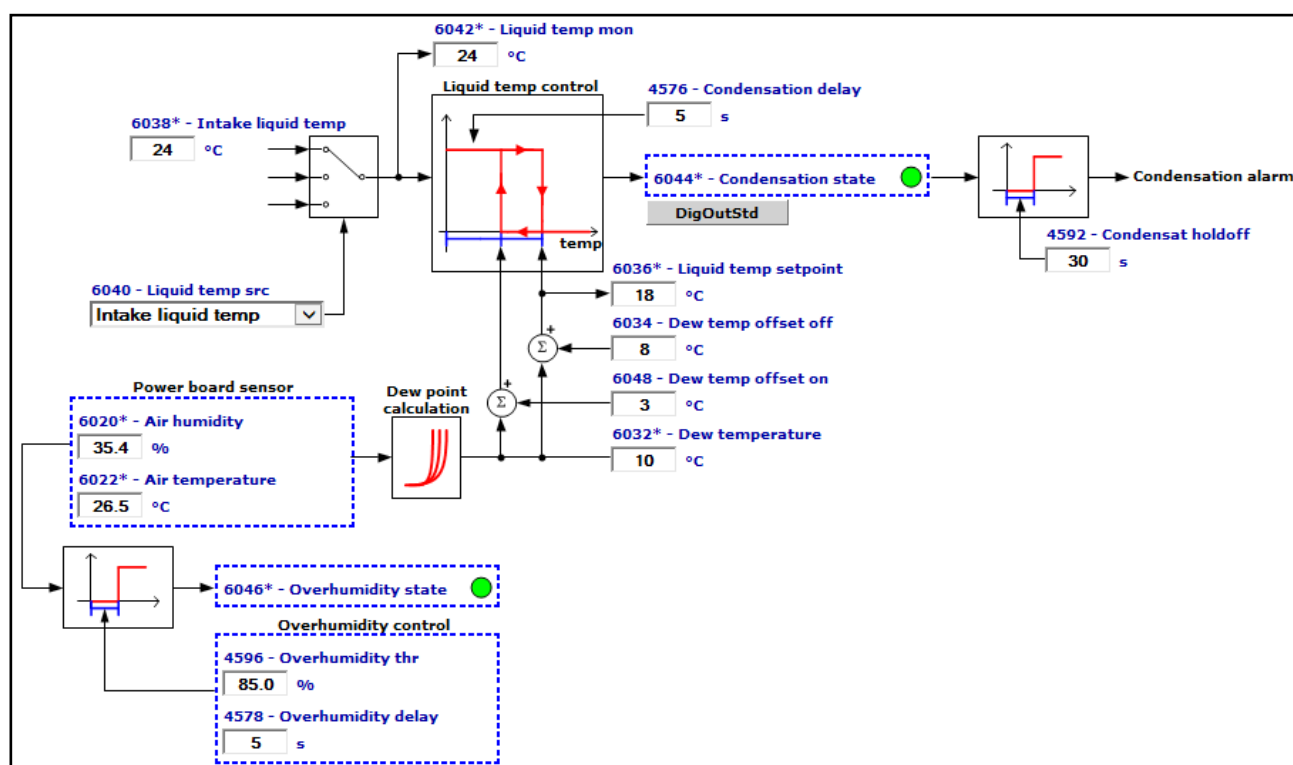
If the cooling liquid temperature is below the dew point, the flag on the Condensation monitor is activated.

By means of a digital output on the drive, the monitor flag is generally used to command the cooling circuit solenoid.

An alarm trips if the Condensation conditions persists for a (settable) time.

Safety conditions are shown on the "Safe operating area" graph below.

The LC function also detects Over-humidity condition and manages the relative alarm.



Condensation Control

- By measuring **Air Temperature** IPA 6022 and **Air humidity** IPA 6020, the dew point is calculated and shown as monitor parameter IPA 6032 **Dew temperature**.
- The selector assigned to parameter IPA 6040 **Liquid temp src** lets you set the sensor used to measure cooling liquid temperature:
- If IPA 6040 **Liquid temp src** = **Intake liquid temp** (IPA 6038, default setting), the measurement is made by a sensor on the drive plate near the input manifold.
- If IPA 6040 **Liquid temp src** = **An inp 1X temp mon** or **2X**, the measurement is made by an external sensor (PT100, PTC or KTY84) connected to the optional EXP-IO-SENS-100-ADV board (see the manual for this option).
- Cooling liquid temperature is displayed on monitor parameter IPA 6042 **Liquid temp mon**. If the temperature is below dew point IPA 6032 added to the offset IPA 6048 **Dew temp offset On** for a time exceeding IPA 4576 **Condensation delay** (default = 5s), monitor flag IPA 6044 **Condensation state** is activated. The flag can be copied to a digital output to control the external valve used to manage cooling liquid circulation.

Flag off = **digital output level** = **L** = **valve open**

Flag on = **digital output level** = **H** = **valve closed**

The digital output can be set on the DIGITAL OUTPUTS menu. For example: IPA 1314 **Digital output 3 src** = **Condensation** (the output will be at terminal 13 of the control board).

The operating state of the digital output may be reversed: IPA 1434 **Dig out 3X inversion** = On.

Note: the draw of the circulation valve coil should always be assessed based on the loadability of the digital output. If draw exceeds loadability, you have to use an external relay. (we recommend a solid-state relay).

- The value obtained by adding IPA 6032 **Dew temperature** and IPA 6048 **Dew temp offset On** is shown in parameter IPA 6036 **Liquid temp setpoint** and represents the minimum temperature allowed for the cooling liquid. This value may be used as a reference for an external controller/regulator.
- If Condensation state persists for a time exceeding the delay set on the ALARMS CONFIG menu, parameter IPA 4592 **Condensat holdoff** (default = 30s), the [32] **Condensation** alarm condition with the programmed activity is signalled.
- If the system has a cooling liquid temperature controller, the time set in IPA 4592 **Condensat holdoff** must match the minimum time needed to bring the temperature to the value of PAR 6036 **Liquid temp setpoint**.

The activities normally provided for the condensation alarm are:

1) IPA 4590 **Condensat activity**= Disabled (default programming)

In this case the condition is put on the alarms list and historical file, the Drive OK relay is opened, and the inverter is disabled. The motor stops based on the inertia, friction, and resistive torque applied to the axis.

You are advised to use relay OK status to open the line contactor of the inverter.

To restart the drive, reset the alarm (from keypad, digital input, or fieldbus) and restore safe working conditions.

2) IPA 4590 **Condensat activity**= Warning

In this case the condition is put on the alarms list and historical file but commands to the inverter are not changed. The motor continues to be controlled according to the assigned references.

The user is responsible for taking all steps to prevent all breakdowns of the drive: disable the inverter, open the line contactor.

If the temperature of the liquid returns above or equal to PAR 6036 **Liquid temp setpoint**, the alarm is automatically reset.

- The alarm condensation condition can be copied to a digital output of the inverter:

ALARMS CONFIG menu – IPA 4702 **Alarm dig sel 1 = Condensation**

DIGITAL OUTPUTS menu– IPA 1316 **Digital output 4 src= 4708 Alm dig out mon 1** (the output will be at terminal 14 of the control board).

Condensation occurs when the temperature of the liquid entering the inverter is significantly lower than ambient temperature (in the electrical panel).

The allowed temperature difference depends on the % of ambient humidity.

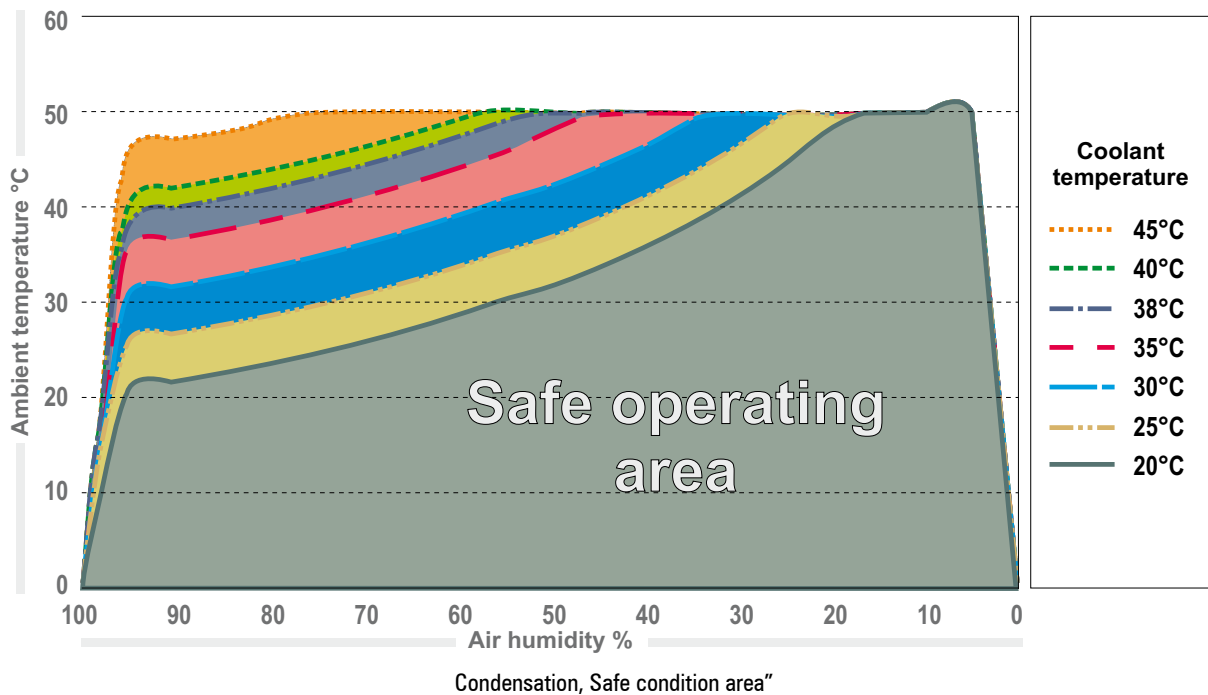
The temperature at which air becomes saturated with water vapor and “precipitates” is called the dew point.

The following graph can be used to check if working conditions (combination of ambient temperature, humidity, and cooling liquid temperature) are safe and, if necessary, to select the allowed cooling liquid temperature.

Safe conditions are obtained when the work point is below the respective “Safe condition area” curve. Otherwise, take adequate precautions by raising the cooling liquid temperature (or by adjusting ambient temperature and humidity).

The curves shown are valid at sea level (1013 mbar).

Note: Raising the cooling liquid temperature may cause a reduction in the nominal current and overload of the inverter (1.5% for each degree over 35°C).



If the temperature in the electrical closet is 30°C, relative humidity 40%, and cooling liquid temperature is 20°C (the lowest curve in the figure shown above), the drive's working conditions are safe.

If the ambient temperature rises to 35°C and relative humidity to 60%, the drive's working conditions are no longer safe. In this case, to restore safe working conditions, the cooling liquid temperature must be brought to at least 25°C.

The following table (dew point table) presents the data shown in the above graph in numerical form (input temperature of cooling liquid [°C] based on ambient temperature and humidity in air).

		Humidity in air [%]									
		10	20	30	40	50	60	70	80	90	100
Ambient temperature[°C]	-25	-45	-40	-36	-34	-32	-30	-29	-27	-26	-25
	-20	-42	-36	-32	-29	-27	-25	-24	-22	-21	-20
	-15	-37	-31	-27	-24	-22	-20	-18	-16	-15	-15
	-10	-34	-26	-22	-19	-17	-15	-13	-11	-11	-10
	-5	-29	-22	-18	-15	-13	-11	-8	-7	-6	-5
	0	-26	-19	-14	-11	-8	-6	-4	-3	-2	0
	5	-23	-15	-11	-7	-5	-2	0	2	3	5
	10	-19	-11	-7	-3	0	1	4	6	8	9
	15	-18	-7	-3	1	4	7	9	11	13	15
	20	-12	-4	1	5	9	12	14	16	18	20
	25	-8	0	5	10	13	16	19	21	23	25
30	-6	3	10	14	18	21	24	26	28	30	
35	-2	8	14	18	22	25	28	31	33	35	
40	1	11	18	22	27	31	33	36	38	40	
45	4	15	22	27	32	36	38	41	43	45	
50	8	19	28	32	36	40	43	45	48	50	

The dew point also depends on absolute pressure, i.e., on the altitude at which the electrical panel is installed.

At altitudes above sea level (0 m), atmospheric pressure (and therefore the dew point) decreases. For this reason, you should always check the cooling liquid temperature by considering the curves and tables calculated for an altitude of 0 m.

In continuous operating conditions, a liquid-cooled inverter works at lower temperatures than an air-cooled inverter. This extends the life of power components such electrolytic capacitors and IGBT modules.

The inverters have been sized based on continuous use of the cooling liquid at the nominal flow rates specified in the manual. Discontinuous use of the cooling liquid (for example, to lower the possibility of condensation), or continuous use but at lower flow rates than specified, may reduce the drive's performance and may also shorten the life of some components.

Overhumidity control

The drive's built-in humidity sensor lets you signal an unsafe condition and can also generate an alarm.

Overhumidity parameter IPA 6046 becomes active when the value of parameter IPA 6020 **Air humidity** exceeds the threshold set in parameter IPA 4596 **Overhumidity thr** (default = 85%) for a time exceeding IPA 4578 **Overhumidity delay**.

Internal alarm [52] **Humidit sens error** detects a possible communication error between the humidity sensor and the drive's control board.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.1	6020	Air humidity	perc	FLOAT		0.0	0.0	0.0	ER	FVS

Monitor value of the Air Humidity detected from the internal sensor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.2	6022	Air temperature	degC	FLOAT		0.0	0.0	0.0	ER	FVS

Monitor value of the Air Temperature detected from the internal sensor.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.3	6032	Dew temperature	degC	INT16		0	0	0	ER	FVS

Monitor value of the Dew point depending on parameters PAR 6020 and PAR 6022.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.4	6034	Dew temp offset Off	degC	INT16		8	3	50	ERW	FVS

Setting of a programmable Offset that can be added to the dew point value so that the **Condensation state** output (IPA 6044) is deactivated (Digital output level = L = circulation valve open) when liquid temperature (IPA 6042) is higher than **Dew temperature** (IPA 6032) + **Dew temp offset off** (IPA 6034).

IPA 6034 **Dew temp offset off** cannot be set to a value below IPA 6048 **Dew temp offset on**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.5	6048	Dew temp offset on	degC	INT16		3	2	50	ERW	FVS

Setting of a programmable Offset that can be added to the dew point value so that the **Condensation state** output (IPA 6044) is activated (Digital output level = H = circulation valve closed) when liquid temperature (IPA 6042) is below **Dew temperature** (IPA 6032) + **Dew temp offset on** (IPA 6048).

IPA 6048 **Dew temp offset on** cannot be higher than IPA 6034 **Dew temp offset off**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.6	6036	Liquid temp setpoint	degC	INT16		0	0	0	ER	FVS

Setpoint monitor value of the Liquid temperature. It is the sum of the parameters PAR 6032 and PAR 6034.

It is the value to which the temperature of the liquid cooling must be in order to be below the internal security curves to avoid condensation. The user must act externally on the values of temperature to avoid alarm situations.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.7	6038	Intake liquid temp	degC	INT16		0	0	0	ER	FVS

Monitor of temperature of cooling liquid flowing into the heatsink plate.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.8	6040	Liquid temp src		LINK	32	6038	0	16384	ERW	FVS

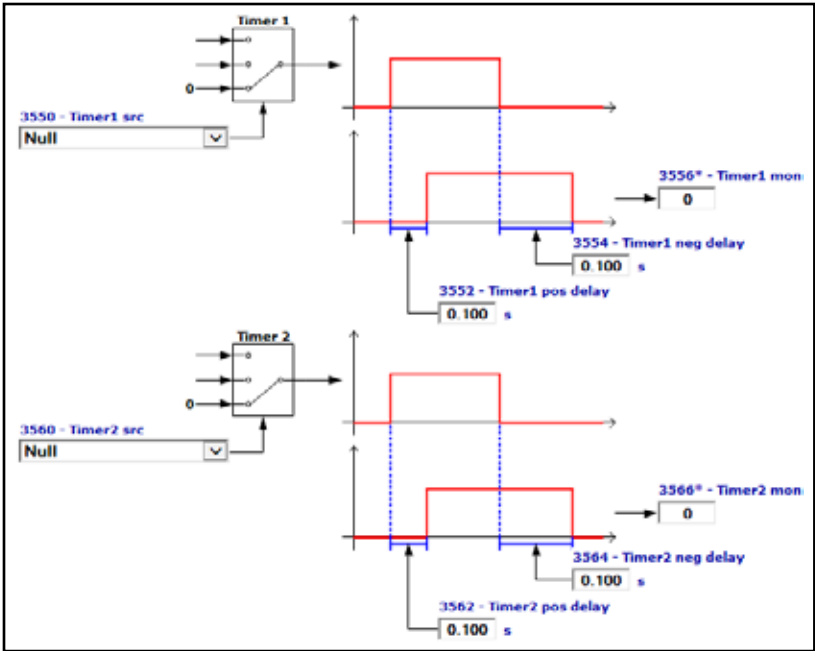
Selection of the origin (source) of the liquid temperature value to be assigned to the relative input. The functions that can be associated are listed in the "L_TEMPCTRL" selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.19.9	6042	Liquid temp mon	degC	INT16		0	0	0	ER	FVS

Monitor of the liquid temperature value.

22.20 - FUNCTIONS/TIMERS

Menu for managing two programmable and independent Timer modules in order to delay the effect of the digital inputs and of all of the parameters on the L_DIGSEL1 selection list.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.20.1	3550	Timer1 src		LINK	32	6000	0	16384	ERW	FVS
22.20.5	3560	Timer2 src		LINK	32	6000	0	16384	ERW	FVS

Lets you assign the control signal to be delayed at Timer X function block input. The signals that can be used for this function can be set from the ones on the L_DIGSEL1 selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.20.2	3552	Timer1 pos delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS
22.20.6	3562	Timer2 pos delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS

Setting of positive delay edge.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.20.3	3554	Timer1 neg delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS
22.20.7	3564	Timer2 neg delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS

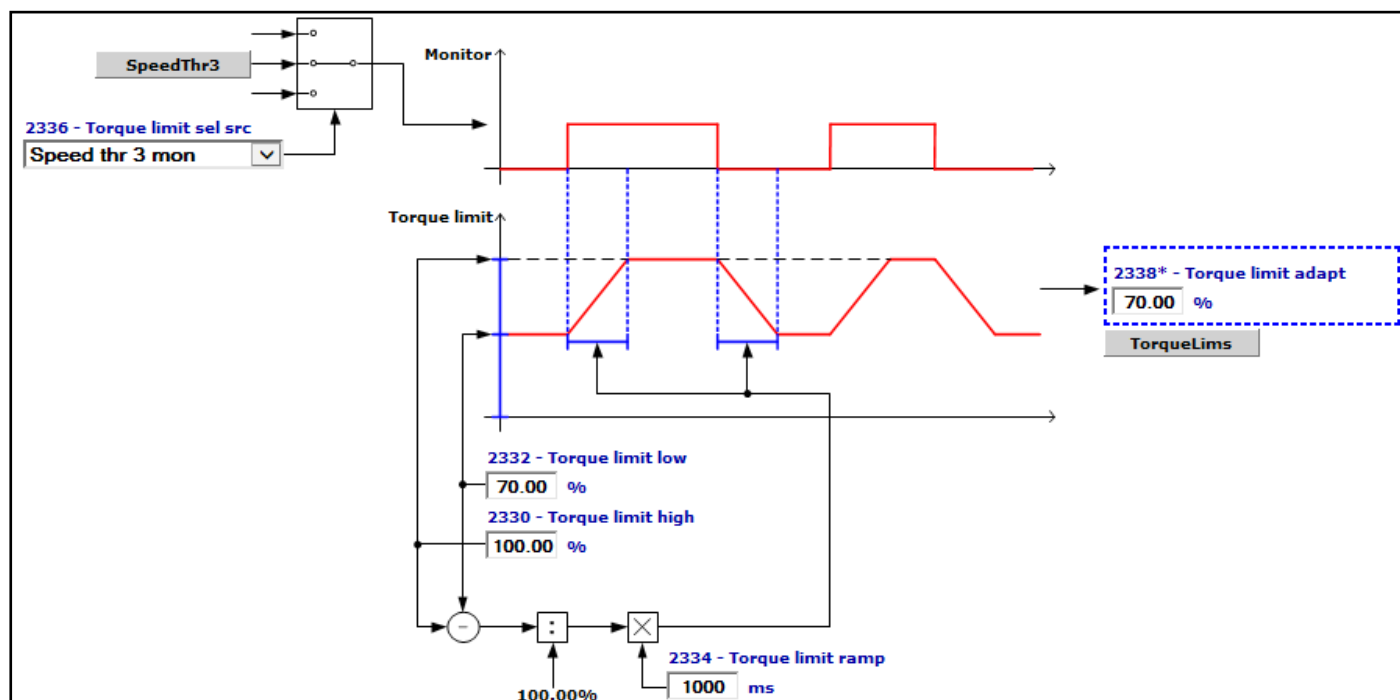
Setting of negative delay edge.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.20.4	3556	Timer1 mon		INT32		0	0	0	ER	FVS
22.20.8	3566	Timer2 mon		INT32		0	0	0	ER	FVS

Display of Timer output state.

22.21 - FUNCTIONS/TORQUE LIMADAPT

These menu parameters let you manage the drive torque limits dynamically based on On/Off conditions, for example, motor speed (above or below a threshold).



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.21.1	2330	Torque limit high	perc	FLOAT		100.0	0.0	CALCF	ERW	F_S

Setting of high torque limit.

If this parameter is set to a value lower than IPA 2332 **Torque limit low**, IPA 2332 is automatically changed to such value.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.21.2	2332	Torque limit low	perc	FLOAT		70.0	0.0	CALCF	ERW	F_S

Setting of low torque limit.

Cannot be higher than the value set in parameter IPA 2330 **Torque limit high**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.21.3	2334	Torque limit ramp	ms	UINT16		1000	0	60000	ERW	F_S

Setting of time to go linearly from 0 to 100% of nominal torque.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.21.4	2336	Torque limit sel src		LINK	16/32	976	0	16384	ERW	F_S

Selection of source to be used to manage the adaptive torque limit:

The list of signals assignable to the function can be selected from the "L_DIGSEL1" selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.21.5	2338	Torque limit adapt	perc	FLOAT		0.0	0.0	0.0	ER	F_S

Adaptive torque limit in percentage, calculated internally by the drive based on the monitor parameter selected in parameter IPA 2336 **Torque limit sel src**.

If the monitor parameter equals 0, IPA 2338 goes to the value of **Torque limit low**

If the monitor parameter equals 1, IPA 2338 goes to the value of IPA 2330 **Torque limit high**.

23 – COMMUNICATION

23.1 – COMMUNICATION/RS485

The ADV200 drive is provided with a standard port (9 pole sub-D connector: XS) for connecting the RS485 serial line used for drive-PC point-to-point communication (via the GF-eXpress configuration software) or for the multidrop connection where it is needed the use of OPT-RS485-ADV optional board. (Max 20 drives can be connected on the serial line).

The RS485 serial line format is: 8 data bits, no parity and one stop bit.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.1.1	3800	Drive address		UINT16		1	1	255	ERW	FVS

Setting of the address to which the drive responds when connected to the RS485 serial line.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.1.2	3802	Serial baudrate		ENUM		38400	0	2	ERW	FVS

Setting of the RS485 serial communication speed (Baud Rate).

- 0 9600
- 1 19200
- 2 38400

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.1.3	3810	Serial parameter		ENUM		None,8,1	0	3	ERW	FVS

Setting of the format of the RS485 serial communication data.

- 0 None,8,1
- 1 None,8,2
- 2 Even,8,1
- 3 Odd,8,1

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.1.4	3804	Serial protocol		ENUM		Modbus	0	1	ERW	FVS

Setting of the serial communication protocol:

- 0 Modbus
- 1 Jbus

Setting to **0** selects the Modbus RTU (Remote Terminal Unit) serial communication protocol.

Setting to **1** selects the Jbus serial communication protocol. The Jbus protocol is functionally identical to the Modbus, except for the different numbering of addresses: in the Modbus these start from zero (0000 = 1st address) while in the JBUS they start from one (0001 = 1st address) and maintain this difference throughout numbering.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.1.5	3806	Serial delay	ms	UINT16		0	0	1000	ERW	FVS

Setting of the minimum delay between the drive receiving the last byte and starting its response. This delay avoids conflicts on the serial line when the RS485 interface that is used has not been pre-set for automatic Tx/Rx switching. The parameter only concerns the use of the standard RS485 serial line.

Example: if the delay in Tx/Rx switching on the master is a maximum of 20ms, the Ser answer delay parameter must be set to at least 20ms: 22ms

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.1.6	3808	Serial swap data		BIT		0	0	1	ERW	FVS

This parameter enables the exchange of the reading of the High and Low parts of the words for FLOAT, UINT32, INT32 type parameters when using the Modbus protocol.

23.2 – COMMUNICATION/FIELDBUS CONFIG

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.1	4000	Fieldbus type		ENUM		Off	0	5	RW	FVS

Setting of the type of fieldbus to be used.

- 0** Off
- 1** CanOpen
- 2** DeviceNet
- 3** Profibus
- 10** DS402
- 30** Profidrive
- 40** Rte

If set to **0** no fieldbus is selected.
 If set to **1** the CanOpen fieldbus profile is selected.
 If set to **2** the ProfiBus-DP fieldbus profile is selected.
 If set to **3** the DeviceNet fieldbus profile is selected.
 If set to **10** the DS402 fieldbus is selected.
 If set to **30** the Profidrive fieldbus is selected.
 If set to **40** the Real Time Ethernet fieldbus is selected.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.2	4004	Fieldbus baudrate		ENUM		500k	0	12	RW	FVS

Setting of the communication network speed (Baud Rate).

- 0** Auto
- 1** 125k
- 2** 250k
- 3** 500k
- 4** 1M
- 5** 9600
- 6** 19200
- 7** 93750
- 8** 187.5k
- 9** 1.5M
- 10** 3M
- 11** 6M
- 12** 12M

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.3	4006	Fieldbus address		INT16		3	0	255	RW	FVS

Setting of the node address of the drive when connected to the network.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.4	4010	Fieldbus M->S enable		ENUM		Enable	0	1	ERWZ	FVS

Setting of fieldbus data updating.

- 0** Disable
- 1** Enable

If set to **0**, the possibility of sending commands and references from the drive PLC via the fieldbus is disabled.
 If set to **1** the possibility of sending commands and references from the drive PLC via the fieldbus is enabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.5	4012	Fieldbus alarm mode		INT32		0	0	1	ERWZ	FVS

Setting of the **Opt Bus Fault** alarm generation mode.

- 0 Off
- 1 On

If set to **0** the alarm is only generated if the drive is enabled.

If set to **1** the alarm is generated even with the drive disabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.6	4014	Fieldbus state		ENUM		Stop	0	9	R	FVS

The logic status of the fieldbus connection is displayed. The value depends on the type of bus that is used.

The following logic states are displayed if the CANopen or Rte fieldbus is selected:

- 0 Stop
- 1 PreOperational
- 2 Operational

The following logic states are displayed if the Profibus fieldbus is selected:

- 3 Error
- 4 WaitPRM
- 5 WaitCFG
- 6 DataExchange
- 7 DPErrors

The following logic states are displayed if the Rte fieldbus is selected:

- 8 SafeOp
- 9 Init

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.7	4398	RTE protocol		ENUM		None	0	6	ER	FVS

The Real Time Ethernet protocol implemented on the expansion card is displayed.

- 0 None
- 1 Ethercat
- 2 EthernetIP
- 3 GdNet
- 4 Profinet
- 5 ModbusTCP (Not available)
- 6 Powerlink (Not available)
- 107 Profidrive

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.2.8	5608	IP address		UINT32		0	0	4294967295	ER	FVS

Display of DCP address set via configuration of Profinet node.

23.3 – COMMUNICATION/FIELDBUS M2S

Configuration of input data

There are 16 groups of parameters, with the same structure, for configuring data to be exchanged cyclically with the fieldbus. Each group permits the exchange of a single datum, which corresponds to a single drive parameter.

The data written by the Master (a PLC, PC or control panel) to the Slave (the drive) can be configured in the COMMUNICATION/FIELDBUS M2S menu, hence the name of the M->S menu:

Parameter for setting input data:

It must contain a valid IPA corresponding to the parameter to be written, or 0 if sys (PAR 4022...4172 **Fieldbus M->Sn sys**) is **Fill** or **Mdplc**.

For *src* (Source) parameters, if you select PAR 4024 **Fieldbus M->S1 mon** in the corresponding enum, the value of parameter 4020 is automatically set to the IPA of the *src*.

E.g.: if PAR 4020 **Fieldbus M->S1 ipa** = 610 then PAR 610 **Ramp ref 1 src** = PAR 4020 **Fieldbus M->S1 ipa**.

For *src* parameters with a FB type other than 0, the datum coming to the fieldbus is not written in the enum selection but directly in the mon associated with the *src*.

E.g.: PAR 4020 **Fieldbus M->S1 ipa** = 610, the reference from the bus is sent to PAR 620 **Ramp ref 1 mon**, it does not modify the selection of PAR 610 **Ramp ref 1 src** which continues to be set to PAR 4020 **Fieldbus M->S1 ipa**.

If it contains a valid IPA and is forced to 0 the corresponding sys parameter assumes the value of Fill (16 or 32 depending on the previous setting), to guarantee that the structure of the exchanged data area is not changed.

PAR 4022 **Fieldbus M->S1 sys** Format of the datum to exchange

This parameter is automatically adjusted to the recommended value when the corresponding PAR 4020...4170 **Fieldbus M->Sn mon** is modified. Although the automatic value is user-definable, acceptable values depend on the datum IPA parameter: some combinations are not allowed and generate a configuration alarm at restart.

Values:

- **Not assigned:** if set to “**Not assigned**” this and all subsequent groups (regardless of their sys) are not part of the data exchanged, regardless of the IPA.
- **Fill16/32:** the datum is exchanged on the fieldbus but not written in any parameter.
- **Eu:** the datum is exchanged in 16-bit signed integer format with the parameter unit configured in the corresponding IPA or, in the case of *src* with the corresponding mon (e.g.: if PAR 4020 **Fieldbus M->S1 ipa** = PAR 610 **Ramp ref 1 src** and PAR 4022 **Fieldbus M->S1 sys** = Eu the datum is in rpm), multiplied by div. This setting is only possible for some parameters. See the table of FBUS types in the list of parameters. For these parameters the datum is exchanged every ms.
- **Eu_float :** Eu_float: same as Eu, but the datum is in floating point 32-bit IEEE754 single precision format.
- **Count16/32:** the datum is exchanged in internal units (see scaling table) every ms (e.g.: if PAR 4020 **Fieldbus M->S1 ipa** = 610, PAR 610 **Ramp ref 1 src** and PAR 4022 **Fieldbus M->S1 sys** = Count16 the datum is scaled so that a value of 0x4000 produces a reference equal to PAR 680 **Full scale speed**). This setting is only possible for some parameters. See the table of FBUS types in the list of parameters: if the field is empty Count cannot be set in the parameter. Some parameters permit the use of Count16 (usually values in which there is no need to exchange the least significant 16 bits) and Count32, according to the following rule: if FBUS = 32bit only Count32 can be set, if 16hi or 16lo Count32 and Count16 can both be set, indicating which word of the parameter is actually used. If Count32 is used and the internal type of the parameter is FLOAT the datum must be exchanged in floating point IEEE754 single precision format, otherwise as an integer (signed or unsigned, again according to the internal type).
- **MdPlc16/32:** this indicates that the datum is for use by the MdPlc application, which will use the value of PAR 4024...4174 **Fieldbus M->Sn mon** accordingly. If set to MdPlc16 the 16 bits of the low part of the mon are exchanged, if set to MdPlc32 all 32 bits are exchanged. All this applies if PAR 4020...4170 **Fieldbus M->Sn mon** = 0 or = at “corresponding **Fieldbus M->Sn mon**” (for example P.4020 = 4024), otherwise it behaves in the same way as Count.
- **Par16/32:** this is the default setting for all parameters with FB type empty so that data cannot be exchanged at 1 ms and the datum is updated in background. The datum format depends on the format of the parameter and the setting: with Par16 the datum is a 16-bit integer (signed or unsigned, according to the external type of the parameter) with the same unit of measure as the selected parameter (multiplied by div); Par16 is only available if the parameter is not actually a 32-bit one (e.g. it is not possible for iPad and Compare). With Par32 the format is float if the external type of the parameter is float, otherwise it is integer, always with the unit of the parameter. Parameters with FB type not empty can also be exchanged as PAR, according to the same rules listed above.

If using the CANopen fieldbus, the sys is also used to structure the data area in 8-byte PDOs. The PDOs are created

starting from the first group and it is necessary to guarantee that the data are contained in the PDO. Therefore, for example, a setting with PAR 4022 Fieldbus M->S1 sys = Count32, PAR 4032 Fieldbus M->S2 sys = Count16, PAR 4042 Sys M->S3 Fieldbus = Count32 is not valid, as the datum in group 3 would straddle the first two 2 PDOs. In these cases, shorter PDOs can be generated by using the Count setting with IPA 0 (in the example PAR 4040 **IPA M->S3 Fieldbus** = 0, PAR 4042 **Fieldbus M->S3 sys** = Count16, PAR 4050 **Fieldbus M->S4 ipa** = IPA of the parameter that was previously in 3 and PAR 4052 **Fieldbus M->S4 sys** = Count32, thus using a first PDO with 6 bytes), or by creating unused areas in the PDO using Fill (the PDO has a size of 8 bytes but the last word is not used).

If the data cannot be mapped in the PDOs, a specific alarm is generated at startup, indicating the group with the problem. Note that this only applies to CANopen and DS402. For the other fieldbuses the exchange area is contiguous with a max size of 16 words (14 for DeviceNet).

PAR 4024 Fieldbus M->S1 mon Monitor of datum coming from the master

This is the value, already scaled in internal counts, of the datum arriving from the master. If, for example, a value equal to PAR 680 **Full scale speed** is sent to PAR 610 **Ramp ref 1 src** in rpm, the internal value is 0x40000000 = 1073741824. The scaling also includes the division of the div parameter.

PAR 4026 Fieldbus M->S1 div Divider to apply to the parameter

This can only be used for sys = Eu or Par. It divides the incoming datum by the value entered: this makes it possible to increase the resolution of the datum. For example, if IPA = PAR 610 **Ramp ref 1 src**, sys is automatically set to Eu. When div = 10 is entered, the Master must send the datum in rpm multiplied by 10, for example to send a reference equal to 100.5 rpm the datum exchanged on the bus is 1005: the resolution is therefore in tenths of a degree. Before entering a value, it is important to consider the maximum value of the datum exchanged, to make sure it can be contained in a 16-bit integer (in the example, the maximum possible speed is 3276.7 rpm).

Use

This group of parameters is repeated 16 times, making it possible to configure up to 16 input data, but also bearing in mind the maximum limit of 16 words in all (14 for DeviceNet). The total number of configurable data thus also depends on the format, whether 16 or 32-bit, according to the above rules for sys.

The drive only implements the parameters in the COMMUNICATION/FIELDBUS M2S menu at startup. Once set, they must therefore be saved and the drive restarted (this procedure is not necessary for values set via dynamic mapping by the master, currently only supported by CANopen and Ethercat). The data are processed in order from 1 to the first with sys = **Not assigned**: depending on the configuration, an area for exchanging data with the fieldbus is created, the size and composition of which are clearly-defined.

If the data entered are not consistent (for example if sys is set as Eu or Count for a parameter that does not support these, or set to 16-bit for a parameter that can only be 32, or if the IPA does not exist, or if the PDO is not the right size, etc.) alarm "[17] **Opt Bus fault**" is generated with a subcode indicating the type of problem and group in which it occurred (code meanings are described in the Interface page in Menu/FIELDBUS WORDS MAP/M->S in Gf_eX-press).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.3.1	4020	Fieldbus M->S1 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.5	4030	Fieldbus M->S2 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.9	4040	Fieldbus M->S3 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.13	4050	Fieldbus M->S4 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.17	4060	Fieldbus M->S5 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.21	4070	Fieldbus M->S6 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.25	4080	Fieldbus M->S7 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.29	4090	Fieldbus M->S8 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.33	4100	Fieldbus M->S9 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.37	4110	Fieldbus M->S10 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.41	4120	Fieldbus M->S11 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.45	4130	Fieldbus M->S12 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.49	4140	Fieldbus M->S13 ipa		FBM2SIPA		0	0	20000	RW	FVS

23.3.53	4150	Fieldbus M->S14 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.3.57	4160	Fieldbus M->S15 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.3.61	4170	Fieldbus M->S16 ipa	FBM2SIPA	0	0	20000	RW	FVS

Setting of the parameter to associate with the bus channel. The default setting is 0, which means channel not active.

If the parameter to be connected is a **sorg** (source), the channel and parameter can also be associated by modifying the **sorg** parameter in its menu.

When setting a parameter, the format is also automatically set in the sys parameter.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.3.2	4022	Fieldbus M->S1 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.6	4032	Fieldbus M->S2 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.10	4042	Fieldbus M->S3 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.14	4052	Fieldbus M->S4 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.18	4062	Fieldbus M->S5 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.22	4072	Fieldbus M->S6 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.26	4082	Fieldbus M->S7 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.30	4092	Fieldbus M->S8 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.34	4102	Fieldbus M->S9 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.38	4112	Fieldbus M->S10 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.42	4122	Fieldbus M->S11 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.46	4132	Fieldbus M->S12 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.50	4142	Fieldbus M->S13 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.54	4152	Fieldbus M->S14 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.58	4162	Fieldbus M->S15 sys		ENUM		Not assigned	0	10	RW	FVS
23.3.62	4172	Fieldbus M->S16 sys		ENUM		Not assigned	0	10	RW	FVS

Setting of the format of the datum received on the channel. When the src parameter is programmed, the format is automatically programmed on the relative sys. If the src parameter is reset to null, the format does not change. The value of the format can be selected from the following list, according to the parameter selected as the source:

- 0** Not assigned
- 1** Count 16
- 2** Count 32
- 3** Fill 16
- 4** Fill 32
- 5** Mdplc 16
- 6** Mdplc 32
- 7** Eu
- 8** Eu float
- 9** Par 16
- 10** Par 32

If set to **0** the channel is not assigned.

If set to **1** the datum is assigned a 16-bit count.

If set to **2** the datum is assigned a 32-bit count.

If set to **3** 16 bits on the channel are reserved for the datum, not used.

If set to **4** 32 bits on the channel are reserved for the datum, not used.

If set to **5** the datum is assigned a 16-bit count used by MDPLC.

If set to **6** the datum is assigned a 32-bit count used by MDPLC.

If set to **7** the datum is assigned engineering units on a 16-bit integer.

If set to **8** the datum is assigned engineering units on a 32-bit integer.

If set to **9**, the datum is assigned a 16-bit integer engineering unit format not in real time (5-10ms)

If set to **10** the datum is assigned a 32-bit integer engineering unit format or float format if the associated parameter is a float-type parameter not in real time (5-10ms)

Note! If the sys parameter is **not assigned**, none of the subsequent fieldbus channels are read, even if programmed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.3.3	4024	Fieldbus M->S1 mon		INT32	16	0	0	0	ERW	FVS
23.3.7	4034	Fieldbus M->S2 mon		INT32	16	0	0	0	ERW	FVS
23.3.11	4044	Fieldbus M->S3 mon		INT32	16	0	0	0	ERW	FVS
23.3.15	4054	Fieldbus M->S4 mon		INT32	16	0	0	0	ERW	FVS
23.3.19	4064	Fieldbus M->S5 mon		INT32	16	0	0	0	ERW	FVS
23.3.23	4074	Fieldbus M->S6 mon		INT32	16	0	0	0	ERW	FVS
23.3.27	4084	Fieldbus M->S7 mon		INT32	16	0	0	0	ERW	FVS
23.3.31	4094	Fieldbus M->S8 mon		INT32	16	0	0	0	ERW	FVS
23.3.35	4104	Fieldbus M->S9 mon		INT32	16	0	0	0	ERW	FVS
23.3.39	4114	Fieldbus M->S10 mon		INT32	16	0	0	0	ERW	FVS
23.3.43	4124	Fieldbus M->S11 mon		INT32	16	0	0	0	ERW	FVS
23.3.47	4134	Fieldbus M->S12 mon		INT32	16	0	0	0	ERW	FVS
23.3.51	4144	Fieldbus M->S13 mon		INT32	16	0	0	0	ERW	FVS
23.3.55	4154	Fieldbus M->S14 mon		INT32	16	0	0	0	ERW	FVS
23.3.59	4164	Fieldbus M->S15 mon		INT32	16	0	0	0	ERW	FVS
23.3.63	4174	Fieldbus M->S16 mon		INT32	16	0	0	0	ERW	FVS

The value received from the bus is displayed. This parameter must be associated with the src parameter to enable the **M->S** channel.

The user may modify the **M->S** and by **S->M** sys parameters. The consistency of the sys with the parameter assigned to the channel is checked.

A Fieldbus M->S X Mon parameter can only be assigned to a single "src". If assigned to more than one src, an error signal is generated during fieldbus initialization.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.3.4	4026	Fieldbus M->S1 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.8	4036	Fieldbus M->S2 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.12	4046	Fieldbus M->S3 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.16	4056	Fieldbus M->S4 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.20	4066	Fieldbus M->S5 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.24	4076	Fieldbus M->S6 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.28	4086	Fieldbus M->S7 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.32	4096	Fieldbus M->S8 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.36	4106	Fieldbus M->S9 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.40	4116	Fieldbus M->S10 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.44	4126	Fieldbus M->S11 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.48	4136	Fieldbus M->S12 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.52	4146	Fieldbus M->S13 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.56	4154	Fieldbus M->S14 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.60	4166	Fieldbus M->S15 div		FLOAT		1.0	1.0	1000.0	ERW	FVS

23.3.64 4176 Fieldbus M->S16 div FLOAT 1.0 1.0 1000.0 ERW FVS

The **Div M->Sx fieldbus** parameters can be used to increase the resolution of the datum sent on the bus to the drive in the corresponding channel in EU and EU_float exchange mode. The parameter value is used by the drive as the divider of the incoming datum, so that a number with decimal digits can be transferred.

N.B.: You must check the size in bits of the datum that is sent to make sure that the maximum value in bits fits in a 16-bit integer. For example, if specifying the divider as “Fieldbus M->Sn div” = 1000, the maximum value that can be used for the exchanged datum is 32.768 (32768/1000).

Example: **Div M->Sx fieldbus = 10, M->S1 fieldbus par = Ramp ref src 1, Sys M->S1 fieldbus = Eu.** If the PLC sends the decimal value 1000 on the first word the value of **ramp ref 1** on the drive is 1000/10 = 100.

23.4 – COMMUNICATION/FIELDBUS S2M

Configuration of output data

The data read by the Master (a PLC, PC or control panel) sent by the slave (the drive) can be configured in the COMMUNICATION/FIELDBUS S2M menu.

Since the functions of the 16 groups are similar to those of the COMMUNICATION/FIELDBUS S2M menu, only the differences are listed here:

PAR 4180 Fieldbus S->M1 ipa: unlike with M->S, the src are not managed. The IPA therefore always refers to the parameter that is entered (e.g. to monitor ramp 1 input I must select **PAR 620 Ramp ref 1 mon** whereas if I select **PAR 610 Ramp ref 1 src** I would read the selection of the enum of that src).

Moreover, with sys = MdPlc16/32, you cannot enter IPA 0 but must enter the IPA of the corresponding dig, for the first group **PAR 4184 Dig Fieldbus S->M1**, etc.), the MdPlc application then writes a value in this parameter, which is sent to the bus in 16 or 32-bit format according to the sys.

If you enter 0 when the IPA was set to a value other than zero, the sys is automatically set to Fill16 or 32, to guarantee the structure of the data exchange area.

PAR 4182 Fieldbus S->M1 sys : the only difference regards the MdPlc16/32 setting, as explained above, to send all 32 bits or just the low word of the corresponding dig.

PAR 4186 Fieldbus S->M1 mul: this works symmetrically with respect to M>S. In this case a multiplier is applied to increase the resolution of the output datum (for Eu and Par only). For example, if **PAR 4180 Fieldbus S->M1 ipa = PAR 260 Motor speed**, **PAR 4182 Fieldbus S->M1 sys = Eu**, **PAR 4186 Fieldbus S->M1 mul = 10** the datum sent to the bus is in rpm multiplied by 10: if the drive turns at 100.5 rpm the master receives a value equal to 1005.

PAR 4184 Dig Fieldbus S->M1: there are no monitors for output data, the digs send a fixed datum to the bus (with the sys set to Count32) or for the MdPlc application, which writes a value in these parameters (with sys set to MdPlc16/32).

The groups are processed in order at startup as for M>S. If there are any configuration errors, alarm “[17] **Opt Bus fault**” is generated with a subcode indicating the type of problem and the group in which it occurred (see the S->M page in Gf_eXpress for the meaning of the code).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.4.1	4180	Fieldbus S->M1 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.5	4190	Fieldbus S->M2 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.9	4200	Fieldbus S->M3 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.13	4210	Fieldbus S->M4 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.17	4220	Fieldbus S->M5 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.21	4230	Fieldbus S->M6 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.25	4240	Fieldbus S->M7 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.29	4250	Fieldbus S->M8 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.4.33	4260	Fieldbus S->M9 ipa		FBM2SIPA		0	0	20000	RW	FVS

23.4.37	4270	Fieldbus S->M10 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.4.41	4280	Fieldbus S->M11 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.4.45	4290	Fieldbus S->M12 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.4.49	4300	Fieldbus S->M13 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.4.53	4310	Fieldbus S->M14 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.4.57	4320	Fieldbus S->M15 ipa	FBM2SIPA	0	0	20000	RW	FVS
23.4.61	4330	Fieldbus S->M16 ipa	FBM2SIPA	0	0	20000	RW	FVS

Setting of the parameter to associate with the bus channel. The default setting is 0, which means channel not active.
When setting a parameter, the format is also automatically set in the sys parameter

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.4.2	4182	Fieldbus S->M1 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.6	4192	Fieldbus S->M2 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.10	4202	Fieldbus S->M3 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.14	4212	Fieldbus S->M4 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.18	4222	Fieldbus S->M5 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.22	4232	Fieldbus S->M6 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.26	4242	Fieldbus S->M7 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.30	4252	Fieldbus S->M8 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.34	4262	Fieldbus S->M9 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.38	4272	Fieldbus S->M10 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.42	4282	Fieldbus S->M11 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.46	4292	Fieldbus S->M12 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.50	4302	Fieldbus S->M13 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.54	4312	Fieldbus S->M14 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.58	4322	Fieldbus S->M15 sys		ENUM		Not assigned	0	10	RW	FVS
23.4.62	4332	Fieldbus S->M16 sys		ENUM		Not assigned	0	10	RW	FVS

When setting the sorg parameter the format is automatically set on the relative **sys**. If **sorg** is set to **null**, the data format does not change. The value of the format can be selected from the following list, according to the parameter selected as the source:

- 0 Not assigned
- 1 Count 16
- 2 Count 32
- 3 Fill 16
- 4 Fill 32
- 5 Mdplc 16
- 6 Mdplc 32
- 7 Eu
- 8 Eu float
- 9 Par 16
- 10 Par 32

If set to **0** the channel is not assigned.

If set to **1** the datum is assigned a 16-bit count.

If set to **2** the datum is assigned a 32-bit count.

If set to **3** 16 bits on the channel are reserved for the datum, not used.

If set to **4** 32 bits on the channel are reserved for the datum, not used.

If set to **5** the datum is assigned a 16-bit count used by MDPLC.

If set to **6** the datum is assigned a 32-bit count used by MDPLC.

If set to **7** the datum is assigned engineering units on a 16-bit integer.

If set to **8** the datum is assigned engineering units on a 32-bit integer.

If set to **9**, the datum is assigned a 16-bit integer engineering unit format not in real time (5-10ms)

If set to **10** the datum is assigned a 32-bit integer engineering unit format or float format if the associated parameter is a float-type parameter not in real time (5-10ms)

Note ! If the sys parameter is **not assigned**, none of the subsequent channels are transferred to the fieldbus, even if programmed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.4.3	4184	Dig Fieldbus S->M1		INT32	16	0	0	0	ERW	FVS
23.4.7	4194	Dig Fieldbus S->M2		INT32	16	0	0	0	ERW	FVS
23.4.11	4204	Dig Fieldbus S->M3		INT32	16	0	0	0	ERW	FVS
23.4.15	4214	Dig Fieldbus S->M4		INT32	16	0	0	0	ERW	FVS
23.4.19	4224	Dig Fieldbus S->M5		INT32	16	0	0	0	ERW	FVS
23.4.23	4234	Dig Fieldbus S->M6		INT32	16	0	0	0	ERW	FVS
23.4.27	4244	Dig Fieldbus S->M7		INT32	16	0	0	0	ERW	FVS
23.4.31	4254	Dig Fieldbus S->M8		INT32	16	0	0	0	ERW	FVS
23.4.35	4264	Dig Fieldbus S->M9		INT32	16	0	0	0	ERW	FVS
23.4.39	4274	Dig Fieldbus S->M10		INT32	16	0	0	0	ERW	FVS
23.4.43	4284	Dig Fieldbus S->M11		INT32	16	0	0	0	ERW	FVS
23.4.47	4294	Dig Fieldbus S->M12		INT32	16	0	0	0	ERW	FVS
23.4.51	4304	Dig Fieldbus S->M13		INT32	16	0	0	0	ERW	FVS
23.4.55	4314	Dig Fieldbus S->M14		INT32	16	0	0	0	ERW	FVS
23.4.59	4324	Dig Fieldbus S->M15		INT32	16	0	0	0	ERW	FVS
23.4.63	4334	Dig Fieldbus S->M16		INT32	16	0	0	0	ERW	FVS

If associated with the relative src, the value of this parameter is sent to the bus.

The user may modify the M->S and by S->M sys parameters. The consistency of the sys with the parameter assigned to the channel is checked.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.4.4	4186	Fieldbus S->M1 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.8	4196	Fieldbus S->M2 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.12	4206	Fieldbus S->M3 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.16	4216	Fieldbus S->M4 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.20	4226	Fieldbus S->M5 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.24	4236	Fieldbus S->M6 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.28	4246	Fieldbus S->M7 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.32	4256	Fieldbus S->M8 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.36	4266	Fieldbus S->M9 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.40	4276	Fieldbus S->M10 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.44	4286	Fieldbus S->M11 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.48	4296	Fieldbus S->M12 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.52	4306	Fieldbus S->M13 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.56	4316	Fieldbus S->M14 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.60	4326	Fieldbus S->M15 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.64	4336	Fieldbus S->M16 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS

The “**Fieldbus S->Mx mul**” parameters are multipliers that the drive applies to the datum before sending it to the bus. It is therefore possible to increase the resolution of some values read in EU and EU_float mode, also

using decimal digits.

N.B.: The drive does not check that the multiplied parameter expressed in bits fits in a 16-bit integer. You must make sure that the multiplier is compatible with the maximum value of the exchanged parameter and that it does not exceed the maximum size of 32768.

Example: **Fieldbus S->Mx mul = 10, S->M1 fieldbus par = Motor speed, Sys S->M1 fieldbus = Eu.**

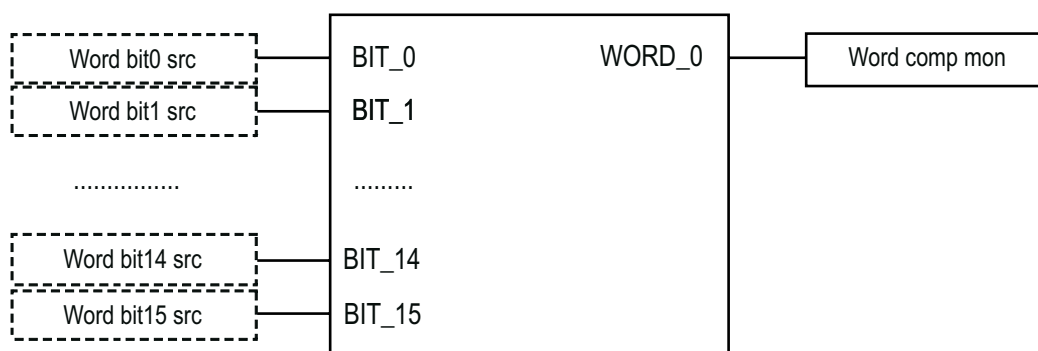
If the motor is running at 100 rpm, the PLC reads the value $100 * 10 = 1000$ on the first word that is exchanged.

23.5 – COMMUNICATION/WORD COMP

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.5.1	4400	Word bit0 src		LINK	16	6000	0	16384	ERW	FVS
23.5.2	4402	Word bit1 src		LINK	16	6000	0	16384	ERW	FVS
23.5.3	4404	Word bit2 src		LINK	16	6000	0	16384	ERW	FVS
23.5.4	4406	Word bit3 src		LINK	16	6000	0	16384	ERW	FVS
23.5.5	4408	Word bit4 src		LINK	16	6000	0	16384	ERW	FVS
23.5.6	4410	Word bit5 src		LINK	16	6000	0	16384	ERW	FVS
23.5.7	4412	Word bit6 src		LINK	16	6000	0	16384	ERW	FVS
23.5.8	4414	Word bit7 src		LINK	16	6000	0	16384	ERW	FVS
23.5.9	4416	Word bit8 src		LINK	16	6000	0	16384	ERW	FVS
23.5.10	4418	Word bit9 src		LINK	16	6000	0	16384	ERW	FVS
23.5.11	4420	Word bit10 src		LINK	16	6000	0	16384	ERW	FVS
23.5.12	4422	Word bit11 src		LINK	16	6000	0	16384	ERW	FVS
23.5.13	4424	Word bit12 src		LINK	16	6000	0	16384	ERW	FVS
23.5.14	4426	Word bit13 src		LINK	16	6000	0	16384	ERW	FVS
23.5.15	4428	Word bit14 src		LINK	16	6000	0	16384	ERW	FVS
23.5.16	4430	Word bit15 src		LINK	16	6000	0	16384	ERW	FVS

Selection of the origin (source) of the signal to be used for coding in **Word comp**. This function allows the user to compose a single word composed of 16 signals, each of which can be selected from among those listed in the “**L_DIGSEL1**” selection list.

The values of the sectioned sizes are converted into a single word.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.5.17	4432	Word comp mon		UINT32	16	0	0	0	ER	FVS

The hexadecimal value of the Word comp output is displayed.

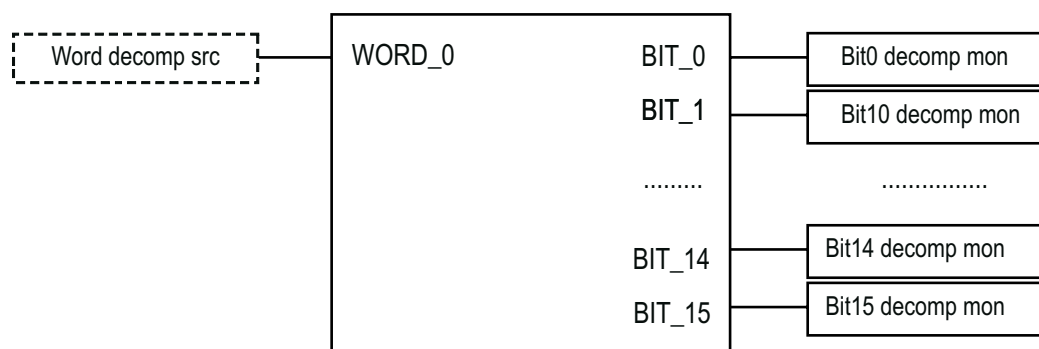
23.6 – COMMUNICATION/WORD DECOMP

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.6.1	4450	Dig word decomp		UINT32	16	0	0	0	ERW	FVS

Setting of the digital input decoded by the “**Word decomp**” block.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.6.2	4452	Word decomp src		LINK	16	4450	0	16384	ERW	FVS

Selection of the origin (source) of the word to be decoded by the “**Word decomp**” block. Each bit that is part of the word to be decoded is associated with the output channel of the “**Word decomp**” block. The variables that can be used for this function can be selected from among those listed in the “**L_WDECOMP**” selection list.



Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.6.3	4454	Bit0 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.4	4456	Bit1 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.5	4458	Bit2 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.6	4460	Bit3 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.7	4462	Bit4 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.8	4464	Bit5 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.9	4466	Bit6 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.10	4468	Bit7 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.11	4470	Bit8 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.12	4472	Bit9 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.13	4474	Bit10 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.14	4476	Bit11 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.15	4478	Bit12 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.16	4480	Bit13 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.17	4482	Bit14 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.18	4484	Bit15 decomp mon		BIT	16	0	0	1	ER	FVS

The single bits that make up the selected word are displayed.

23.7 - COMMUNICATION/EXTERNAL IO

The optional EXP-FL-XCAN-ADV card (generally inserted in slot 1) allows the number of I/Os managed by the drive to be increased, using an external device. Communication with the external device is performed via CAN using the “DS401 Device profile for generic IO modules”.

For more details see manual 1S5F32_EXP-FL-XCAN-ADV.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.7.1	5480	External IO enable		ENUM		Disable	0	1	ERW	FVS

This parameter is used to enable or disable communication between the EXP-FL-XCAN-ADV card and the external device.

0 Disable

1 Enable

Communication is disabled in the default configuration. Communication can be enabled by setting **Enable** and saving the parameters. When the drive is re-started the EXP-FL-XCAN-ADV card, if installed, is recognised. The communication is started and the external I/Os are managed. With the “**External IO enable**” set to **Disable** the EXP-D6A4R1-ADV can be managed, if installed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.7.2	5482	External IO info		UINT32		0	0	4294967295	ER	FVS

This parameter displays the number of I/O resources read by the module.
It is a 32-bit parameter made up as follows:

Uint32			
Uint16 High		Uint16 Low	
Uint8 High	Uint8 Low	Uint8 High	Uint8 Low
N. of AO	N. of AI	N. of DO	N. of DI

The parameter is displayed in HEX format.

E.g.:

PAR 5482	N. of AO	N. of AI	N. of DO	N. of DI
0x02041020 33820704	0x02 2	0x04 4	0x10 16	0x20 32
0x00000810 2064	0x00 0	0x00 0	0x08 8	0x10 16

If the configuration that is read has changed (compared to the last configuration saved or read) the drive displays and message requires the intervention of the operator in order to proceed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.7.3	5484	External IO state		BIT	16	0	0	1	ER	FVS

This parameter displays the communication state

0 Off

1 On

This parameter is set to 1 (on) if the communication state is operational.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.7.4	5486	External IO failcode		UINT32		0	0	4294967295	ER	FVS

If an “Ext I/O fault” occurs due to the **Emergency slave subcode 255..65535** alarm message, this parameter displays 4 of the 5 InfoBytes of the “Emergency” message.

See the slave manual for information about the meaning of the InfoBytes in the Emergency message (CAN slave communication module).

See Chapter C - “ExtIO fault alarm”.

23.8 - COMMUNICATION/FAST LINK

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.1	5702	FL address		UINT16		0	0	16	ERWZ	FVS

This parameter is used to enable the FastLink function and select whether the drive is to be the master or slave. If used as a slave device, the address can be selected.

0 = Disabled

1 = Master

2 = Slave 1

X = Slave X-1

16 = Slave 16

For the Pwm synchronisation to function properly, the address of the slave drive must be configured in the same order as the physical connection.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.2	5818	FL bidirectional		ENUM		Enable	0	1	ERWZ	FVS

Enables/disables bi-directional Fast Link mode.

0 Disable

1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.3	5820	FL N of slave		UINT16		0	0	32767	ERWZ	FVS

It is a parameter related only to the master drive and it indicates which slave drives need to be interrogated.

The encoding data used is an integer having set to 1 the bit corresponding to the slaves that need to be interrogated:

- bit 0 (least significant bit)) is related to slave with address 2

- bit 1 is related to the slave with address 3

- ...

- ...until to the slave with address 16.

For example, if need to be interrogated slaves with address 2 and address 5, the value will be 9 (1001 binary).

If one or more slaves are not connected to the drops giving no answer, it will produce a fast link alarm on the master drive. Fast link alarm on the master will produce communication error to all the slaves connected.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.4	5710	FL sync slave type		ENUM		Pwm&Ctrl	0	2	ERWZ	FVS

This parameter is ineffective on the master drive.

On the slave drive this parameter is used to enable the function for generating Pwm signals that are synchronised with the Pwm signals of the master. It is also possible to enable the function for executing control tasks synchronised with execution of control tasks of the master.

0 Off Fastlink transfers information between the drives.

1 Pwm The Fastlink transfers information between the drives and the function for synchronising the generation of Pwm signals with the Pwm signals of the master is enabled. The variables in the 11) Updating times for the various functions table are synchronised at 125 us

2 Pwm&Ctrl The Fastlink transfers information between the drives, the function for synchronising the generation of Pwm signals with the Pwm signals of the master is enabled and the function for synchronising control tasks with the control tasks of the master is enabled. The variables in table "Updating times for the various functions" (on manual 1S5F32_EXP-FL-XCAN-ADV) and the MDPLC tasks are also synchronised to 1 ms and 8 ms.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.5	5712	FL N Fwd slave chg		UINT16		0	0	4	ERWZ	FVS

There are two possible operation modes.

In the first, the master sends the data frame to the first slave. The first slave takes all the data in the frame and sends the same frame to the next slave without making any changes. The same sequence is repeated by all the slave drives.

In the second, the master sends the data frame to the first slave. The first slave takes all the data in the frame, replaces part of the data and then sends the frame to the next slave drive. The same sequence is repeated by all the slave drives.

This parameter is ineffective on the master drive.

On the slave drive this parameter is used to configure the amount of data to be replaced in the data frame.

FL N Fw slave change	Information replaced
0	None
1	FL Fw 1
2	FL Fw 1, FL Fw 2

3	FL Fw 1, FL Fw 2, FL Fw 3
4	FL Fw 1, FL Fw 2, FL Fw 3, FL Fw 4

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.6	5714	FL fault enable src		LINK	16	6002	0	16384	ERW	FVS

This parameter is used to select the origin (source) of the **FL fault enable** signal.

The signal to be associated with this function can be selected from the "**L_DIGSEL1**" selection list.

0 FL fault enable not active (No FastLink alarm signal)

1 FL fault enable active (FastLink alarm signal)

When the drive detects a FastLink fault, it prepares to trigger a "FastLink fault" alarm.

This command is used to select whether an alarm is generated when a fault is detected.

Alarm generation is enabled in the default configuration.

The configuration of the "**FL fault enable src**" parameter can be changed to control the phases in which alarm generation is enabled.

For example, by connecting the "**FL fault enable src**" parameter to "**Enable state mon**" you can enable generation of the "FastLink fault" alarm in the phase when the drive is enabled.

In systems where drive the drives are not powered-off simultaneously, some drives detect a FastLink fault and generate a FastLink alarm.

This parameter is used to disable the alarm at power-off by connecting the "**FL fault enable src**" parameter to "**Enable state mon**".

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.7	5730	FL Fwd 1 src		LINK	16/32	6000	0	16384	ERW	FVS
23.8.8	5732	FL Fwd 2 src		LINK	16/32	6000	0	16384	ERW	FVS
23.8.9	5734	FL Fwd 3 src		LINK	16/32	6000	0	16384	ERW	FVS
23.8.10	5736	FL Fwd 4 src		LINK	16/32	6000	0	16384	ERW	FVS

This parameter is used to select the origin (source) of the **FL Fw 1 src** signal.

The signal to be associated with this function can be selected from the "**L_FLWORD**" selection list.

On the drive configured as the master, these parameters are used to select the data to be sent to the first slave.

On drives configured as slaves, these paramters are used to select the data that the slave must include in the data frame to replace the data received from the previous drive.

Replacement is disabled in the default configuration. It can be enabled with the PAR 5712 "**FL N Fwd slave chg**" parameter.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.11	5830	FL Rev 1 src		LINK	16/32	6000	0	16384	ERW	FVS
23.8.12	5832	FL Rev 2 src		LINK	16/32	6000	0	16384	ERW	FVS

Parameter significant only for Slave drive, indicates what data to insert in first word to be sent to Master drive when Slave is interrogated. Selectable values are shown on the L_FLWORD list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.13	5750	FL Fwd 1 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.14	5752	FL Fwd 2 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.15	5754	FL Fwd 3 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.16	5756	FL Fwd 4 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.17	5758	FL Fwd 5 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.18	5760	FL Fwd 6 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.19	5762	FL Fwd 7 mon		INT32	32	0	0	2 ^ 32	ER	FVS
23.8.20	5764	FL Fwd 8 mon		INT32	32	0	0	2 ^ 32	ER	FVS

These parameters are not used on the master drive.

On the slave drive these parameters show the value received from the previous drive. The “Inv” parameters enable the value received to be used with the opposite sign, without changing any of the data sent to subsequent slaves.

These parameters are available in the src analog parameter selection lists.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.21	5850	FL Rev 1 mon		INT32	32	0	0	0	ER	FVS
23.8.22	5852	FL Rev 2 mon		INT32	32	0	0	0	ER	FVS
23.8.23	5854	FL Rev 3 mon		INT32	32	0	0	0	ER	FVS
23.8.24	5856	FL Rev 4 mon		INT32	32	0	0	0	ER	FVS

Display of data selected via parameters **FL Rev X Slave sel** corresponding (PAR 5822 ... 5828).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.25	5822	FL Rev 1 slave sel		UINT16		0	0	31	ERWZ	FVS
23.8.26	5824	FL Rev 2 slave sel		UINT16		0	0	31	ERWZ	FVS
23.8.27	5826	FL Rev 3 slave sel		UINT16		0	0	31	ERWZ	FVS
23.8.28	5828	FL Rev 4 slave sel		UINT16		0	0	31	ERWZ	FVS

Parameter significant only for Master drive, indicates what data of which Slave drive to display in parameter **FL Rev X mon** (you can choose to display word 1 or 2 of a Slave with address from 2 to 16). The code used assigns the significance of the first word of the Slave at address 2 to value 0, value 1 for the first word of the Slave at address 3 14 first word of the Slave at address 16, 15 has no significance, 16 second word of Slave at address 2 ... 30 second word of Slave at address 16.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.29	5720	Sync slave mon		BIT	16	0	0	1	ER	FVS

This parameter is not significant on the master drive.

On the slave drives this parameter indicates the state of the function that enables Pwm signals to be synchronised with the Pwm signals of the master and execution of control tasks to be synchronised with execution of control tasks of the master.

0 Slave not synchronised

1 Slave synchronised

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
23.8.30	5722	FL fault code		UINT32		0	0	0	ER	FVS

This parameter is used to display the cause of the FastLink fault alarm.

See chapter C - FastLink Fault.

24 – ALARM CONFIG

In the **ALARM CONFIG** menu the type of effect any alarm signals have on the drive is determined:

- The alarm status is saved
- How must the drive react to the alarm signal?
- Auto restart
- Alarm reset

For some alarms, behaviour can be configured separately for each signal, while for the others the **Disable drive** is executed. Individual signals can also be sent to a programmable digital output.

<u>Activity</u>	Ignore	The alarm is not included in the list of alarms, it is not included in the alarm log, it is not signalled on the digital outputs, no drive commands are modified.
	Warning	The alarm is included in the list of alarms, it is included in the alarm log, it is signalled on the digital outputs, the First alarm information is updated, the Alarm enabled information is updated, no drive commands are modified.
	Disable drive	The alarm is included in the list of alarms, it is included in the alarm log, it is signalled on the digital outputs, the First alarm information is updated, the Alarm enabled information is updated, a command is sent to stop and disable the motor, which stops due to inertia.
	Stop	The alarm is included in the list of alarms, it is included in the alarm log, it is signalled on the digital outputs, the First alarm information is updated, the Alarm enabled information is updated, a Stop command is sent. When the zero speed is reached the drive is disabled. If Ramp control mode is enabled, the drive moves to the zero speed with the set ramp time; when the Speed delay 0 signal is activated the drive is disabled. If Speed control mode is enabled, the drive moves to the zero speed with the maximum current possible; when the Speed delay 0 signal is activated the drive is disabled. If Torque control mode is enabled, the drive moves to the zero speed with the time set by the load; when the Speed delay 0 signal is activated the drive is disabled.
	Fast stop	The alarm is included in the list of alarms, it is included in the alarm log, it is signalled on the digital outputs, the First alarm information is updated, the Alarm enabled information is updated, a Fast Stop command is sent. When the zero speed is reached the drive is disabled. If Ramp control mode is enabled, the drive moves to the zero speed with the set fast stop ramp time (deceleration time 3); when the Speed delay 0 signal is activated the drive is disabled. If Speed control mode is enabled, the drive moves to the zero speed with the maximum current possible; when the Speed delay 0 signal is activated the drive is disabled. If Torque control mode is enabled, the drive moves to the zero speed with the set load time; when the Speed delay 0 signal is activated the drive is disabled.

n alarms with Activity = Ignore or Warning can be enabled at the same time.

If an alarm with Activity = Stop or Fast Stop is enabled and another alarm with an Activity other than Ignore or Warning is enabled, the drive stops and is disabled.

Not all alarms allow the controlled stopping of the drive. The following table shows the possibility of setting the Activities for the individual alarm signals.

Alarm	Ignore	Warning	Disable drive	Stop	Fast stop
ExtFlt	✓	✓	✓	✓	✓
Motor OT	✓	✓	✓	✓	✓
Overspeed	✓	✓	✓	✓	✓
SpdRefLoss	✓	✓	✓	✓	✓
SpdFbkLoss	✓	✓	✓	✓	✓
Drive ovld	✓	✓	✓	✓	✓
Motor ovld	✓	✓	✓	✓	✓
Bres ovld	✓	✓	✓	✓	✓
HTsens	-	-	✓	✓	✓
InAir	✓	✓	✓	✓	✓
Desat	-	-	✓	-	-
IOVerC	-	-	✓	-	-
OverV	-	-	✓	-	-
UnderV	-	-	✓	-	-
PhLoss	✓	✓	✓	✓	✓
Bus option	✓	✓	✓	✓	✓
GroundFault thr	-	-	✓	-	-
Brake fault	✓	✓	✓	✓	✓
EXT IO	✓	✓	✓	✓	✓
FL fault	✓	✓	✓	✓	✓
Missing Motor phase	✓	✓	✓	✓	✓
Condensation (for ADV200-LC series only)	✓	✓	✓	✓	✓
An inpLoss	✓	✓	✓	✓	✓
UV Ride Thr	-	✓	-	-	-

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.1	4500	Fault reset src		LINK	16	1120	0	16384	RW	FVS

Selection of the origin (source) of the signal to be used for the command to reset the drive after an alarm. The terminal that can be used for this function can be selected from among those listed in the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.2	4502	ExtFlt src		LINK	16	6000	0	16384	RW	FVS

Selection of the origin (source) of the signal to be used as the input for the drive external fault alarm **ExtFlt**. The terminal that can be used for this function can be selected from among those listed in the “**L_DIGSEL2**” selection list.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.3	4504	ExtFlt activity		ENUM		Disable	0	4	RW	FVS

Setting of the behaviour of the drive in the event of an external fault alarm **ExtFlt**. This alarm indicates the intervention of a drive external protection.

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.4	4506	ExtFlt restart		ENUM		Disable	0	1	RW	FVS

Enabling of automatic restart after the external fault alarm **ExtFlt**

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.5	4508	ExtFlt restart time	ms	UINT16		1000	120	30000	RW	FVS
Setting of the time within which the External Fault alarm must be reset in order to perform automatic restart.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.6	4510	ExtFlt holdoff	ms	UINT16		0	0	10000	RW	FVS
Setting of the delay between the signalling of the external fault alarm ExtFlt and enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before blocking is enabled. If the alarm is removed within the set time, the drive will not indicate any alarm condition.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.7	4516	MotorOT pre activity		ENUM		Ignore	0	4	ERW	FVS
Manages activity from motor overtemperature prealarm.										
0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.8	4518	MotorOT pre thr	perc	UINT16		60	0	100	ERW	FVS
Represents the threshold, in % of the value set in IPA 4532 MotorOT thr , at which the motor overtemperature prealarm trips.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.9	4520	MotorOT src		LINK	16	6000	0	16384	RW	FVS
Selection of the origin (source) of the signal to be used for the motor overtemperature alarm MotorOT . The terminal that can be used for this function can be selected from among those listed in the “ L_DIGSEL2 ” selection list.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.10	4522	MotorOT activity		ENUM		Warning	0	4	RW	FVS
Setting of the behaviour of the drive in case of a motor overtemperature alarm MotorOT . This alarm indicates that the motor temperature is too high.										
0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.11	4524	MotorOT restart		ENUM		Disable	0	1	RW	FVS
Enabling of automatic restart after the motor overtemperature alarm MotorOT .										
0 Disable 1 Enable										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.12	4526	TMotorOT restart time	ms	UINT16		1000	120	30000	RW	FVS
Setting of the time within which the Motor Overtemperature alarm must be reset in order to perform automatic restart.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.13	4528	MotorOT holdoff	ms	UINT16		1000	0	30000	RW	FVS

Setting of the delay between the signalling of the motor overtemperature alarm **MotorOT** and enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before enabling the alarm. If the alarm is removed within the set time, the drive will not indicate any alarm condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.14	4530	MotorOT probe		ENUM		SRC	0	8	ERW	FVS

Selection of type of sensor for measuring external temperature. The following can be selected:

- 0 SRC alarm managed via IPA 4520 **MotorOT src**
- 1 Sens An1X alarm managed via **PT100/PT1000/Ni1000** read by input 1 expansion card (*)
- 2 Sens An2X alarm managed via **PT100/PT1000/Ni1000** read by input 2 expansion card (*)
- 3 KTY84 AnX alarm managed via **KTY84** read by dedicated input for cards (*)
- 4 PTC AnX alarm managed via **PTC** read by dedicated input for cards (*)
- 5 KTY84 An1 alarm managed via **KTY84** read by analog input 1 of control card
- 6 KTY84 An2 alarm managed via **KTY84** read by analog input 2 of control card
- 7 PTC An1 alarm managed via **PTC** read by analog input 1 of control card
- 8 PTC An2 alarm managed via **PTC** read by analog input 2 of control card
- 9 Klixon AnX alarm managed via **KLIXON** read by dedicated input for cards (*)
- 10 KTY84 An1X alarm managed via **KTY84** read by analog input 1 expansion card (*)
- 11 KTY84 An2X alarm managed via **KTY84** read by analog input 2 expansion card (*)
- 12 PTC An1X alarm managed via **PTC** read by analog input 1 expansion card (*)
- 13 PTC An2X alarm managed via **PTC** read by analog input 2 expansion card (*)

(*) = **EXP-IO-SENS-100-ADV, EXP-IO-SENS-1000-ADV.**

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.15	4514	MotorOT KTY84 unit		ENUM		ohm	0	1	ERW	FVS

It allows to select the activation “**MotorOT**” alarm threshold in ohm or degrees Celsius (°C):

- 0 ohm (IPA 4532 **MotorOT thr** and IPA 4536 **MotorOT mon** will be shown in ohm).
- 1 °C (IPA 4532 **MotorOT thr** and IPA 4536 **MotorOT mon** will be shown in °C).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.16	4532	MotorOT thr	(*)	UINT16		0	0	32767	ERW	FVS

Represents the resistance threshold at which the “**Motor OT**” alarm must trip.

To the IPA 4536 has been associated the “SysMotorOTmon” system variable and It is available for MDPLC application. This system variable is scaled for 2¹⁶ and it has been defined in Ohm or °C depending on the selection thru IPA 4514.

(*) The parameter is expressed in counts, ohms or °C depending on the type of sensor selected.

The parameter is expressed in Ohm when selecting PTC An1, PTC An2.

The parameter is expressed in Ohm or °C when selecting KTY84 An1, KTY84 An2.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.17	4536	MotorOT mon	(*)	INT16	16/32	0	0	32767	ER	FVS

Represents the measurement monitor of the sensor.

(*) The parameter is expressed in counts, ohms or °C depending on the type of sensor selected.

The parameter is expressed in Ohm when selecting PTC An1, PTC An2.

The parameter is expressed in Ohm or °C when selecting KTY84 An1, KTY84 An2.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.18	4540	Overspeed threshold	rpm	INT32		CALCI	0	CALCI	RW	FVS

Setting of the threshold above which the overspeed alarm **Overspeed** is enabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.19	4542	Overspeed activity		ENUM		Disable	0	4	RW	FVS
Setting of the behaviour of the drive in case of a motor overspeed alarm Overspeed. This alarm indicates that the motor speed has exceeded the threshold set in the Speed ref top lim and Speed ref bottom lim parameters in the COMMANDS menu. 0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.20	4544	Overspeed holdoff	ms	UINT16		0	0	5000	RW	FVS
Setting of the delay between the signalling of the motor overspeed alarm Overspeed and enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before enabling the alarm. If the alarm is removed within the set time, the drive will not indicate any alarm condition.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.21	4550	SpdRefLoss threshold	rpm	INT16		100	0	CALCI	RW	FVS
Setting of the threshold below which the speed reference loss alarm SpdRefLoss occurs.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.22	4552	SpdRefLoss activity		ENUM		Ignore	0	4	RW	FVS
Setting of the behaviour of the drive in case of a speed reference loss alarm SpdRefLoss. This alarm indicates that the difference between the speed regulator reference and the actual motor speed is more than 100 rpm. This alarm must be disabled (= 0 Ignore) when parameter 556 Control mode select is set to Torque (0) or when parameter 2354 is set to a value other than zero. 0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.23	4554	SpdRefLoss holdoff	ms	UINT16		1000	0	10000	RW	FV_
Setting of the delay between the signalling of the speed reference loss alarm condition SpdRefLoss and enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before enabling the alarm. If the alarm is removed within the set time, the drive will not indicate any alarm condition.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.24	4558	SpdRefLoss minThr en		BIT		0	0	1	ERW	FVS
Mode to enable the speed reference loss alarm over the entire motor speed range or based on Speed threshold 3 (IPA 970). If SpdRefLoss minThr en (IPA 4558) is set to "Off," the speed reference loss alarm enables because the difference between the speed regulate reference and current motor speed is higher than SpdRefLoss threshold (IPA 4550). If SpdRefLoss minThr en (IPA 4558) is set to "On," the following occurs: - If Speed thr 3 mon (IPA 976) is 0 (current speed below threshold), the drive checks the conditions of the speed reference loss alarm. - If Speed thr 3 mon (IPA 976) is 1 (current speed above threshold), the drive DOES NOT check the conditions of the speed reference loss alarm (alarm disabled).										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.25	4560	SpdFbkLoss activity		ENUM		Disable	0	4	RW	FV_
Setting of the behaviour of the drive in case of a speed feedback loss alarm SpdFbkLoss . This alarm indicates the loss of the encoder feedback signals.										
0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.26	4562	SpdFbkLoss holdoff	ms	UINT16		200	0	10000	RW	FVS
Setting of the delay between the signalling of the speed feedback loss alarm condition SpdFbkLoss and the enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before enabling the alarm. If the alarm is removed within the set time, the drive will not indicate any alarm condition.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.27	4564	SpdFbkLoss threshold	rpm	INT16		100	5	CALCI	RW	FVS
For SE (single ended) encoders and with parameters 2110 or 5110 = (3) Control A-B-SE.										
The Speed fbk loss [22] alarm control is enabled when the speed reference is higher than the value set in this parameter										
If using incremental digital encoders in single-ended mode, this parameter sets the limit above which the drive executes the action set with parameter 4560 SpdFbkLoss activity .										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.28	4570	Drive ovld activity		ENUM		Ignore	0	4	ERW	FVS
Setting of the behaviour of the drive in case of a drive overload alarm Drive ovld . This alarm indicates that the drive overload threshold has been reached.										
0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.29	4572	Motor ovld activity		ENUM		Warning	0	4	ERW	FVS
Setting of the behaviour of the drive in case of a motor overload alarm Motor ovld [14] . This alarm indicates that the motor overload threshold has been reached.										
0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.30	4574	Bres ovld activity		ENUM		Disable	0	4	ERW	FVS
Setting of the behaviour of the drive in case of a braking resistor overload alarm Bres ovld . This alarm indicates that the braking resistor overload threshold has been reached.										
0 Ignore 1 Warning 2 Disable 3 Stop 4 Fast stop										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.31	4582	HTsens restart		ENUM		Disable	0	1	ERW	FVS
Enabling of automatic restart after the drive heatsink overtemperature alarm HeatsinkS OTUT [10] .										
0 Disable										
1 Enable										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.32	4584	HTsens restart time	ms	UINT16		20000	120	60000	ERW	FVS
Setting of the time within which the HeatsinkS OTUT [10] alarm must be reset in order to perform automatic restart.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.33	4600	InAir activity		ENUM		Stop	0	4	ERW	FVS
Setting of the behaviour of the drive in case of an intake air overtemperature alarm Intakeair OT [11] . This alarm indicates that the temperature of the intake cooling air is too high.										
0 Ignore										
1 Warning										
2 Disable										
3 Stop										
4 Fast stop										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.34	4602	InAir restart		ENUM		Disable	0	1	ERW	FVS
Enabling of automatic restart after the intake air overtemperature alarm Intakeair OT [11] .										
0 Disable										
1 Enable										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.35	4604	InAir restart time	ms	UINT16		1000	120	30000	ERW	FVS
Setting of the time within which the Intakeair OT [11] alarm must be reset in order to perform automatic restart.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.36	4606	InAir holdoff	ms	UINT16		10000	1000	30000	ERW	FVS
Setting of the delay between the signalling of the intake air overtemperature alarm Intakeair OT [11] and enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before enabling the alarm. If the alarm is removed within the set time, the drive will not indicate any alarm condition.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.37	4610	Desat restart		ENUM		Disable	0	1	ERW	FVS
Enabling of automatic restart after the desaturation alarm Desat . This alarm indicates a short circuit between the motor phases or on the power bridge.										
0 Disable										
1 Enable										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.38	4612	Desat restart time	ms	UINT16		2000	1000	10000	ERW	FVS
Setting of the time within which the Desaturation alarm must be reset in order to perform automatic restart. (Time with alarm signal active + 1000 msec).										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.39	4620	IOverC restart		ENUM		Disable	0	1	ERW	FVS
Enabling of automatic restart after the drive overcurrent alarm. This alarm indicates an overcurrent (or short circuit between phases or towards the ground).										
0 Disable										
1 Enable										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.40	4622	IOverC restart time	ms	UINT16		2000	1000	10000	ERW	FVS
Setting of the time within which the Overcurrent alarm must be reset in order to perform automatic restart. (Time with alarm signal active + 1000 msec).										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.41	4630	OverV restart		ENUM		Disable	0	1	ERW	FVS
Enabling of automatic restart after the overvoltage alarm. This alarm indicates an overvoltage on the intermediate circuit (DC link)										
0 Disable										
1 Enable										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.42	4632	OverV restart time	ms	UINT16		2000	1000	10000	ERW	FVS
Setting of the time within which the Overvoltage alarm must be reset in order to perform automatic restart. (Time with alarm signal active + 1000 msec).										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.43	4640	UnderV restart		ENUM		Enable	0	1	ERW	FVS
Enabling of automatic restart after the Undervoltage [2] alarm. This alarm indicates an undervoltage on the intermediate circuit (DC link).										
If parameter 4640 UnderV restart is set to “ Enable ”, when undervoltage condition is detected the drive is disabled and UV Wng & Restart warning signal is generated. “ Drive ok ” signal remains at the high level (relay contacts closed).										
0 Disable										
1 Enable										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.44	4642	UnderV restart time	ms	UINT16		1000	120	10000	ERW	FVS
Setting of the time within which the Undervoltage [2] alarm must be reset in order to perform automatic restart. (Time with alarm signal active + 100 msec).										

If **UnderV restart** is enabled the below conditions can occurs:

- The **Undervoltage** condition disappear within the time indicated by the parameter 4642: this means that the motor is restarted (depending on the setting by the parameter 552 **Regulation mode** and parameter 3350 **Speed capture**) and, after reaching the level of speed before the undervoltage situation, the warning **UV Wng & Restart** will be automatic reset (**UV Wng & Restart** message disappears from the display on the keypad). If before this event the drive is disabled, the warning **UV Wng & Restart** will be no more shown but without automatic reset (**UV Wng & Restart** message disappears from the display on the keypad. In this condition “**Drive OK**” signal will stay at its high level).
- The **Undervoltage** condition does not disappear within the time indicated by the parameter 4642: this causes the automatic reset of the warning **UV Wng & Restart** and it is generate an **Undervoltage** alarm and **Drive ok** signal goes at low level. If the undervoltage condition is no more present, the restart of the drive is inhibited.
- During **Undervoltage** situation, another alarm is generated (it cannot configured as **Ignore** or **Warning**): this causes the warning **UV Wng & Restart** disappear without automatic reset and the signal **Drive ok** go at low level. If the undervoltage condition is no more present, the restart of the drive is inhibited.

The output signal **UV Wng & Restart** goes at high level when an alarm is generated **UV Wng & Restart** warning and it returns at low level when the alarm disappears, as indicated above.

Note! If the automatic restart function is required, the start and Enable signals must be active.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.45	4650	UVRep attempts		UINT16		5	0	1000	ERW	FVS

Setting of the maximum number of attempts at automatic restart after the **Undervoltage** [2] alarm before a **Mult Undervoltage** [6] alarm is generated. If this parameter is set to 1000 an infinite number of attempts are available.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.46	4652	UVRep delay	s	UINT16		240	0	300	ERW	FVS

Setting of the time within which, if no automatic restarts are executed after the **Undervoltage** [2] alarm, the attempts counter is reset. In this way the number of attempts set in **UVRep attempt** are still available.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.47	4660	PhLoss activity		ENUM		Disable	0	4	ERW	FVS

Setting of the behaviour of the drive in case of a no phase alarm. This alarm indicates the absence of a drive power supply phase.

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.48	4662	PhLoss restart		ENUM		Disable	0	1	ERW	FVS

Enabling of automatic restart after the no phase alarm.

- 0 Disable
- 1 Enable

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.49	4664	PhLoss restart time	ms	UINT16		1000	120	10000	ERW	FVS

Setting of the time within which the **Phase loss** alarm must be reset in order to perform automatic restart. (Time with alarm signal active + 100 msec).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.50	4670	Optionbus activity		ENUM		Disable	0	4	ERW	FVS

Setting of the behaviour of the drive in case of an **Opt Bus Fault** alarm.

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.51	4672	Optbus fault en src		LINK	16	6002	0	16384	ERW	FVS

Selection of the origin (source) of the signal to be used as "**Opt bus fault**" [17] alarm. The terminal that can be used for this function can be selected from among those listed in the "**L_DIGSEL1**" selection list.

The default is PAR 6002 **One**. If it is selected the PAR 1030 **Local / remote mon**, it can inhibit the alarm only when you switch from "**Remote**" to "**Local**".

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.52	4680	Ground Fault thr	perc	FLOAT		10.0	0	150.0	ERWS	FVS

Setting of the threshold for the ground short circuit alarm **Ground Fault**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.53	4684	Brake fault activity		ENUM		Disable	0	4	ERW	FVS

This parameter can be used to configure the behaviour of the drive in the event of a mechanical brake fault. The following activities are programmable:

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.54	4690	ExtI/O activity		ENUM		Disable	0	4	ERW	FVS

This parameter is used to configure the behaviour of the drive if the “**Ext I/O fault**” [27] alarm occurs when the EXP-FL-XCAN-ADV card is installed.

See Chapter C - “**Ext I/O fault**” [27] alarm.

When the alarm is activated due to a communication error, the last value that was received is maintained.

The following activities are programmable:

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

You can check whether a card that supports XCAN External IO functions is installed from the DRIVE INFO menu for parameters 530, 532, 534 **SlotX card type**:

Value	Description	Expansion	
832	IO FastLink	EXP-FL-XCAN-ADV	XCAN External IO supported

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.55	4940	FL fault activity		ENUM		Disable	0	4	ERW	FVS

This parameter is used to configure the behaviour of the drive when the “**FastLink fault**” [28] alarm occurs.

If the EXP-FL-XCAN-ADV card is installed in the drive, all the FastLink communication fault signals are enabled and managed via generation of a “**FastLink fault**” [28] alarm, with different subcodes to indicate the cause of the error.

See Chapter C - “**FastLink Fault**” [28] alarm.

The following activities are programmable:

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.56	4654	Mot PhLoss activity		ENUM		Ignore	0	4	ERW	FV_

The “**Motor phase loss**” alarm signals the loss of a motor phase. This parameter manages the alarm activity.

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.57	4656	Mot PhLoss holdoff	ms	UINT16		800	400	10000	ERW	FVS

Represents the time the alarm condition has to persist before the alarm is actually generated.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.58	4658	Mot PhLoss threshold	A	FLOAT		0.40	0	CALCF	ERW	FVS

Represents the output current threshold for generating the alarm.

The value has to be lower than the torque current value set in the drive.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.59	4674	Mot PhLoss speed thr	rpm	INT16		30	10	32000	ERW	FVS

In case of failure of the connection between a phase of the motor and the drive, the alarm signal is active when it is exceeded the speed threshold set in this parameter.

It can be used to mask the alarm at very low speed during the start and stop transients when external noise could cause false alarm tripping.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.60	4678	Mot PhLoss code		UINT32		0	0	0	ER	FVS

The hexadecimal value contains information about the type of problem detected and the motor phase where there is the anomaly.

0x0001	Error detected on phase U with motor running
0x0002	Error detected on phase V with motor running
0x0004	Error detected on phase W with motor running
0x0008	Error detected on phase U with motor running and speed ref loss
0x0010	Error detected on phase V with motor running and speed ref loss
0x0020	Error detected on phase W with motor running and speed ref loss
0x0040	Error detected on phase U during magnetizing stage (Asynchronous motor only)
0x0080	Error detected on phase V during magnetizing stage (Asynchronous motor only)
0x0100	Error detected on phase W during magnetizing stage (Asynchronous motor only)
0x0200	Error detected on phase U with motor disabled (Asynchronous motor only)
0x0400	Error detected on phase V with motor disabled (Asynchronous motor only)
0x0800	Error detected on phase W with motor disabled (Asynchronous motor only)

In some cases it is possible that more bit are showed at the same time. Depending on the type of fault, in fact, if the interruption of one phase makes that even in the other two there is no more current circulation, the displayed code indicates the absence of all three phases, while being just one connection failed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.61	4590	Condensat activity		ENUM		Disable	0	4	ERW	FVS

Setting of the behaviour of the drive in the event of the [32] **Condensation** alarm. This alarm Indicates the intervention of the dangerous situation of condensation inside the ADV200-LC drive series.

- 0 Ignore
- 1 Warning
- 2 Disable
- 3 Stop
- 4 Fast stop

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.62	4592	Condensat holdoff	s	UINT16		30	0	500	ERW	FVS

Setting of the delay between the signalling of the [32] **Condensation** alarm and enabling of the alarm. If an alarm condition occurs, the drive will wait for the set time before disabling the drive regulation. If the alarm is removed within the set time, the drive will not indicate any alarm condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.63	4576	Condensation delay	s	UINT16		5	0	50	ERW	FVS										
Setting of delay time (in seconds) for activation of the Condensation state (IPA 6044) condition used to switch from 0 to 1 after the Liquid temp mon (IPA 6042) parameter has dropped below Dew temperature (IPA 6032) + Dew temp offset off (IPA 6034)																				
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.64	4596	Overhumidity thr	perc	FLOAT		85.0	0.0	100	ERW	FVS										
Represents the threshold value, in % , at which the Overhumidity state (PAR 6046) output trips.																				
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.65	4578	Overhumidity delay	s	UINT16		5	0	50	ERW	FVS										
Setting of delay time (in seconds) for activation of the Overhumidity state (IPA 6046) condition used to switch from 0 to 1 after the Air humidity (IPA 6020) parameter has become higher than Overhumidity thr (IPA 4596)																				
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.66	4598	HumTSensErr code		UINT32		0	0	0	ER	FVS										
Error code of alarm [52] HumTempSensErr , which can be:																				
0x0: no error																				
0x1: communication error on humidity / temperature sensor																				
0x2: error on NTC temperature sensor for temperature of liquid flowing into heatsink																				
0x3: the sum of both																				
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.67	4546	An inpLoss activity		ENUM		Warning	0	4	ERW	FVS										
0 Ignore																				
1 Warning																				
2 Disable																				
3 Stop																				
4 Fast stop																				
Setting of drive behavior if alarm [62] An inpLos trips.																				
This alarm indicates disconnection of the 0.1V..10.1V or KTY84 o 4..20mA signal for parameters IPA 1502 Analog inp 1 type , IPA 1552 Analog inp 2 type , IPA 1602 Analog inp 1X type and IPA 1652 Analog inp 2X type .																				
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.68	4548	An inpLoss holdoff	ms	UINT16		1000	0	30000	ERW	FVS										
Represents the time the alarm condition has to persist before the [62] An inpLoss alarm is actually generated.																				
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.69	4568	An inpLoss code		UINT32		0	0	0	ER	FVS										
Lets you specify which analog input has gone into error.																				
<table><tr><td>0x01</td><td>error on analog input 1 standard control board</td></tr><tr><td>0x02</td><td>error on analog input 2 standard control board</td></tr><tr><td>0x04</td><td>error on analog input 1 I/O expansion board</td></tr><tr><td>0x08</td><td>error on analog input 2 I/O expansion board</td></tr><tr><td>0x10</td><td>error on dedicated KTY84 input on EXP-SENS expansion boards</td></tr></table>											0x01	error on analog input 1 standard control board	0x02	error on analog input 2 standard control board	0x04	error on analog input 1 I/O expansion board	0x08	error on analog input 2 I/O expansion board	0x10	error on dedicated KTY84 input on EXP-SENS expansion boards
0x01	error on analog input 1 standard control board																			
0x02	error on analog input 2 standard control board																			
0x04	error on analog input 1 I/O expansion board																			
0x08	error on analog input 2 I/O expansion board																			
0x10	error on dedicated KTY84 input on EXP-SENS expansion boards																			
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod										
24.70	4700	Alarm dig sel 1		ENUM		No alarm	0	63	ERW	FVS										
24.71	4702	Alarm dig sel 2		ENUM		No alarm	0	63	ERW	FVS										
24.72	4704	Alarm dig sel 3		ENUM		No alarm	0	63	ERW	FVS										

Setting of the alarm signal to enable on a digital output. The digital output is selected using parameters **Alm dig out mon 1÷4**, which can be enabled in the **L_DIGSEL1** selection list.

- 0 No alarm
- 1 Overvoltage
- 2 Undervoltage
- 3 Ground fault
- 4 Overcurrent
- 5 Desaturation
- 6 MultiUndervolt
- 7 MultiOvercurr
- 8 MultiDesat
- 9 Heatsink OT
- 10 Heatsinks OTUT
- 11 Intakeair OT
- 12 Motor OT
- 13 Drive overload
- 14 Motor overload
- 15 Bres overload
- 16 Phaseloss
- 17 Opt Bus fault
- 18 Opt 1 IO fault
- 19 Opt 2 IO fault
- 20 Opt Enc fault
- 21 External fault
- 22 Speed fbk loss
- 23 Overspeed
- 24 Speed ref loss
- 25 Emg stop alarm
- 26 Power down
- 27 ExtIO fault
- 28 FastLink fault
- 29 Brake fault
- 30 Motor pre OT
- 31 Mot phase loss
- 32 Condensation
- 33 Plc1 fault
- 34 Plc2 fault
- 35 Plc3 fault
- 36 Plc4 fault
- 37 Plc5 fault
- 38 Plc6 fault
- 39 Plc7 fault
- 40 Plc8 fault
- 41 Watchdog
- 42 Trap error
- 43 System error
- 44 User error
- 45 Param error
- 46 Load def par
- 47 Plc cfg error
- 48 Load def plc
- 49 Key failed
- 50 Encoder error
- 51 Opt cfg change
- 52 HumTempSensErr
- 53 Plc9 fault
- 54 Plc10 fault
- 55 Plc11 fault
- 56 Plc12 fault
- 57 Plc13 fault
- 58 Plc14 fault
- 59 Plc15 fault
- 60 Plc16 fault

61 UV Wng&Restart
62 An inpLoss
63 UV Ride Thr

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.74	4720	Alm autoreset time	s	FLOAT		0.0	0.0	60.0	ERW	FVS

Setting of the time interval that must pass before executing an automatic reset.

If no alarms are enabled the drive is set to restart.

If some alarms are still enabled the drive is set to execute a new attempt at automatic reset.

At each attempted reset a counter increases. If the limit set in the Alm autoreset number parameter is reached the drive is set to make no more attempts at reset and waits for a user reset.

The counter is set to zero when an automatic reset or user reset is performed and no alarms are enabled.

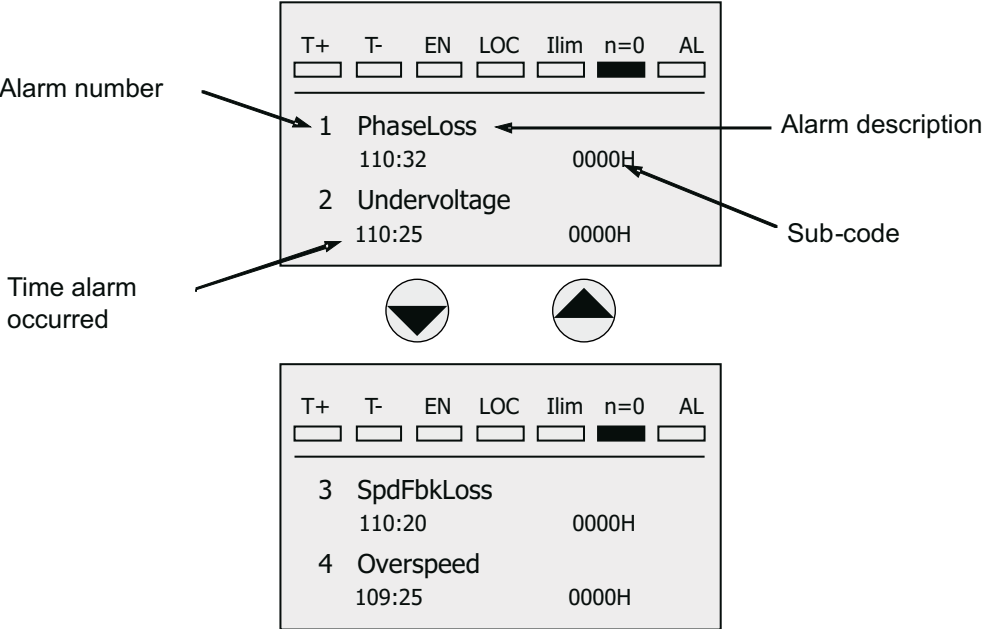
If the parameter is 0 the function is disabled.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
24.75	4722	Alm autoreset number		UINT16		20	0	100	ERW	FVS

Setting of the maximum number of attempted automatic resets.

25 – ALARM LOG

This is the menu in which the log of previous alarms is saved, with the time the alarm occurred (in relation to the **Time drive power** on parameter). The alarms are displayed starting from the most recent (No. 1) up to the furthest back in time (No. 30). Up to 30 alarm signals can be displayed. The sub-code is used by service technicians to identify the specific type of alarm. Press the ▲ and ▼ keys to scroll the screen pages of the alarm log. The alarm log cannot be deleted.



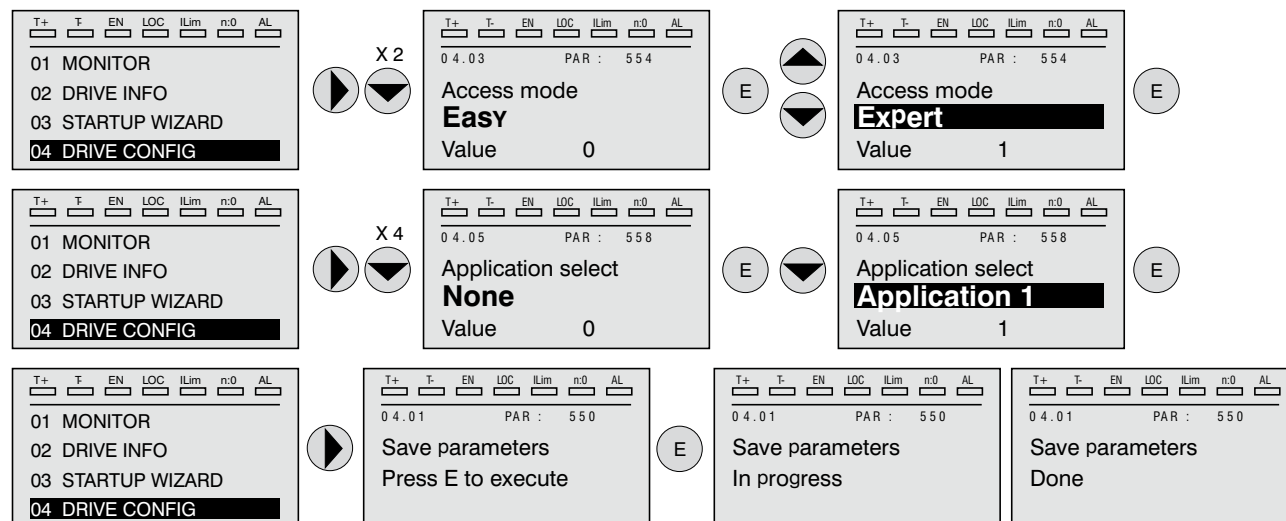
26 – APPLICATION

This menu is designed to host two applications using the MDPIc program.

The PID application is installed by default in the APPLICATION / APPLICATION 1 menu. Follow below procedure to activate PID application.

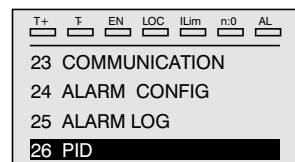
The APPLICATION / APPLICATION 2 menu is available for custom applications.

It will not be possible to use both applications simultaneously. The **558 Application select** parameter in the DRIVE CONFIG menu must be used to select between the two possible applications.



Switch the drive off and then switch it on again.

The PID menu will be available via keypad.



28 - RECIPE CONFIG

Lets you create a custom menu from the keypad (or from GF_eXpress), composed of a maximum of 20 parameters (menu 29 - RECIPE).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
28.1	6300	Recipe config 1		UINT16		0	0	0	RW	FVS
28.2	6302	Recipe config 2		UINT16		0	0	0	RW	FVS
28.3	6304	Recipe config 3		UINT16		0	0	0	RW	FVS
28.4	6306	Recipe config 4		UINT16		0	0	0	RW	FVS
28.5	6308	Recipe config 5		UINT16		0	0	0	RW	FVS
28.6	6310	Recipe config 6		UINT16		0	0	0	RW	FVS
28.7	6312	Recipe config 7		UINT16		0	0	0	RW	FVS
28.8	6314	Recipe config 8		UINT16		0	0	0	RW	FVS
28.9	6316	Recipe config 9		UINT16		0	0	0	RW	FVS
28.10	6318	Recipe config 10		UINT16		0	0	0	RW	FVS
28.11	6320	Recipe config 11		UINT16		0	0	0	RW	FVS
28.12	6322	Recipe config 12		UINT16		0	0	0	RW	FVS
28.13	6324	Recipe config 13		UINT16		0	0	0	RW	FVS
28.14	6326	Recipe config 14		UINT16		0	0	0	RW	FVS
28.15	6328	Recipe config 15		UINT16		0	0	0	RW	FVS
28.16	6330	Recipe config 16		UINT16		0	0	0	RW	FVS
28.17	6332	Recipe config 17		UINT16		0	0	0	RW	FVS
28.18	6334	Recipe config 18		UINT16		0	0	0	RW	FVS
28.19	6336	Recipe config 19		UINT16		0	0	0	RW	FVS
28.20	6338	Recipe config 20		UINT16		0	0	0	RW	FVS

Configuration parameters for creating custom menu.

Select a **Recipe config X** parameter, press **Enter** and insert the IPA of the parameter to be added to the custom list (will be available on menu 29 - RECIPE).

To remove an IPA from the list of custom menus, set the related parameter **Recipe config X = 0**.

When settings are done, use the "**Save parameters**" command on the DRIVE CONFIG menu to save in permanent memory.

29 - RECIPE

The parameters configured on menu 28 - RECIPE CONFIG. are written on the RECIPE menu (initially empty).

PARAMETERS ON SELECTION LISTS, BUT NOT DISPLAYED ON KEYPAD

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	220	Theta ref mon		INT32		0.0	0.0	0.0	ER	
Monitor value of the electrical motor angle.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	224	Flux ref mon		INT32		0.0	0.0	0.0	ER	
Monitor value of the Flux reference.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	262	Motor speed nofilter	FF	INT16	16	0	0	0	ER	
This parameter indicates the unfiltered motor speed.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	362	Drive overload trip		BIT	16	0	0	1	ER	
This signal indicates that the drive is in the overload condition. In the default condition the alarm is not triggered as the relative action is set to Ignore .										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	366	Drive overload 80		BIT	16	0	0	1	ER	
This signal indicates that the drive has reached 80% of the thermal image accumulator (drive overload).										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	626	Ramp ref out mon	FF	INT16	16	0	0	0	ER	
This parameter displays the reference value output of the ramp reference function block.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	760	Ramp out mon	FF	INT16	16	0	0	0	ER	
This parameter displays the reference value output of the ramp function block.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	764	Ramp acc state		BIT	16	0	0	1	ER	
This signal indicates whether the acceleration ramp is active.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	766	SRamp dec state		BIT	16	0	0	1	ER	
This signal indicates whether the deceleration ramp is active.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	934	Ref is 0		BIT	16	0	0	1	ER	
This signal is active when the reference is below the limit set in parameter 930 Reference 0 threshold .										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	936	Ref is 0 delay		BIT	16	0	0	1	ER	
This parameter is active when the reference is below the threshold set in parameter 930 Reference 0 threshold . The signal is enabled after the delay set with parameter 932 Reference delay 0 .										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	938	Ref is 0 Vf limit		BIT	16	0	0	1	ER	

This parameter is active only with control mode V/F

It indicates the state 1 when the motor speed is below the value set in parameter P940. It indicates the state 0 when the motor speed is greater than the value set in parameter P940.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	944	Speed is 0		BIT	16	0	0	1	ER	

This parameter is active when the speed is below the threshold set in parameter **940 Speed 0 threshold**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	946	Speed is 0 delay		BIT	16	0	0	1	ER	

This signal is active when the reference is below the threshold set in parameter **940 Speed 0 threshold**. The signal is activated after the delay set in parameter **942 Speed 0 delay**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	956	Speed thr 1_2 mon		BIT	16	0	0	1	ER	

To display the speed threshold status: if the motor speed is higher than the value set in parameter **950 Speed threshold 1** or lower than the value set in parameter **952 Speed threshold 2** this parameter assumes the value of 0.

If the motor speed is between the value of **950 Speed threshold 1** and that of **952 Speed threshold 2**, this parameter assumes the value of 1.

Use parameter **954 Speed threshold dly** to set a delay time for the transition from 0 to 1 of parameter **956 Speed thr 1_2 mon**; the transition from 1 to 0 is always immediate.

When **950 Speed threshold 1** is set to a value higher than **952 Speed threshold 2**, if the motor speed is between the thresholds this parameter assumes the value of 1. If **950 Speed threshold 1** is set to a value lower than **952 Speed threshold 2**, the threshold status is not significant

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	966	Set speed		BIT	16	0	0	1	ER	

This signal is active when the error between the speed reference and actual motor speed is greater than the tolerance set in parameter **962 Set speed error**.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	976	Speed thr 3 mon		BIT	16	0	0	1	ER	

The status of the block that detects exceeding of the speed 3 threshold is displayed.

0 Actual speed below threshold

1 Actual speed above threshold

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	986	Current thr mon		BIT	16	0	0	1	ER	

The status of the block that detects exceeding of the current threshold is displayed.

0 Actual output current below threshold

1 Actual output current above threshold.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	1030	Local/remote mon		BIT	16	0	0	1	ER	

This signal is active when the drive is in the **Remote** operating mode.

0 Local

1 Remote

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	1060	Sequencer status		UINT16	16	0	0	0	ER	

This signal indicates the state of the “machine states” that controls drive operation.

STS_INIT	0
STS_MAGN	1
STS_STOP	2
STS_START	3
STS_FS_STOP	4
STS_FS_START	5
STS_QSTOP	6
STS_FS_MAGN	7
STS_W_QSTOP	8
STS_READY	9
STS_MAGN_START	10
STS_ALM_DISABLED	11
STS_ALM_END_ACTION	12
STS_ALM_STOP	13
STS_ALM_FSTOP	14
STS_ALM_R_TO_NORMAL	15
STS_READY_START	16
STS_READY_FSTOP	17
STS_ALM_NO_RESTART	18
STS_FS_MAGN_START	19

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	1062	Drive OK		BIT	16	0	0	1	ER	

This signal is active when the drive is in the “OK” condition and no alarms are present.

Connected to the relay output, the normally open relay contact closes when:

- the drive is powered
- no alarm conditions are active.

Note: in the case of parameter 4640 **UnderV restart** is set to “**Enable**”, signal remains at the high level if undervoltage condition disappears within the specified time in P4642.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	1064	Drive ready		BIT	16	0	0	1	ER	

This signal is active when the drive reference is in the “Ready” to run condition.

Connected to the relay output, the normally open relay contact closes when:

- the drive is powered
- preloading is complete
- no alarm conditions are active
- the drive is enabled
- motor magnetisation is complete.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	1072	UV Wng&Restart		BIT	16	0	0	1	ER	

If parameter 4640 **UnderV restart** is set to “**Enable**”, when undervoltage condition is detected the drive is disabled and **UV Wng & Restart** warning signal is generated. “**Drive ok**” signal remains at the high level (relay contacts closed).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	1110	Digital input E mon		BIT	16	0	0	1	ER	
	1112	Digital input 1 mon		BIT	16	0	0	1	ER	
	1114	Digital input 2 mon		BIT	16	0	0	1	ER	
	1116	Digital input 3 mon		BIT	16	0	0	1	ER	
	1118	Digital input 4 mon		BIT	16	0	0	1	ER	

1120 Digital input 5 mon	BIT	16	0	0	1	ER
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These signals represent the state of the corresponding digital input.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
		1210 Digital input 1X mon		BIT	16	0	0	1	ER	
		1212 Digital input 2X mon		BIT	16	0	0	1	ER	
		1214 Digital input 3X mon		BIT	16	0	0	1	ER	
		1216 Digital input 4X mon		BIT	16	0	0	1	ER	
		1218 Digital input 5X mon		BIT	16	0	0	1	ER	
		1220 Digital input 6X mon		BIT	16	0	0	1	ER	
		1222 Digital input 7X mon		BIT	16	0	0	1	ER	
		1224 Digital input 8X mon		BIT	16	0	0	1	ER	
		5510 Digital input 9X mon		BIT	16	0	0	1	ER	
		5512 Digital input 10X mon		BIT	16	0	0	1	ER	
		5514 Digital input 11X mon		BIT	16	0	0	1	ER	
		5516 Digital input 12X mon		BIT	16	0	0	1	ER	
		5518 Digital input 13X mon		BIT	16	0	0	1	ER	
		5520 Digital input 14X mon		BIT	16	0	0	1	ER	
		5522 Digital input 15X mon		BIT	16	0	0	1	ER	
		5524 Digital input 16X mon		BIT	16	0	0	1	ER	

These signals represent the state of the corresponding digital input on the expansion card.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
		1530 Analog inp1		BIT	16	0	0	1	ER	

This signal is active when the value of the analog input is below the threshold set in parameter **1520 Analog inp 1 thr.**

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-		1540 An inp 1 err mon		BIT	16	0	0	0	ER	

This parameter contains the signal of possible disconnection of the related input.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-		1542 Analog inp1 > thr		BIT	16	0	0	1	ER	

This signal activates when the value of the analog input exceeds the threshold set with parameter **1520 Analog inp 1 thr.**

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
		1580 Analog inp2		BIT	16	0	0	1	ER	

This signal is active when the value of the analog input is below the threshold set in parameter **1570 Analog inp 2 thr.**

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-		1590 An inp 2 err mon		BIT	16	0	0	0	ER	

This parameter contains the signal of possible disconnection of the related input.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-		1592 Analog inp2 > thr		BIT	16	0	0	1	ER	

This signal activates when the value of the analog input exceeds the threshold set with parameter **1570 Analog inp 2 thr.**

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-		1640 An inp 1X err mon		BIT	16	0	0	0	ER	

- **1690 An inp 2X err mon** BIT 16 0 0 0 ER
This parameter contains the signal of possible disconnection of the related input from the optional board.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	2388	Torque ref nofilter	perc	FLOAT	16	0.0	0.0	0.0	ER	

The torque control reference current without filter is displayed (in Flux vector OL and field-oriented vector mode).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	2396	Torque nofilter	perc	FLOAT	16	0.0	0.0	0.0	ER	

Monitoring of the actual torque reference without filters.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3006	Speed ratio out mon	rpm	INT16	16	0	0	0	ER	

This parameter displays the value of the speed ratio used by the “Speed draw” function (speed ratio).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	2392	Torque ref 1 mon	perc	FLOAT	16/32	0.0	-300.0	300.0	ERW	

The total value of torque reference 1 is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3180	Brake control mon	rpm	INT16	16	0	0	1	ER	

This parameter displays the status of the brake command.

0 Brake closed

1 Brake open

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3192	Brake open thr mon	perc	FLOAT		0	0.0	0	ERS	

Brake opening threshold value. Only if **Hoist mode 2** has been selected.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3214	Motor overload trip		BIT	16	0	0	1	ER	

This signal is active when the drive is in the motor overload alarm condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3262	Bres overload trip		BIT	16	0	0	1	ER	

This signal is active when the drive is in the braking resistor overload alarm condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3374	Vf catch out		INT32	16	0	0	0	ER	

The voltage applied during capture on-the-fly of the motor in Vf mode is displayed.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	3442	Powerloss rampdown		BIT	16	0	0	1	ER	

This parameter indicates the status of the Powerloss function deceleration ramp

0 Powerloss function deceleration ramp not ended

1 Powerloss function deceleration ramp ended

The signal is enabled at the end of the Powerloss function deceleration ramp.

The signal is disabled at different times depending on the **Powerloss mode** setting.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	3446	Powerloss nexratio		INT32	32	0	0	0	ER	
This parameter gives the ratio between the motor speed and the speed reference. For machines with several drives, line synchronisation can be achieved by connecting the Powerloss mode output of the master to the Speed ratio src input of the slave drives. The master => slave connection can be achieved via analog signals or fieldbus. The value 2³⁰ corresponds to a ratio of 1.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	3448	Powerloss nextactive		BIT	16	0	0	1	ER	
This parameter indicates the status of the Powerloss function 0 Powerloss not enabled 1 Powerloss enabled The function is enabled when there is a power failure. The function is disabled at different times depending on the Powerloss mode setting.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	3480	Vdc ctrl ramp freeze		BIT	16	0	0	1	ER	
This parameter displays when the deceleration ramp block is requested during the Vdc control function. 0 VdcCtrl function not enabled 1 VdcCtrl function enabled										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	3512	Drv thr overtemp mon		UINT32		0	0	1	ER	
Signals that the threshold set in PAR 3504 Drv temp thr has been exceeded. 0 Threshold not exceeded 1 Threshold exceeded										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	3514	Mot thr overtemp mon		UINT32		0	0	1	ER	
Signals that the threshold set in PAR 3506 Mot temp thr has been exceeded. 0 Threshold not exceeded 1 Threshold exceeded										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	4372	DS402 status word		UINT16	16	0	0	65535	ER	
This parameter displays the status word according to the DS402 profile. For more information reference should be made to the fieldbus manual.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4394	PFdrv status word 1		UINT16	16	0	0	65535	ER	
This parameter displays the status word 1 according to the Profidrives profile. For more information reference should be made to the fieldbus manual.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4396	PFdrv status word 2		UINT16	16	0	0	65535	ER	
This parameter displays the status word 2 according to the Profidrives profile. For more information reference should be made to the fieldbus manual.										

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4538	KTY84/PTC current	mA	UINT32		2	1	10	ERWS	
Value of current flowing in connected temperature sensor KTY84.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4708	Alm dig out mon 1		BIT	16	0	0	1	ER	
This signal is activated when the alarm configured in parameter 4700 alarm dig sel 1 is active.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4710	Alm dig out mon 2		BIT	16	0	0	1	ER	
This signal is activated when the alarm configured in parameter 4702 alarm dig sel 2 is active.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4712	Alm dig out mon 3		BIT	16	0	0	1	ER	
This signal is activated when the alarm configured in parameter 4704 alarm dig sel 3 is active.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4714	Alm dig out mon 4		BIT	16	0	0	1	ER	
This signal is activated when the alarm configured in parameter 4706 alarm dig sel 4 is active.										
Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4770	First alarm		UINT32	16	0	0	0	ERW	
This parameter displays the first alarm to be activated.										
0 No alarm 1 Overvoltage 2 Undervoltage 3 Ground fault 4 Overcurrent 5 Desaturation 6 MultiUndervolt 7 MultiOvercurr 8 MultiDesat 9 Heatsink OT 10 HeatsinkS OTUT 11 Intakeair OT 12 Motor OT 13 Drive overload 14 Motor overload 15 Bres overload 16 Phase loss 17 Opt Bus fault 18 Opt 1 IO fault 19 Opt 2 IO fault 20 Opt Enc fault 21 External fault 22 Speed fbk loss 23 Overspeed 24 Speed ref loss 25 Emg stop alarm 26 Power down 27 ExtIO fault 28 FastLink fault 29 Brake fault 30 Motor pre OT										

- 31 Mot phase loss
- 32 Condensation
- 33 Plc1 fault
- 34 Plc2 fault
- 35 Plc3 fault
- 36 Plc4 fault
- 37 Plc5 fault
- 38 Plc6 fault
- 39 Plc7 fault
- 40 Plc8 fault
- 41 Watchdog
- 42 Trap error
- 43 System error
- 44 User error
- 45 Param error
- 46 Load def par
- 47 Plc cfg error
- 48 Load def plc
- 49 Key failed
- 50 Encoder error
- 51 Opt cfg change
- 52 HumTempSensErr
- 53 Plc9 fault
- 54 Plc10 fault
- 55 Plc11 fault
- 56 Plc12 fault
- 57 Plc13 fault
- 58 Plc14 fault
- 59 Plc15 fault
- 60 Plc16 fault
- 61 UV Wng&Restart
- 62 An inpLoss
- 63 UV Ride Thr

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4780	Alarm PLC		UINT16		0	0	0	ER	

This parameter displays the state of the alarms generated by the application written with the internal MDPlc.

Bit	Description
0	1 = PLC 1 fault active
1	1 = PLC 2 fault active
2	1 = PLC 3 fault active
3	1 = PLC 4 fault active
4	1 = PLC 5 fault active
5	1 = PLC 6 fault active
6	1 = PLC 7 fault active
7	1 = PLC 8 fault active

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4840	Alarm Io state		UINT32	32	0	0	0	ER	

This parameter displays the state of alarms 1..32 of the drive.

Bit	Description
0	1 = Overvoltage active
1	1 = Undervoltage active
2	1 = Ground fault active
3	1 = Overcurrent active
4	1 = Desaturation active

Bit	Description
5	1 – MultiUndervolt active
6	1 = MultiOvercurr active
7	1 – MultiDesat active
8	1 = Heatsink OT active
9	1 = Heatsink lin OT active
10	1 = Air OT active
11	1 = Motor OT active
12	1 = Drive overload active
13	1 = Motor overload active
14	1 = Bres overload active
15	1 = Phase loss active
16	1 = Opt bus fault active
17	1 = Opt 1 I/O fault active
18	1 = Opt 2 I/O fault active
19	1 = Opt enc fault active
20	1 = External fault active
21	1 = Fbk loss active
22	1 = Overspeed active
23	1 = Ref loss active
24	1 = Emg stop alarm active
25	1 = Power down active
26	1 = not used
27	1 = not used
28	1 = not used
29	1 = not used
30	1 = not used
31	1 = not used

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	4842	Alarm hi state		UINT32	32	0	0	0	ER	

This parameter displays the state of alarms 33...64 of the drive.

Bit	Description
0	1 = PLC 1 fault active
1	1 = PLC 2 fault active
2	1 = PLC 3 fault active
3	1 = PLC 4 fault active
4	1 = PLC 5 fault active
5	1 = PLC 6 fault active
6	1 = PLC 7 fault active
7	1 = PLC 8 fault active

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	5800	FL Fwd 1 inv mon		INT32	32	0	0	0	ER	
	5802	FL Fwd 2 inv mon		INT32	32	0	0	0	ER	
	5804	FL Fwd 3 inv mon		INT32	32	0	0	0	ER	
	5806	FL Fwd 4 inv mon		INT32	32	0	0	0	ER	
	5808	FL Fwd 5 inv mon		INT32	32	0	0	0	ER	
	5810	FL Fwd 6 inv mon		INT32	32	0	0	0	ER	
	5812	FL Fwd 7 inv mon		INT32	32	0	0	0	ER	
	5814	FL Fwd 8 inv mon		INT32	32	0	0	0	ER	

These parameters are not used on the master drive.

On the slave drive these parameters show the value received from the previous drive. The “Inv” parameters enable the value received to be used with the opposite sign, without changing any of the data sent to subsequent slaves.

These parameters are available in the “src” analog parameter selection lists.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	6000	Null		UINT32	32	0	0	0	ER	

This signal forces the variable to the zero level (always disabled).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	6002	One		UINT32	32	1	1	1	ER	

This signal forces the variable to level one (always active).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	6004	Speed limit state		BIT	16	0	0	1	ER	

This signal is activated when the drive is in the speed limit condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
	6006	Current limit state		BIT	16	0	0	1	ER	

This signal is activated when the drive is in the current limit condition.

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	6044	Condensation state		UINT32		0	0	0	ER	

This signal is activated when the drive is in the condensation alarm condition. (ADV200-LC series).

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
-	6046	Overhumidity state		UINT32		0	0	0	ER	

This signal is activated when the drive is in the overhumidity alarm condition. (ADV200-LC series).

C – TROUBLESHOOTING - Alarms

Note ! To reset alarms, see Quick start guide, **paragraph 6.6.1**.
In the following table, the Code is visible only from serial line.

Code	Error message shown on the display	Sub-code	Description
0	No alarm	Condition: No alarm present	
1	Overvoltage	Condition: DC link overvoltage alarm due to energy recovered from the motor. The voltage arriving at the drive power section is too high compared to the maximum threshold relating to the PAR 560 Mains voltage parameter setting. Solution: - Extend the deceleration ramp. - Use a braking resistor between terminals BR1 and BR2 to dissipate the recovered energy - Use the VDC Control function	
2	Undervoltage	Condition: DC link undervoltage alarm. The voltage arriving at the drive power section is too low compared to the minimum threshold relating to the PAR 560 Mains voltage parameter setting due to: - the mains voltage being too low or overextended voltage drops. - poor cable connections (e.g. loose contactor terminals, inductance, filter, etc.). Solution: Check the related connections of the drive power supply and its correct range.	
3	Ground fault	Condition: Ground short circuit alarm Solution: - Check drive and motor wiring. - Check that the motor is not grounded.	
4	Overcurrent	Condition: Instantaneous overcurrent protection intervention alarm. This may be due to the incorrect setting of current regulator parameters or a short circuit between phases or ground fault on the drive output. Solution: - Check the current regulator parameters - Check wiring towards the motor	
5	Desaturation	Condition: Instantaneous overcurrent in the IGBT bridge alarm. Solution: Switch the drive off and then switch it on again. If the alarm persists, contact the technical service centre.	
6	MultiUndervolt	Condition: The number of attempted automatic restarts after the Undervoltage alarm has exceeded the set PAR 4650 UVRep attempts value in the PAR 4652 UVRep delay time. Solution: Too many Undervoltage alarms. Adopt the proposed solutions for the Undervoltage alarm.	
7	MultiOvercurr	Condition: 2 attempted automatic restarts after the Overcurrent alarm within 30 seconds. If more than 30 seconds pass after the Overcurrent alarm was generated, the attempt counter is reset. Solution: Too many Overcurrent alarms. Adopt the proposed solutions for the Overcurrent alarm.	
8	MultiDesat	Condition: 2 attempted at automatic restarts after the Desaturation alarm within 30 seconds. If more than 30 seconds pass after the Desaturation alarm was generated, the attempt counter is reset. Solution: Too many Desaturation alarms. Adopt the proposed solutions for the Desaturation alarm.	
9	Heatsink OT	Condition: Heatsink temperature too high alarm Solution: - Verify the correct operation of the cooling fan. - Check that the heatsinks are not clogged - Check that the openings for the cabinet cooling air are not blocked.	
10	HeatsinkS OTUT	Condition: IGBT modules temperature too high or too low alarm Solution: - Verify the correct operation of the cooling fan. - Check that the heatsinks are not clogged - Check that the openings for the cabinet cooling air are not blocked.	
11	Intakeair OT	Condition: Intake drive air temperature too high alarm.	

Code	Error message shown on the display	Sub-code	Description
			Solution: - Check correct fan operation - Check that the heatsinks are not clogged - Check temperature in electrical panel.
12	Motor OT		Condition: Motor overtemperature alarm. Possible causes: - Load cycle too heavy - The motor is installed in a place where the ambient temperature is too high - If the motor is provided with a blower: the fan is not working - If the motor is not provided with a blower: the load is too high at slow speeds. Cooling the fan on the motor shaft is not sufficient for this load cycle. - The motor is used at less than the rated frequency, causing additional magnetic losses. Solution: - Change the processing cycle. - Use a cooling fan to cool the motor.
13	Drive overload		Condition: Drive overload alarm. The overload threshold of the accumulator of the I ² t drive thermal image has been exceeded. Solution: Check that the size of the drive is suitable for the application.
14	Motor overload		Condition: Motor overload alarm. The current absorbed during operation is greater than that specified on the motor data plate. The overload threshold of the accumulator of the I ² t motor thermal image has been exceeded. Solution: - Reduce the motor load. - Increase the size of the motor.
15	Bres overload		Condition: Braking resistor overload alarm. The current absorbed by the resistor is greater than the rated current. The overload threshold of the accumulator of the I ² t braking resistor thermal image has been exceeded. Solution: Increase the Watt value of the braking resistor
16	Phaseloss		Condition: Power phase loss alarm. Solution: Check the mains voltage and whether any protections upstream of the drive have been tripped.
17	Opt Bus fault		Condition: Error in the configuration stage or communication error. XXX0H-X If the first digit to the left of "H" in the alarm sub-code is 0, the error regards a communication problem. XXXXH-X If the first digit to the left of "H" in the alarm sub-code is other than 0, the error regards a configuration problem. Solution: For configuration errors, check the configuration of the bus communication, type of bus, baudrate, address, parameter setting. For communication errors verify wiring, resistance of terminations, interference immunity, timeout settings. For further details, please refer to the user guide for the specific bus.
18	Opt 1 IO fault		Condition: Error in the communication between Regulation and I/O expansion card in slot 1 Solution: Check that it has been inserted correctly, see chapter 10.5 ADV200 QS manual.
19	Opt 2 IO fault		Condition: Error in the communication between Regulation and I/O expansion card in slot 2 or 3 Solution: Check that it has been inserted correctly, see chapter 10.5 ADV200 QS manual.
20	Opt Enc fault		Condition: Error in the communication between Regulation and Encoder feedback card. Solution: Check that it has been inserted correctly, see chapter 10.5 ADV200 QS manual.
21	External fault		Condition: External alarm present. A digital input has been programmed as an external alarm, but the +24V voltage is not available on the terminal. Solution: Check that the terminal screws are tight
22	Speed fbk loss		Condition: Speed feedback loss alarm. The encoder is not connected, not connected properly or not powered: verify encoder operation by selecting the Motor speed parameter in the MONITOR menu.

Code	Error message shown on the display	Sub-code	Description
			Solution: - Check encoder wiring for integrity. - Check that the encoder is connected to the power supply. - With the drive disabled, turn the motor clockwise (seen from the motor shaft side). A positive value must be displayed. - If the value does not change or values are indicated randomly, check the encoder power supply and cables. - If the value displayed is negative, invert the encoder connections. Change channel A+ and A- or B+ and B-. - Check that the encoder electronics are consistent with those of the relative expansion card. - Generated in case of an encoder fault. Each type of encoder generates a "Loss of feedback" alarm differently. See parameter 2172 SpdFbkLoss code for information about the cause of the alarm and chapter C.1 Speed fbk loss alarm.
23	Overspeed		Condition: Motor overspeed alarm. The motor speed exceeds the limits set in the PAR 4540 Overspeed threshold parameter.
			Solution: - Limit the speed reference. - Check that the motor is not driven in overspeed during rotation.
24	Speed ref loss		Condition: Speed reference loss alarm; occurs if the difference between the speed regulator reference and the actual motor speed is more than 100 rpm. This condition occurs because the drive is in the current limit condition. It is only available in the Flux Vect OL and Flux Vect OC mode.
			Solution: - Check the drive load conditions - Check the number of encoder impulses
25	Emg stop alarm		Condition: Emergency stop alarm. The Stop key on the keypad was pressed with the PAR 1008 Stop key mode parameter set to EmgStop&Alarm . Active in remote control mode (PAR 1012=1) both by using "Terminals" command or "Digital" commands and, in local control mode (PAR 1012=0) by using "Terminals" command.
			Solution: Eliminate the reason for which the Stop key on the keypad was pressed and reset the drive.
26	Power down		Condition: The drive was enabled with no supply voltage at the power section.
			Solution: Check the drive power supply
27	ExtIO fault		Condition: Communication fault with the external module.
			Solution: See paragraph "C-2 "ExtIO fault" Alarm" on page 212
28	FastLink fault		Condition: FastLink communication fault
			Solution: See paragraph "C-3 "Fastlink" Alarm" on page 213
29	Brake fault		Condition: Incorrect setting of brake control function parameters.
			Solution: See menu 22.13 - FUNCTIONS/BRAKE CONTROL
30	Motor pre OT		Condition: Motor overtemperature prealarm. % value of threshold compared to PAR 4532 MotorOT thr ,
			Solution: - Value set too low for duty cycle - Heavy duty cycle
31	Mot phase loss		Condition: Output phase loss.
			Solution: Check Drive/motor connection.
32	Condensation		Condition: There may be problem of condensation inside the ADV200-LC drive series. Working condition (combination of ambient temperature, Humidity level and temperature of the cooling liquid) is not safe,
			Solution: Safe conditions are obtained when the work point is under the respective curve indicated in the drawing of chapter 22.18 FUNCTION/LC CONTROL. Otherwise, you have to take adequate precautions to lower the ambient temperature and/or the relative humidity or to raise the cooling liquid temperature.
33 ... 40	Plc1 fault ... Plc8 fault		Condition: Enabled application developed in the IEC 61131-3 environment has found the conditions for generating this specific alarm to be true. The meaning of the alarm depends on the type of application. For more information, refer to the documentation concerning the specific application..
		XXXXH-X	The XXXXH-X code indicates the reason for the error: make a note of this to discuss it with the service centre.
			Solution: Refer to the documentation concerning the enabled application.

Code	Error message shown on the display	Sub-code	Description
41	Watchdog	Condition: may occur during functioning when the watchdog protection of the micro is activated; the alarm is inserted in the alarm list and alarm log. After this alarm: - the drive automatically runs a reset - motor control is not available.	
		XXXXH-X	The XXXXH-X code indicates the reason for the error: take note for examination with the service centre.
		Solution: If the alarm was a consequence of a variation to the drive configuration (parameter setting, installation of an option, downloading of a PLC application), remove it. Switch the drive off and then switch it on again.	
42	Trap error	Condition: this condition can occur during operation when the trap micro protection is enabled; the alarm is included in the list of alarms and alarm log. After this alarm: - the drive automatically runs a reset - motor control is not available.	
		XXXXH-X	The XXXXH-X code (SubHandler-Class) indicates the reason for the error: take note for examination with the service centre.
		Solution: If the alarm was a consequence of a variation to the drive configuration (parameter setting, installation of an option, downloading of a PLC application), remove it. Switch the drive off and then switch it on again.	
43	System error	Condition: this condition can occur during operation when the operating system protection is enabled; the alarm is included in the list of alarms and alarm log. After this alarm: - the drive automatically runs a reset - motor control is not available.	
		XXXXH-X	The XXXXH-X code (Error-Pid) indicates the reason for the error: take note for examination with the service centre.
		Solution: If the alarm was a consequence of a variation to the drive configuration (parameter setting, installation of an option, downloading of a PLC application), remove it. Switch the drive off and then switch it on again.	
44	User error	Condition: this condition can occur during operation when the software protection is enabled; the alarm is included in the list of alarms and alarm log. After this alarm: - the drive automatically runs a reset - motor control is not available.	
		XXXXH-X	The XXXXH-X (Error-Pid) code indicates the reason for the error: make a note of this to discuss it with the service centre.
		Solution: If the alarm was a consequence of a variation to the drive configuration (parameter setting, installation of an option, downloading of a PLC application), remove it. Switch the drive off and then switch it on again.	
45	Param error	Condition: if an error occurs during the enabling of the parameter database saved in the Flash memory; the alarm is included in the list of alarms and alarm log.	
		XXXH-X	The code XXXXH-X indicates the IPA of the parameter that has been set outside the range allowed when the database is enabled.
		Solution: Set the parameter causing the error to a value within the range and run Save parameter . Switch the drive off and then switch it back on again. If the IPA of the parameter is not shown in the manual, contact the service centre.	
46	Load default	Condition: this can occur during loading of the parameter database saved in the Flash memory it is normal if it appears in the following conditions: the first time the drive is switched on, when a new version of the firmware is downloaded, when the regulation is installed on a new size, when a new region is entered. If this message appears when the drive is already in use it means there has been a problem in the parameter database saved in the Flash memory. If this message is displayed the drive restores the default database, i.e. the one downloaded.	
		0001H-1	The database saved is not valid
		0002H-2	The database saved is not compatible
		0003H-3	The saved database refers to a different size and not to the current size
		0004H-4	The saved database refers to a different region and not to the current region
		Solution: Set the parameters to the desired value and run Save parameter	
47	Plc cfg error	Condition: this can occur during loading of the MDPLC application The Mdpplc application present on the drive is not run.	
		0004H-4	The application that has been downloaded has a different Crc on the DataBlock and Function table.

Code	Error message shown on the display	Sub-code	Description
		0065H-101	The application that has been downloaded has an invalid identification code (Info).
		0066H-102	The application that has been downloaded uses an incorrect task number (Info).
		0067H-103	The application that has been downloaded has an incorrect software configuration.
		0068H-104	The application that has been downloaded has a different Crc on the DataBlock and Function table.
		0069H-105	A Trap error or System error has occurred. The drive has automatically executed a Power-up operation. Application not executed. See the Alarm List for more information about an error that has occurred.
		006AH-106	The application that has been downloaded has an invalid identification code (Task).
		006BH-107	The application that has been downloaded uses an incorrect task number (Task).
		006CH-108	The application that has been downloaded has an incorrect Crc (Tables + Code)
		Solution: Remove the MDPLC application or download a correct MDPLC application.	
48	Load def plc	Condition: this can occur during loading of the parameter database saved in the Flash memory of the MDPLC application it is normal if it appears the first time the drive is switched on, after downloading a new application. If this message appears when the drive is already in use it means there has been a problem in the parameter database saved in the Flash memory. If this message appears the drive automatically runs the Load default command.	
		0001H-1	The database saved is not valid
		Solution: Set the parameters to the desired value and run Save parameter.	
49	Key failed	Condition: This may occur at drive power-on if the incorrect enabling key was inserted for a given firmware function.	
		0001H-1	Incorrect PLC key. PLC application not available.
		Solution: Ask Gefran for the correct key to enable the desired firmware function.	
50	Encoder error	Condition: this condition may occur when the drive is powered during encoder setup each time parameter 552 Regulation mode is set.	
		100H-256	An error occurred during setup; the information received from the encoder is not reliable. If the encoder is used for feedback the Speed fbk loss [22] alarm is also generated.
		Solution: Take the recommended action for the Speed fbk loss [22] alarm.	
		200H-512	Cause: The firmware on the optional encoder card is incompatible with that on the regulation card. The information received from the encoder is not reliable
		Solution: Contact Gefran in order to update the firmware on the optional encoder card.	
51	Opt cfg change	Condition: this may occur when powering the drive if an expansion card has been removed or replaced or the incorrect enable key is inserted for a given firmware function.	
		0064H-100	Card removed from slot 1.
		0014H-20	Card removed from slot 2
		0003H-3	Card removed from slot 3
		0078H-120	Card removed from slot 1 and from slot 2
		0067H-103	Card removed from slot 1 and from slot 3.
		0017H-23	Card removed from slot 2 and from slot 3.
		007BH-123	Card removed from slot 1, from slot 2 and from slot 3
		Solution: Check the hardware configuration, then press ESC. Save the parameters (Save parameters , menu 04.01 par 550) to save the new hardware configuration.	
52	HumTempSensErr	Condition: Disconnection or short circuit of the humidity sensor built into the ADV200-LC drive.	
		0x0	No error.
		0x1	Communication error on humidity / temperature sensor
		0x2	Error on NTC temperature sensor for temperature of liquid flowing into heatsink
		0x3	Communication error and NTC temperature sensor
		Solution: Reset the drive. If the problem persists, contact Gefran Customer Service.	

Code	Error message shown on the display	Sub-code	Description
53 ... 60	Plc9 fault ... Plc16 fault		Condition: Enabled application developed in the IEC 61131-3 environment has found the conditions for generating this specific alarm to be true. The meaning of the alarm depends on the type of application. For more information, refer to the documentation concerning the specific application..
		XXXXH-X	The XXXXH-X code indicates the reason for the error: make a note of this to discuss it with the service centre.
			Solution: Refer to the documentation concerning the enabled application.
61	UV Wng&Restart		Condition: parameter 4640 UnderV restart is set to "Enable". Undervoltage condition is detected, the drive is disabled and UV Wng & Restart warning signal is generated.
			Solution: Check drive power supply wirings and its correct range.
62	An inpLoss		Condition: Occurs when: - the input signal is below 0.1V or 4-20mA - the KTY84 sensor short-circuits or disconnect
			Solution: Check the wiring.
63	UV Ride Thr		Condition: Parameter 3280 UV RT enable is set = 1. Due to a mains voltage dip (Mains loss) the DC link voltage value is lower than the threshold PAR 3282 UV RT on .
			Solution: Check drive power supply wirings and its correct range.

C-1 Speed fbk loss alarm according to the type of feedback

Note !

To interpret the causes of the alarm correctly, read the parameter 17.30 **SpdFbkLoss code**, PAR 2172, as described below.

Take the digits of the number in hexadecimal format and enter them in the table below:

	D7..D4	D3	D2	D1	D0
Value					

For each D0, D1, D2, D3 value other than 0x0 (0x0 = no alarm active) search for the sub-values it can be divided into in the table below.

D0 D1 D2 D3				
0x0	0x0	0x0	0x0	0x0
0x1	0x0	0x0	0x0	0x1
0x2	0x0	0x0	0x2	0x0
0x3	0x0	0x0	0x2	0x1
0x4	0x0	0x4	0x0	0x0
0x5	0x0	0x4	0x0	0x1
0x6	0x0	0x4	0x2	0x0
0x7	0x0	0x4	0x2	0x1
0x8	0x8	0x0	0x0	0x0
0x9	0x8	0x0	0x0	0x1
0xA	0x8	0x0	0x2	0x0
0xB	0x8	0x0	0x2	0x1
0xC	0x8	0x4	0x0	0x0
0xD	0x8	0x4	0x0	0x1
0xE	0x8	0x4	0x2	0x0
0xF	0x8	0x4	0x2	0x1

In the table regarding the type of encoder in use, search for the sub-values obtained from each D0, D1, D2, D3 digit in the corresponding columns Value.D0, Value.D1, Value.D2, Value.D3.

Example with Endat encoder:

PAR 2172 = A0H

Take the digits of the number in hexadecimal format and enter them in the table below:

	D7..D4	D3	D2	D1	D0
Value				0xA	0x0

For each D0, D1, D2, D3 value other than 0x0 search for the sub-values it can be divided into in table 1.

D0 D1 D2 D3				
0x0	0x0	0x0	0x0	0x0
0x1	0x0	0x0	0x0	0x1
0x2	0x0	0x0	0x2	0x0
0x3	0x0	0x0	0x2	0x1
0x4	0x0	0x4	0x0	0x0
0x5	0x0	0x4	0x0	0x1
0x6	0x0	0x4	0x2	0x0
0x7	0x0	0x4	0x2	0x1
0x8	0x8	0x0	0x0	0x0
0x9	0x8	0x0	0x0	0x1
0xA	0x8	0x0	0x2	0x0
0xB	0x8	0x0	0x2	0x1
0xC	0x8	0x4	0x0	0x0
0xD	0x8	0x4	0x0	0x1
0xE	0x8	0x4	0x2	0x0
0xF	0x8	0x4	0x2	0x1

For each D0, D1, D2, D3 value other than 0x0 search for the sub-values it can be divided into in table 1.

In the table regarding the type of encoder in use, search for the sub-values obtained from each D0, D1, D2, D3 digit in the corresponding columns Value.D0, Value.D1, Value.D2, Value.D3

Value.D1 = 2H

Cause: (CRC_CKS_P)disturbed SSI signals cause a CKS error or Parity.

Valore.D1 = 8H

Cause: (DT1_ERR) Encoder has detected a malfunction and signals this to the drive via Error bit. Bits 16..31 contain the type of malfunction detected by the encoder.

• Speed fbk loss [22] alarm with digital incremental encoder

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
0					0x1	CHA	Cause: no impulses or disturbance on incremental channel A. Solution: Check the connection of the encoder-drive channel A, check the connection of the screen, check the encoder supply voltage. Check parameters 2102 Encoder 1 supply and 2104 Encoder 1 input cfg (if encoder 1 is used). Check parameters 5102 Encoder 2 supply and 5104 Encoder 2 input cfg (if encoder 2 is used).
1					0x2	CHB	Cause: no impulses or disturbance on incremental channel B. Solution: Check the connection of the encoder-drive channel B, check the connection of the screen, check the Encoder 1 supply voltage. Check parameters 2102 Encoder 1 supply and 2104 Encoder 1 input cfg (if encoder 1 is used). Check parameters 5102 Encoder 2 supply and 5104 Encoder 2 input cfg (if encoder 2 is used).
2					0x4	CHZ	Cause: no impulses or disturbance on incremental channel Z.

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
							Solution: Check the connection of the encoder-drive channel Z, check the connection of the screen, check the Encoder 1 supply voltage. Check parameters 2102 Encoder 1 supply and 2104 Encoder 1 input cfg (if encoder 1 is used). Check parameters 5102 Encoder 2 supply and 5104 Encoder 2 input cfg (if encoder 2 is used).

- Speed fbk loss [22] alarm with sinusoidal incremental encoder

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
3					0x8	MOD_INCR	Cause: voltage level not correct or disturbance on signals of incremental channels A-B. Solution: Check the connection of the encoder-drive channels A-B, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2108 Encoder 1 signal Vpp .

- Speed fbk loss [22] alarm with SinCos encoder

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
3					0x8	MOD_INCR	Cause: voltage level not correct or disturbance on signals of incremental channels A-B. Solution: Check the connection of the the encoder-drive channels A-B, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2108 Encoder 1 signal Vpp .
4				0x1	0x0	MOD_ABS	Cause: voltage level not correct or disturbance on signals of absolute SinCos channels. Solution: Check the connection of the the encoder-drive channels A-B, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2108 Encoder 1 signal Vpp .

- Speed fbk loss [22] alarm with SSI absolute encoder

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
3					0x8	MOD_INCR	Cause: voltage level not correct or disturbance on signals of incremental channels A-B. Solution: Check the connection of the the encoder-drive channels A-B, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2108 Encoder 1 signal Vpp .
5				0x2	0x0	CRC_CKS_P	Cause: SSI signals not present or disturbed. Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2112 Encoder 1 SSI bits .
8			0x1	0x0	0x0	Setup error	Cause: An error occurred during setup. Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2112 Encoder 1 SSI bits .

- Speed fbk loss [22] alarm with EnDat absolute encoder

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
3					0x8	MOD_INCR	Cause: voltage level not correct or disturbance on signals of incremental channels A-B. Solution: Check the connection of the the encoder-drive channels A-B, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2108 Encoder 1 signal Vpp .
5				0x2	0x0	CRC_CKS_P	Cause: SSI signals not present or disturbed cause an error on CRC Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply .
8			0x1	0x0	0x0	Setup error	Cause: An error occurred during setup. Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply .

The following conditions occur while resetting the encoder following **Speed fbk loss [22]** activation

Bit	Value					Name	Description																																				
	D7.. D4	D3	D2	D1	D0																																						
6				0x4	0x0	ACK_TMO	Cause: SSI signals not present or disturbed cause an error on CRC Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply .																																				
7				0x8	0x0	DT1_ERR	Cause: Encoder has detected malfunction and signals this to the drive via bit DT1. Bits 16..31 contain the type of malfunction detected by the encoder. Solution: See the encoder manufacturer's technical guide.																																				
16.31	xxxx						<table><tr><th>Bit</th><th></th><th>=0</th><th>=1</th></tr><tr><td>0</td><td>Light source</td><td>OK</td><td>Failure (1)</td></tr><tr><td>1</td><td>Signal amplitude</td><td>OK</td><td>Erroneous (1)</td></tr><tr><td>2</td><td>Position value</td><td>OK</td><td>Erroneous (1)</td></tr><tr><td>3</td><td>Over voltage</td><td>NO</td><td>Yes (1)</td></tr><tr><td>4</td><td>Under voltage</td><td>NO</td><td>Under voltage supply (1)</td></tr><tr><td>5</td><td>Over current</td><td>NO</td><td>Yes (1)</td></tr><tr><td>6</td><td>Battery</td><td>OK</td><td>Change the battery (2)</td></tr><tr><td>7..15</td><td></td><td></td><td></td></tr></table> (1) Can also be set after the power supply is switched off or on. (2) Only for battery-buffered encoders	Bit		=0	=1	0	Light source	OK	Failure (1)	1	Signal amplitude	OK	Erroneous (1)	2	Position value	OK	Erroneous (1)	3	Over voltage	NO	Yes (1)	4	Under voltage	NO	Under voltage supply (1)	5	Over current	NO	Yes (1)	6	Battery	OK	Change the battery (2)	7..15			
Bit		=0	=1																																								
0	Light source	OK	Failure (1)																																								
1	Signal amplitude	OK	Erroneous (1)																																								
2	Position value	OK	Erroneous (1)																																								
3	Over voltage	NO	Yes (1)																																								
4	Under voltage	NO	Under voltage supply (1)																																								
5	Over current	NO	Yes (1)																																								
6	Battery	OK	Change the battery (2)																																								
7..15																																											

- Speed fbk loss [22] alarm with Hiperface absolute encoder

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
3					0x8		Cause: voltage level not correct or disturbance on signals of incremental channels A-B. Solution: Check the connection of the the encoder-drive channels A-B, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply , check parameter 2108 Encoder 1 signal Vpp .
5				0x2	0x0		Cause: disturbed SSI signals cause a CKS error or Parity

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
							Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply.
6				0x4	0x0		Cause: Encoder does not recognise the command that has been sent to it and replies with ACK. The SSI signals not present cause a TMO error. Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply.
8			0x1	0x0	0x0		Cause: An error occurred during setup. Solution: Check the connection of the clock and encoder-drive data, check the connection of the screen, check the encoder supply voltage, check parameter 2102 Encoder 1 supply.

The following conditions occur while resetting the encoder following **Speed fbk loss [22]** activation.

Bit	Value					Name	Description		
	D7.. D4	D3	D2	D1	D0				
7				0x8	0x0	DT1_ERR	Cause: Encoder has detected malfunction and signals this to the drive via Error bit. Bits 16..31 contain the type of malfunction detected by the encoder. Solution: See the encoder manufacturer's technical guide.		
16.31	xxxx						Type	Code	Description
							Transmis- sion	09h	Transmitted parity bit is incorrect
								0AH	Checksum of transmitted data is wrong
								0BH	Incorrect command code
								0CH	Wrong number of transmitted data
								0DH	Illegal transmitted command argument
								0FH	Wrong access authorization specified
								0EH	Selected field has READ ONLY status
								10H	Data field (re) definition not executable due to field size
								11H	Specified address is not available in selected field
								12H	Selected field does not yet exist
								00H	No encoder error, no error message
								03H	Data field operations disabled
								04H	Analog monitoring inoperative
								08H	Counting register overflow
								01H	Encoder analog signals are unreliable
								02H	Wrong synchronisation or offset
								05H- 07H	Encoder-internal hardware fault, no operation possible
								1CH- 1DH	Error in sampling, no operation possible
								1EH	Permissible operation temperature is exceeded
							(1) Can also be set after the power supply is switched off or on. (2) Only for battery-buffered encoders		

- **Speed fbk loss [22] alarm with Resolver**

Code	Name	Error description	Possible solution
0x00000001	D0 FAULT REGISTER	Configuration parity error	Reset Resolver card
0x00000002	D1 FAULT REGISTER	Phase error exceeds phase lock range	
0x00000004	D2 FAULT REGISTER	Velocity exceeds maximum tracking rate	
0x00000008	D3 FAULT REGISTER	Tracking error exceeds LOT (Loss of Signal) threshold	

Code	Name	Error description	Possible solution
0x00000010	D4 FAULT REGISTER	SIN/COS inputs exceed DOS (Degradation of signal) mismatch threshold	Check the connection of the Resolver input pins (SIN-, SIN+, COS-, COS+), check PAR 2128
0x00000020	D5 FAULT REGISTER	SIN/COS inputs exceed DOS (Degradation of signal) over range threshold	Check the connection of the Resolver input pins (SIN-, SIN+, COS-, COS+)
0x00000040	D6 FAULT REGISTER	SIN/COS inputs below LOS (Loss of Signal) threshold	Check the connection of the Resolver input pins (SIN-, SIN+, COS-, COS+), check PAR 2124
0x00000080	D7 FAULT REGISTER	SIN/COS inputs clipped	Check if any of the Resolver input pins (SIN-, SIN+, COS-, COS+) are shorted with power input or ground of the resolver board

C-1.1 Reset Speed fbk loss alarm

The reasons for activating the **Speed fbk loss** alarm and the information acquired by the encoder are shown in parameter 2172 **SpdFbkLoss code**.

If no card has been installed the **Speed fbk loss** [22] alarm is generated and no cause is displayed in parameter 2172 **SpdFbkLoss code**. Several causes may be present at the same time.

If no card is recognised, the system runs a routine that always returns **Speed fbk loss** [22] active without specifying a cause.

C-1.2 Encoder error alarm

Setup is performed each time the drive is turned on, regardless of the regulation mode that has been selected. If an error is detected during setup the **Encoder error** alarm is generated with the following codes:

Bit	Value					Name	Description
	D7.. D4	D3	D2	D1	D0		
8			0x1	0x0	0x0	Setup error	Cause: An error occurred during setup. When this has been signalled the information obtained from the encoder is not reliable. Solution: Take the action recommended for Speed fbk loss [22] alarm according to the type of encoder.
9			0x2	0x0	0x0	Compatibility error	Cause: Firmware on option card incompatible with firmware on regulation card. When this has been signalled the information obtained from the encoder is not reliable. Solution: Contact Gefran in order to update the firmware on the optional card.

C-2 “ExtIO fault” Alarm

The drive may generate an “ExtIO fault” alarm for a series of reasons. At drive startup there may be problems with configuration, associated with the EXP-FL-XCAN-ADV card or parameter settings. During the Config phase the alarm might depend on an SDO communication error. During the Control phase the HeartBeat or NodeGuarding protocol might fail due to an interruption in the communication with the slave. An Emergency message sent by the slave could generate the “ExtIO fault” alarm.

Each reason for the alarm can be identified by to the associated subcode.

The table below shows information about the subcodes and how to associate these with the cause of the alarm, to enable troubleshooting and proper use of the system.

Subcode		Description	Remarks
0	0	BusLoss	Loss of communication in the Operational state
1..51	1h..35h	SDO error	Error sending the SDO. See the SDO Configuration Table on appendix to identify the object with the problem
200	0xC8	CAN error	Internal hardware fault; if the problem cannot be solved, replace the regulation card
202	0xCA	Config error	The number or I/Os in the slave module has changed. Check parameter 5482 External IO info . Save the parameters to store the current configuraiton.
203	0xCB	Lost Messages	TPDOs coming from the slave too frequently. Check that the slave meets CAN-open specifications for TPDO sending times
204	0xCC	Opt IO installed	An optional internal I/O expansion card has been installed. The EXP-XCAN-ADV card functions are not available.
255..65535	0xFF..0xFFFF	Slave Emergency	Emergency message sent by the slave.

If the alarm is due to an Emergency message sent by the slave, the subcode contains the error code (Error code low and Error code Hi) of the message, while 4 of the 5 additional bytes in the message are shown by parameter 5486 **External IO Failcode**.

Emergency message content:

Byte0	Byte1	Byte2	Byte3	Byte4	Byte5	Byte6	Byte7
Error code Low	Error code Hi	Error register	Info 0	Info 1	Info 2	Info3	Info4
Subcode	PAR 5486 External IO Failcode						

See the slave manual for information about the meaning of the Emergency message.

C-3 “Fastlink” Alarm

Reasons why the FastLink alarm is generated:

Bit					Name	Description
	D3	D2	D1	D0		
0				0x1	Cks	Cause: The drive has detected a checksum error Solution: Take all the necessary precautions to increase the resistance of the drive to disturbance
1				0x2	Not used	Cause: Solution:
2				0x4	Not used	Cause: Solution:
3				0x8	Not used	Cause: Solution:
4			0x1		Not used	Cause: Solution:
5			0x2		RX Timeout	Cause: The slave drive has not received a new data frame for 2 consecutive cycles. Solution: Take all the necessary precautions to increase the resistance of the drive to disturbance
6			0x4		Pwm sync slave	Cause: On the slave drives there is a problem with the function that enables the generation of Pwm signals to be synchronised with the Pwm signals of the master and with the function that enables the execution of control tasks to be synchronised with execution of control tasks by the master. An error exceeding the maximum error allowed has been detected for 4 consecutive cycles. Solution: Take all the necessary precautions to increase the resistance of the drive to disturbance
7			0x8		Cable open	Cause: No optical fibre. Solution: Check connection with optical fibre.
8		0x1			Setup error	Cause: An error occurred during setup; the information received from the FastLink is not reliable. Solution: Check setting of FastLink parameters.
9		0x2			Compatibility error	Cause: The firmware on the optional FastLink card is incompatible with that on the regulation card. Solution: Contact Gefran in order to update the firmware on the optional fastlink card.
10		0x4			Slave answer NOK	Cause: situation in which an interrogated Slave does not reply Solution: check FastLink connection

D – MESSAGES

Note ! For more information see Quick start guide, **chapter 6.7**.

Index	Error message shown on the display	Sub-code	Description
1	Load default param	Condition: may occur during loading of the parameter database saved in flash normally appears in the following conditions: at initial power-on when a new firmware version is downloaded, when the regulation is installed on a new size, when the region is changed. If this message is displayed when the drive is already operating, this means that a problem has occurred in the parameter database saved in Flash. If this message is displayed the drive restores the default database, i.e. the one downloaded.	
		0001H-1	The database saved is not valid
		0002H-2	The database saved is not compatible
		0003H-3	The database saved refers to a different size from the current size
		0004H-4	The database saved refers to a different region from the current region
		Solution: Set the parameters to the value required and perform Save parameter	
		2 3 4	Option detect slot 1 Option detect slot 2 Option detect slot 3
0H-0	None		
0004H-4	Can/DeviceNet		
00FFH-255	Unknown		
0104H-260	Profibus		
0204H-516	Rte		
0208H-520	Enc 3 EXP-SESC- I1R1F2-ADV		
0301H-769	I_0_1		
0308H-776	Enc 4 EXP-EN/SSI- I1R1F2-ADV		
0408H-1032	Enc 5 EXP-HIP- I1R1F2-ADV		
0608H-1544	Enc 1 EXP-DE-I1R1F2-ADV		
0701H-1793	I_0_2		
0108H-1800	Enc 2 EXP-SE-I1R1F2-ADV		
0808H-2056	Enc 7 EXP-DE-I2R1F2-ADV		
0901H-2305	I_0_3		
0D01H-3329	I_0_4		
0508H-1288	Enc 6 EXP-RES-I1R1-ADV		
908H-2312	Enc 8 EXP-ASC-I1-ADV		
Solution:			
5	Autotune		
		0	No error
		1	The commands are not configured in Local mode.
			Solution: Execute the requested configuration
		2	The Commands local sel parameter has not been configured from the keypad
			Solution: Execute the requested configuration
		3	The motor plate data parameters have changed but the Take parameters command, PAR 2020, has not been executed
			Solution: Execute the Take parameters command.
		4	Error in motor connection.
			Solution: Check the motor connection, set the value of the direct current of the motor to 1/3 and perform the motor autotune procedure. Then increase the direct current until autotuning is executed. The penultimate value is the nominal current value at which the drive performs autotuning.
		5	While running self-tuning the ESC key was pressed or the enable contact was opened or an alarm occurred. The Autotune command was sent with the drive in the alarm condition
			Solution: Eliminate the reason for the alarm, remove the reason for the opening of the enable contact, reset alarms.
		6	A setting performed by the Autotune function produced a parameter value outside the min or max range.
			Solution: Check the motor plate data or drive and motor sizes have been combined incorrectly.
		7	The Autotune command was sent without being enabled.
			Solution: Close the enable contact before sending the Autotune command

Index	Error message shown on the display	Sub-code	Description
		8	Internal calculation error concerning IGBT control Solution: Perform autotuning once more, if the problem persists, contact the Gefran technical support centre.
		9	The drive has measured a stator resistance value exceeding the set limit. Solution: contact the Gefran technical support centre.
		10	The drive has measured a stator resistance value below the set limit. Solution: contact the Gefran technical support centre.
		11-12	Measurement of DTL internal compensation voltage outside accepted range. Solution: check connection between drive and motor. If correct, the drive is faulty, contact the Gefran technical support centre.
		13-14	Measurement of DTS internal voltage outside accepted range. Solution: check connection between drive and motor. If correct, the drive is faulty, contact the Gefran technical support centre.
		15 - 16 - 17	LS leakage inductance value outside accepted range. Solution: Perform autotuning once more, if the problem persists, contact the Gefran technical support centre.
6	Power config	18-19	Measurement of Im magnetising current outside accepted range. Solution: Perform autotuning once more, if the problem persists, contact the Gefran technical support centre.
		20-21	Measurement of Rr rotor resistor outside accepted range. Solution: Perform autotuning once more, if the problem persists, contact the Gefran technical support centre.
		Solution: If the message appears with a value other than 0, follow the instructions supplied for each particular case and repeat Autotune . This should be performed using the wizard function available from the keypad (STARTUP WIZARD) and the Tool software on the PC. Pay attention to all motor plate data parameters, especially: - Rated speed, Motor rated speed in rpm. - Rated frequency, Motor rated frequency in Hz - Pole pairs, Motor pole pairs Take care not to set the Rated speed parameter to the synchronous speed. The value of the Rated speed parameter must be less than: $[(\text{Rated frequency} * 60) / \text{Pole pairs}]$. If the problem persists even after following the instructions supplied, confirm the values of the motor plate data parameters, execute the Take parameters command but not Autotune .	
6	Power config	Condition: may occur during recognition of power cards. If this message is displayed, it is not possible to drive the motor.	
		0020H-32	The power card is configured for a drive that is incompatible with the regulation card
		0021H-33	The configuration of the power card is not compatible with the regulation card
		0017H-23	The configuration required is not available on the power card
		Solution: Download the correct configuration on the power card	
7	Save par failed	Condition: during transfer of the parameters from the drive to the memory of the keypad	
		0H-0	Communication error
		0025H-37	The data saved on the keypad are not valid
		0026H-38	Incompatible drive series
		0027H-39	Incompatible software version
		0028H-40	Incompatible drive size
		0029H-41	Error during saving of parameters on the drive
		Solution:	
8 9	Load par failed Load par incomplete	Condition: during transfer of the parameters from the memory of the keypad to the drive	
		0H-0	Communication error
		0025H-37	The data saved on the keypad are not valid. No parameter is transferred from the keypad to the drive
		0026H-38	Incompatible control type. No parameter is transferred from the keypad to the drive
		0027H-39	Incompatible software version. All the parameters present in the memory of the keypad have been transferred to the drive. The set of parameters transferred refers to a drive with a different firmware version; therefore, certain parameters may not be updated.
		0028H-40	Incompatible control type. All the parameters present in the memory of the keypad (excluding those that depend on the size of the drive), have been transferred to the drive. The parameters that depend on size maintain their original value.

Index	Error message shown on the display	Sub-code	Description
		0029H-41	Error during saving of parameters on the drive. All the parameters present in the memory of the keypad have been transferred to the drive. The transfer of one or more parameters has caused an "out of range" error, or one or more parameters does not exist. At the end of transfer, one or more parameters may not have been updated.
		002AH-42	PLC application release and version not compatible. All parameters in the keypad memory have been transferred to the drive. The transferred set of parameters relates to a drive with a PLC application in which the version and release of the application are different. As a result some of the PLC application parameters may not be updated.
		002BH-43	PLC application not compatible. All the parameters in the keypad memory except those relating to the PLC application have been transferred to the drive. The transferred set of parameters relates to a drive with a different PLC application. As a result none of the PLC application parameters are updated.
		Solution: Recover a set of parameters from a compatible drive (model and size)	
10	Options config error	Condition: may occur at drive start-up, during recognition of the optional cards installed	
		0001H-1	Non-permissible optional card in slot 1
		0002H-2	Non-permissible optional card in slot 2
		0004H-4	Non-permissible optional card in slot 3
		0010H-16	Conflict slot 1 with slot 2
		0020H-32	Conflict slot 1 with slot 3
		0040H-64	Conflict slot 2 with slot 3
		Solution: Remove the optional cards from the incorrect slots and insert them in the correct slots	
11	Load def plc	Condition: may occur during loading of the parameter database saved in the Flash of the Mdplc application Normally appears at initial power-on after downloading a new application. If this message is displayed when the drive is already operating, this means that a problem has occurred in the parameter database saved in Flash. If this message appears the drive restores the default database, i.e. the one that was downloaded.	
		0001H-1	The database saved is not valid
		Solution: Set the parameters to the value required and perform Save parameter	
12	Plc cfg error	Condition: may occur during loading of the Mdplc application The Mdplc application present on the drive is not run.	
		0004H-4	The application downloaded has a different Crc on DataBlock and Function table
		0065H-101	The application downloaded has an invalid identifier (Info)
		0066H-102	The application downloaded has an incorrect task number (Info)
		0067H-103	The application downloaded has an incorrect software configuration
		0068H-104	The application downloaded has a different Crc on DataBlock and Function table
		0069H-105	A Trap error or System error has occurred. The drive automatically performs a Power-up operation. The application is not run. See in Alarm List for further information regarding the error occurred
		006AH-106	The application downloaded has an incorrect identifier (Task)
		006BH-107	The application downloaded has an incorrect task number (Task)
		006CH-108	The application downloaded has an incorrect Crc (Tables + Code)
		Solution: Remove the Mdplc application or download a correct Mdplc application	
13	Plc 1	Reserved messages and dedicated to the PLC application. See the application manual.	
14	Plc 2		
15	Plc 3		
16	Plc 4		
17	Option bus fault	Condition: this may occur when the drive is turned on, during fieldbus card setup. Error during configuration or communication error.	
		XXX0H-X	If the first digit to the left of "H" in the alarm sub-code is 0, the error regards a communication problem.
		XXX0H-X	If the first digit to the left of "H" in the alarm sub-code is other than 0, the error regards a configuration problem.
		Solution: For configuration errors, check the configuration of the bus communication, type of bus, baudrate, address, parameter setting. For communication errors, check wiring, termination resistors, disturbance immunity, timeout settings. For further details, please refer to the user guide for the specific bus.	
18	Key failed	Condition: this may occur when powering the drive, if the incorrect enable key is inserted for a given firmware function.	

Index	Error message shown on the display	Sub-code	Description
		0001H-1	Incorrect PLC key. PLC application not available. Solution: Ask Gefran to supply the correct key to enable the desired firmware function.
19	Key expiring		Condition: this may occur at drive power-on if the incorrect enabling key was inserted for a given firmware function. At this stage the firmware function can still be used freely, but this time limit is about to expire. xxxxH-x Number of hours for which the function can still be used freely. Solution: Ask Gefran for the correct key to enable the desired firmware function.
20	Param error		Condition: if an error occurs during activation of the parameter database saved in flash; the alarm is inserted in the alarm list and alarm log. XXX0H-X The code XXXXH-X indicates the IPA of the parameter that has been set outside the range allowed when the database is enabled. Solution: Set the parameter causing the error to a value within the range and run Save parameters . Switch the drive off and then switch it back on again. If the IPA of the parameter is not shown in the manual, contact the service centre.
21	Encoder error		Condition: this condition may occur when the drive is powered during encoder setup each time parameter 552 Regulation mode is set. 100H-2564 Cause: An error occurred during setup; the information received from the encoder is not reliable. If the encoder is used for feedback the Speed fbk loss [22] alarm is also generated. Solution: Take the recommended action for the Speed fbk loss[22] alarm. 200H-512 Cause: The firmware on the optional encoder card is incompatible with that on the regulation card. The information received from the encoder is not reliable Solution: Contact Gefran in order to update the firmware on the optional encoder card.
22	Options cfg changed		Condition: this may occur when powering the drive if an expansion card has been removed or replaced or the incorrect enable key is inserted for a given firmware function. 0064H-100 Card removed from slot 1 0014H-20 Card removed from slot 2 0003H-3 Card removed from slot 3 0078H-120 Card removed from slot 1 and from slot 2 0067H-103 Card removed from slot 1 and from slot 3 0017H-23 Card removed from slot 2 and from slot 3 007BH-123 Card removed from slot 1, from slot 2 and from slot 3 Solution: Check the hardware configuration, then press ESC. Save the parameters (Save parameters , menu 04.01 par 550) to save the new hardware configuration.
23	Safe start active		Condition: The drive was restarted when PAR 1010 Safe Start Command = ON and in presence of Enable command. Solution: Press the ESC key to cancel the message You have to disable the Enable command to restart the drive.

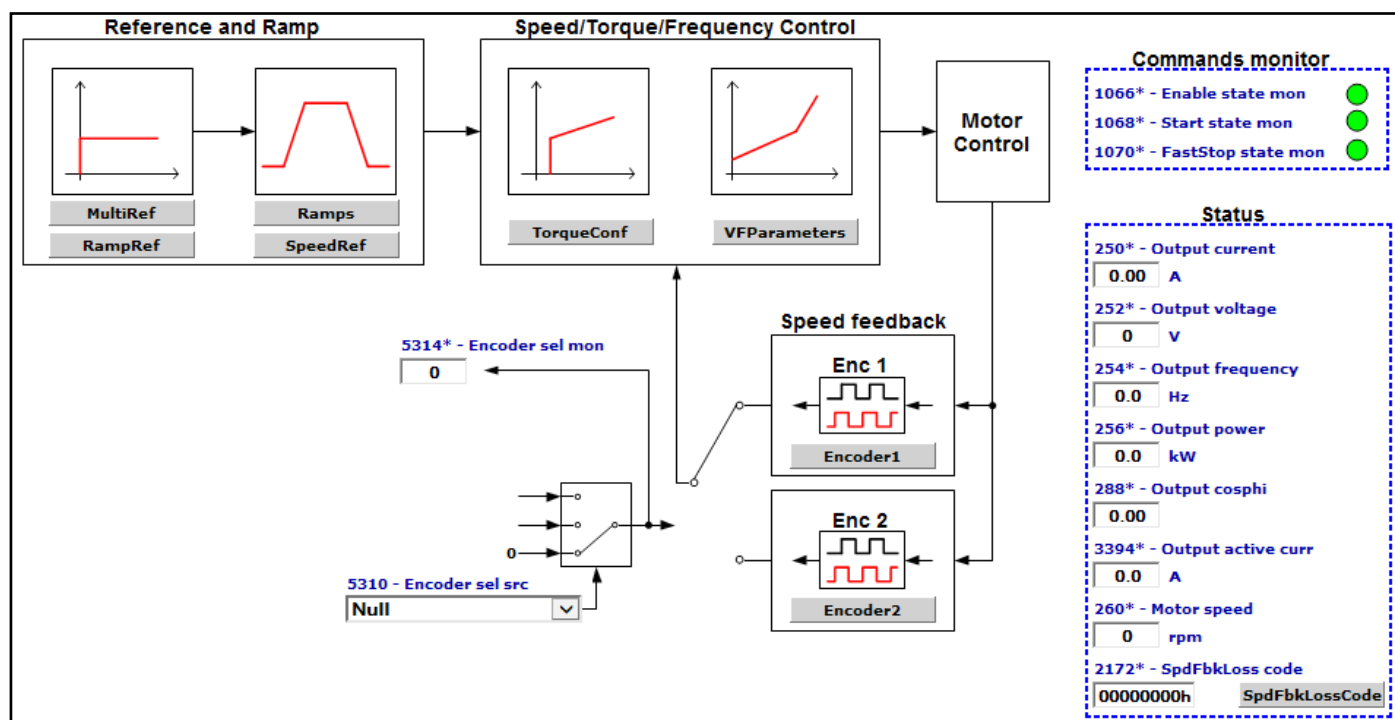
Note!

For any messages that are displayed but not included in this list reference should be made to the manual for the MDPLc application used by the drive.

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REFERENCES	References	AnalInps	ANALOG INPUTS
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MOTORPOTENTIOMETER	Mpot	SpeedRegGains	SPEED REG GAINS
JOG FUNCTION	Jog	TorqueConf	TORQUE CONFIG
MONITOR FUNCTION	MonitorFunc	VFParameters	VF PARAMETERS
COMMANDS	Commands	Functions	FUNCTIONS
DIGITAL INPUTS	DigInps	AppIndex	APPLICATIONS DIAGRAMS INDEX

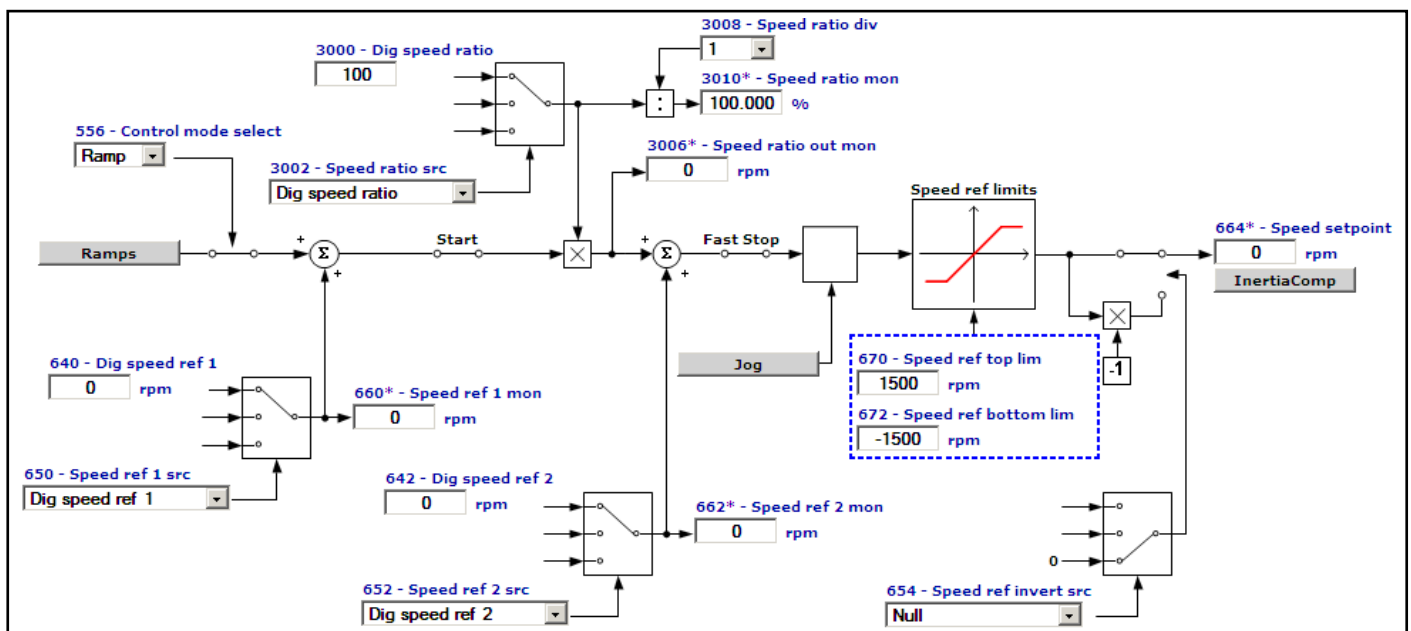
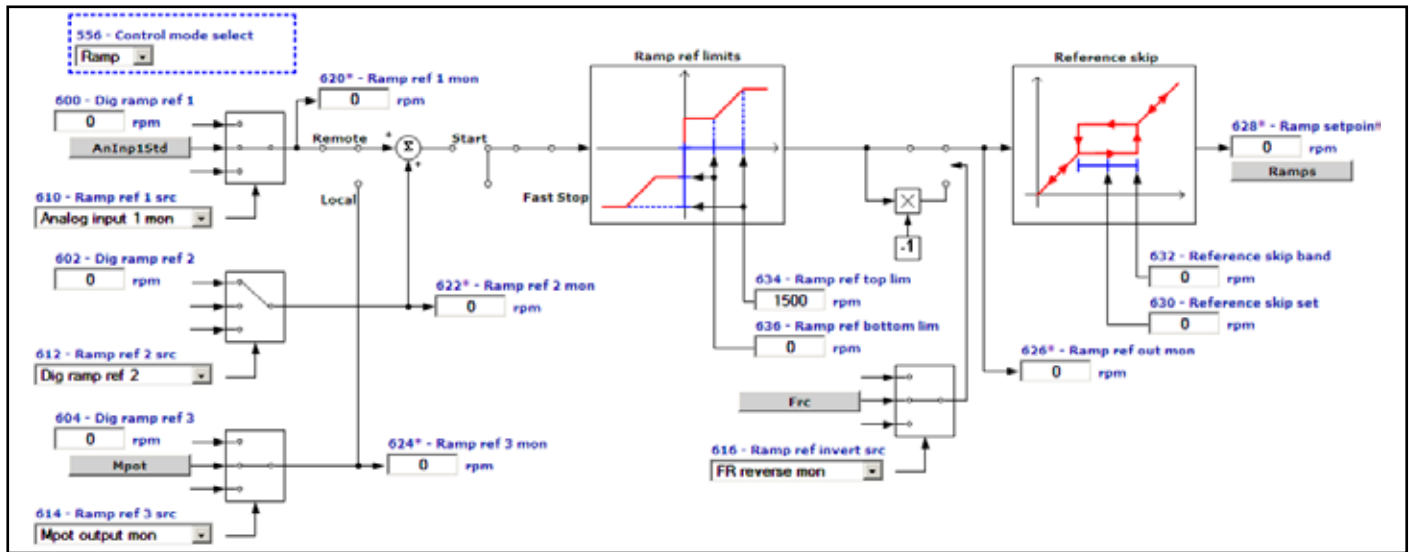
Drive overview



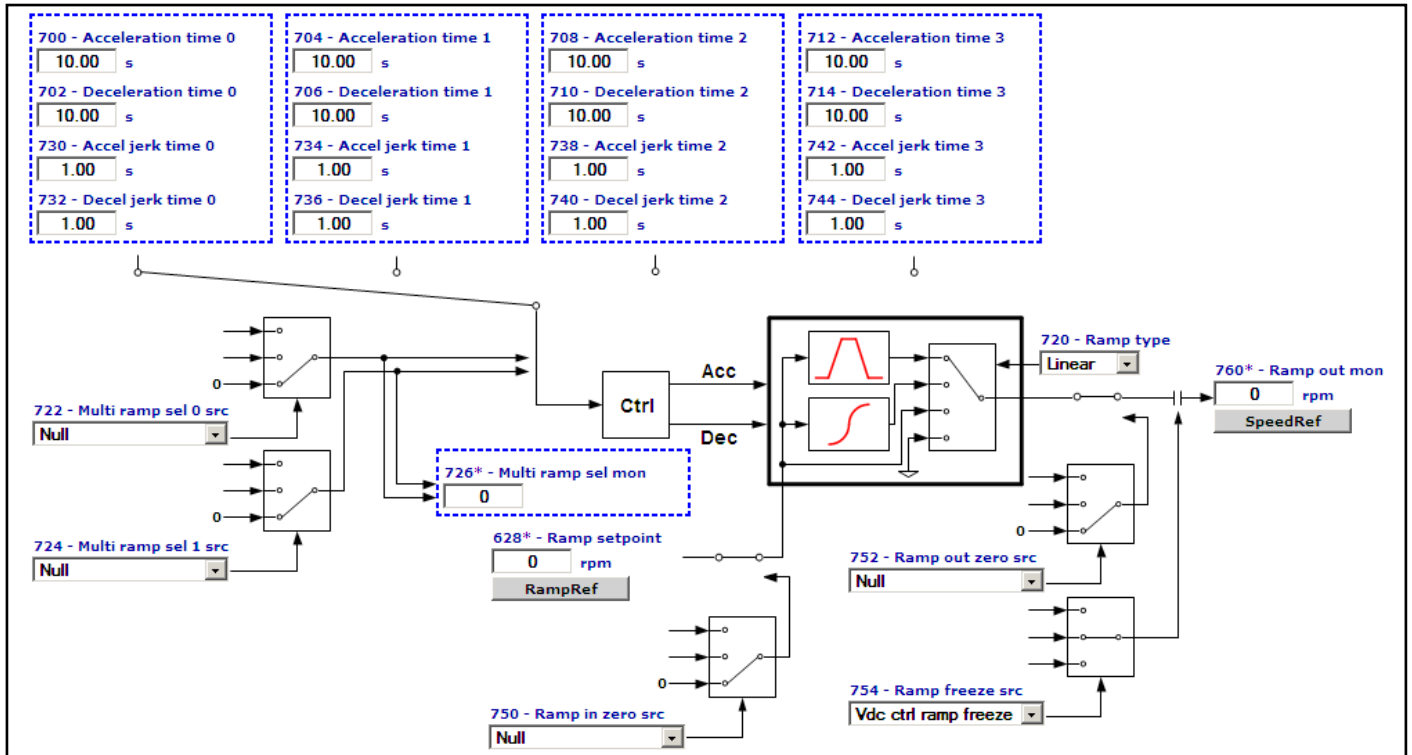
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RAMP REFERENCE RampRef

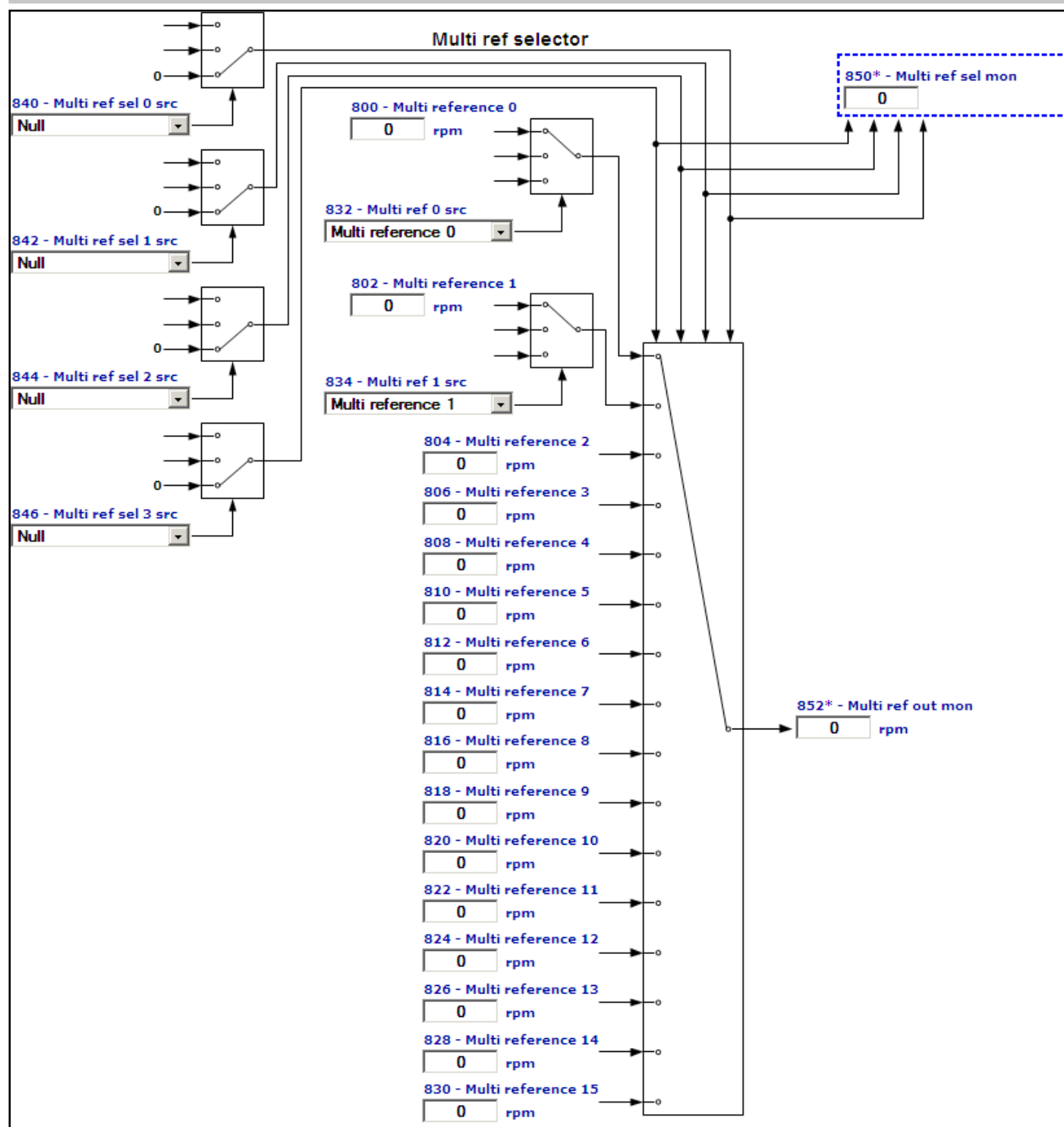
SPEED REFERENCE SpeedRef



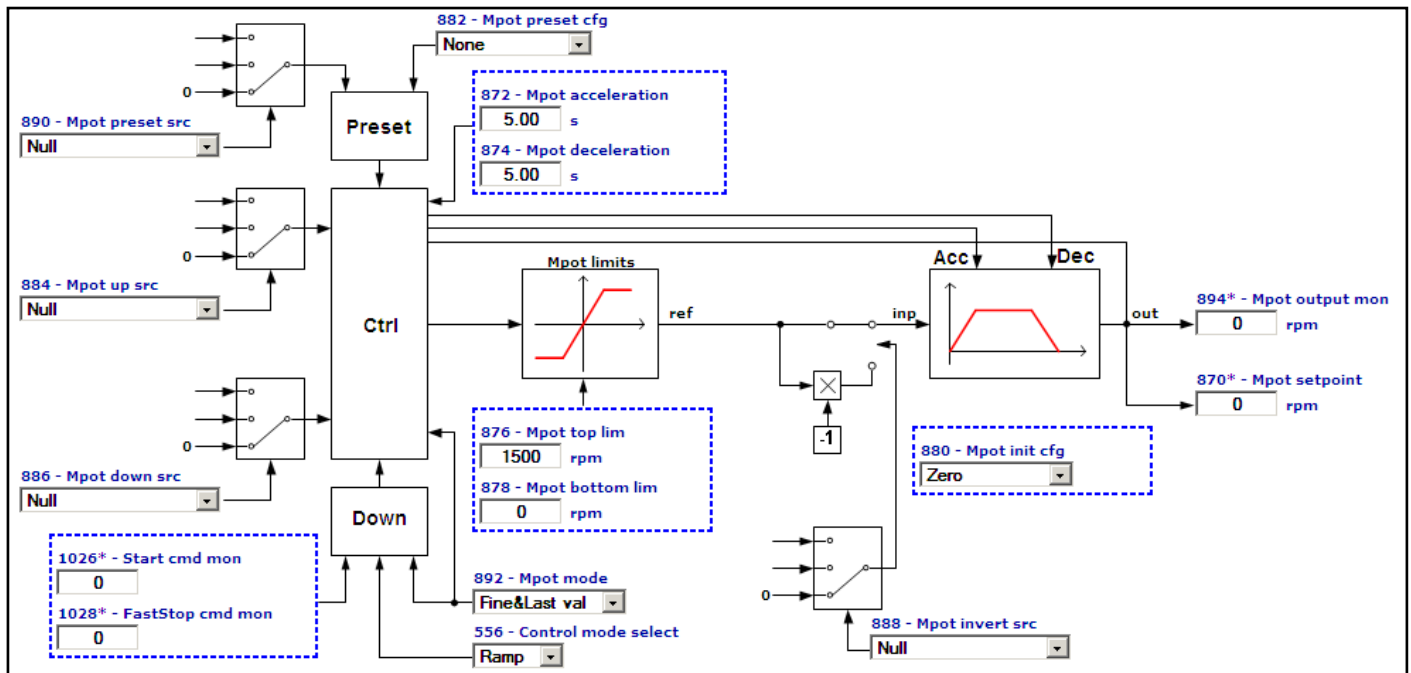
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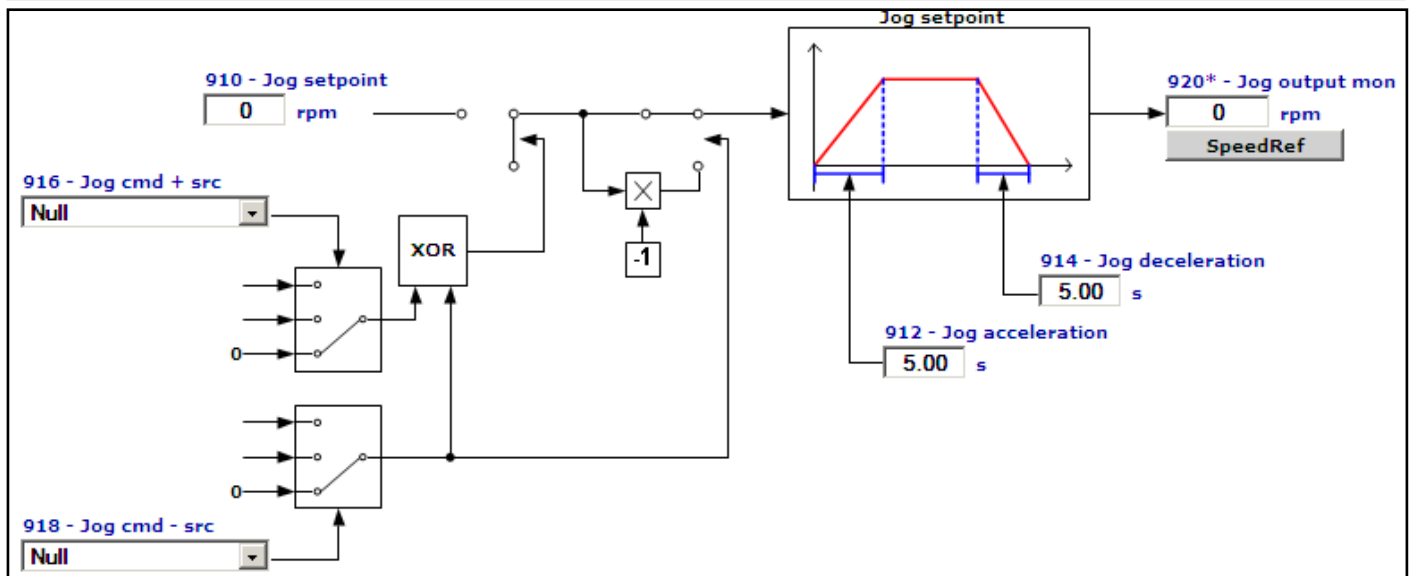
Multireference



Motorpotentiometer

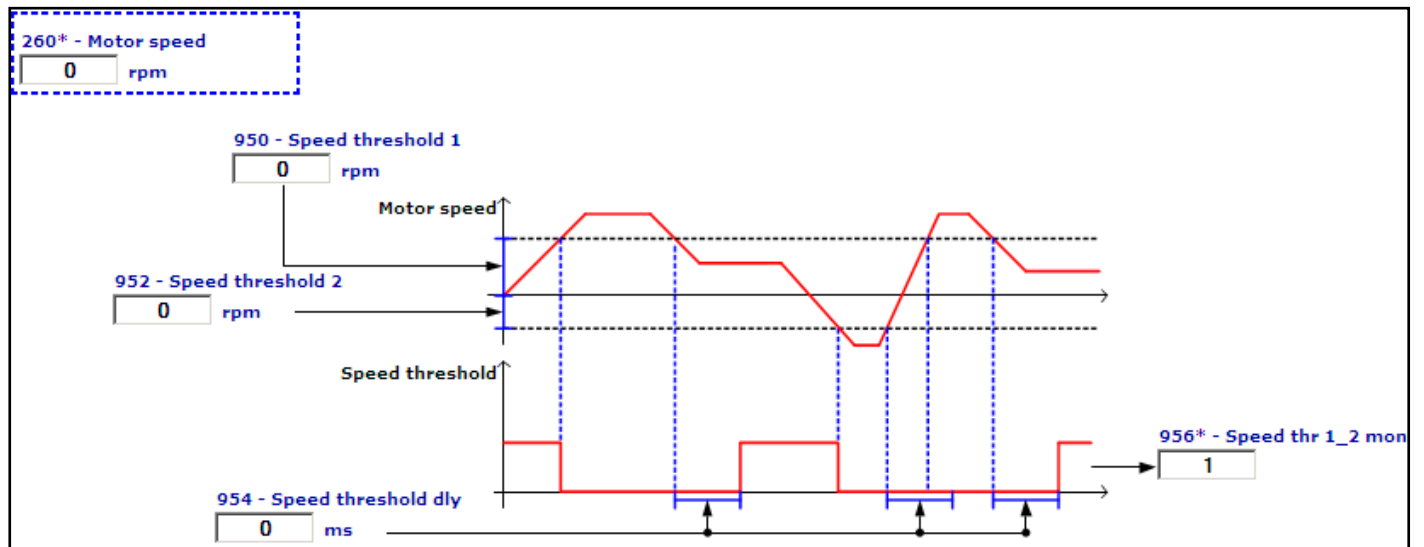
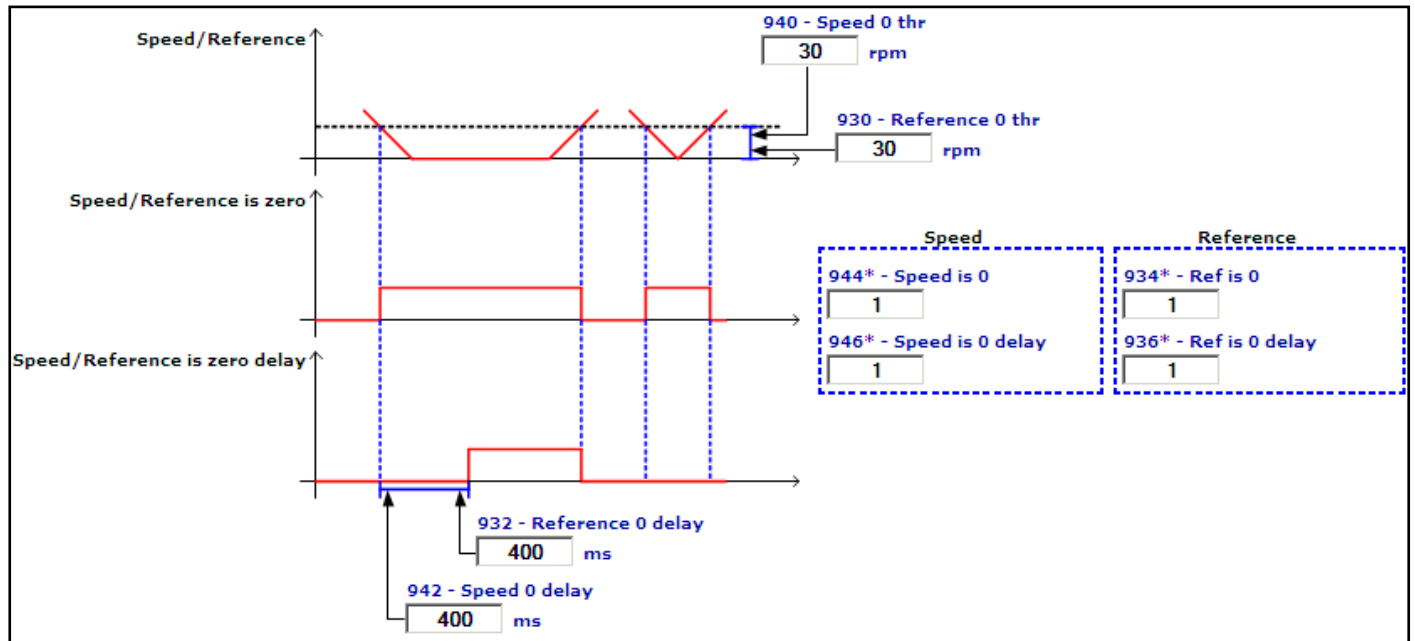


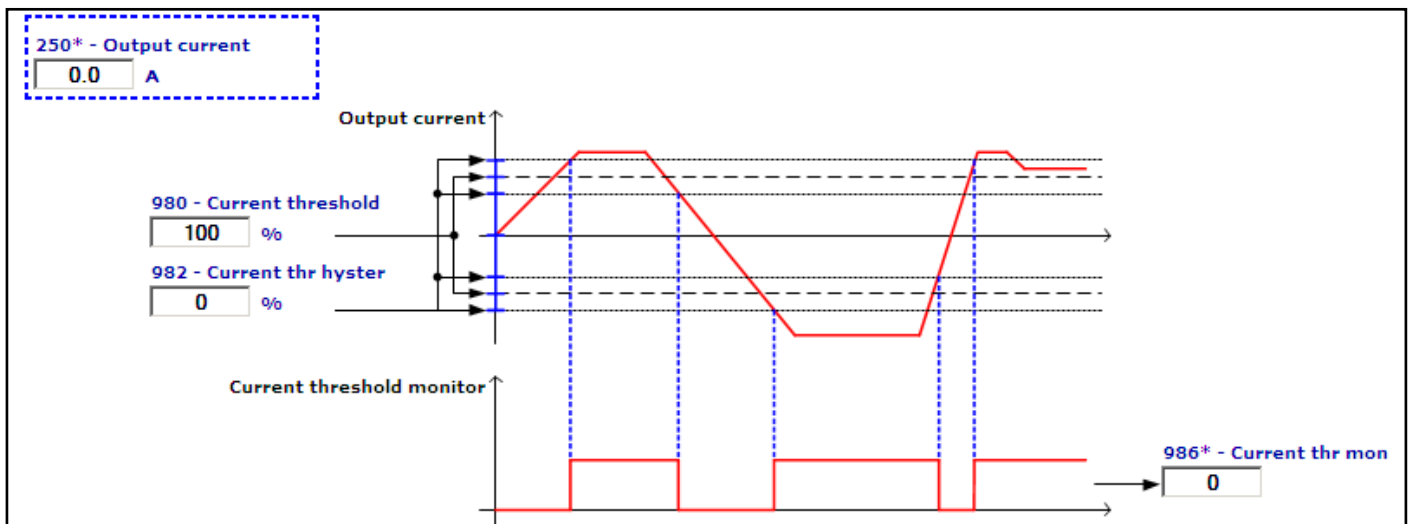
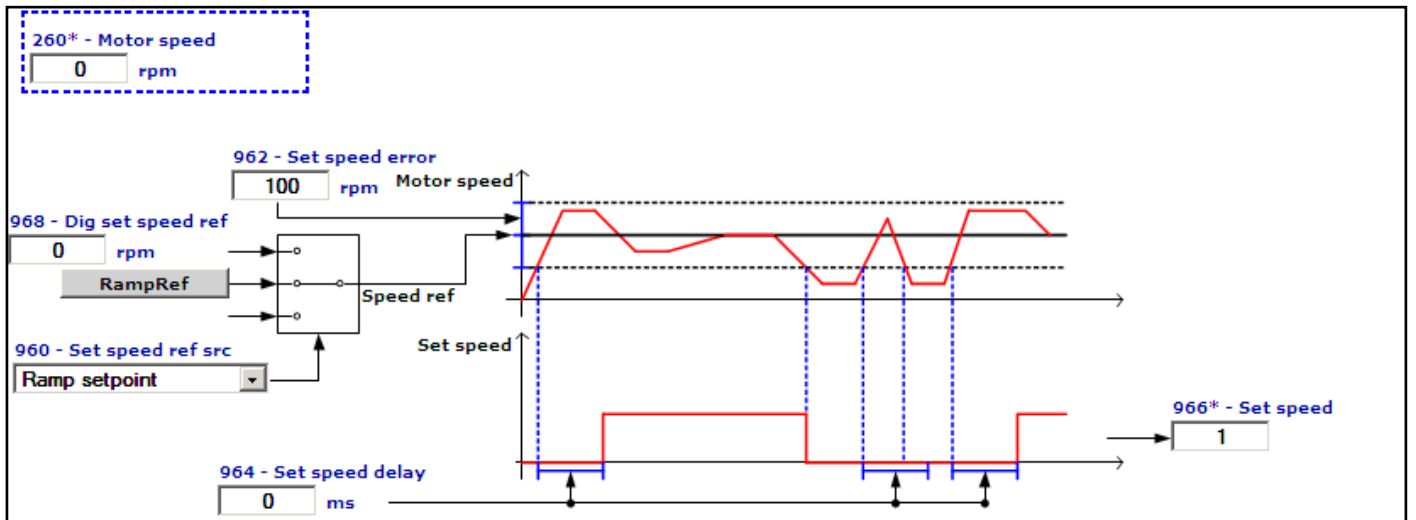
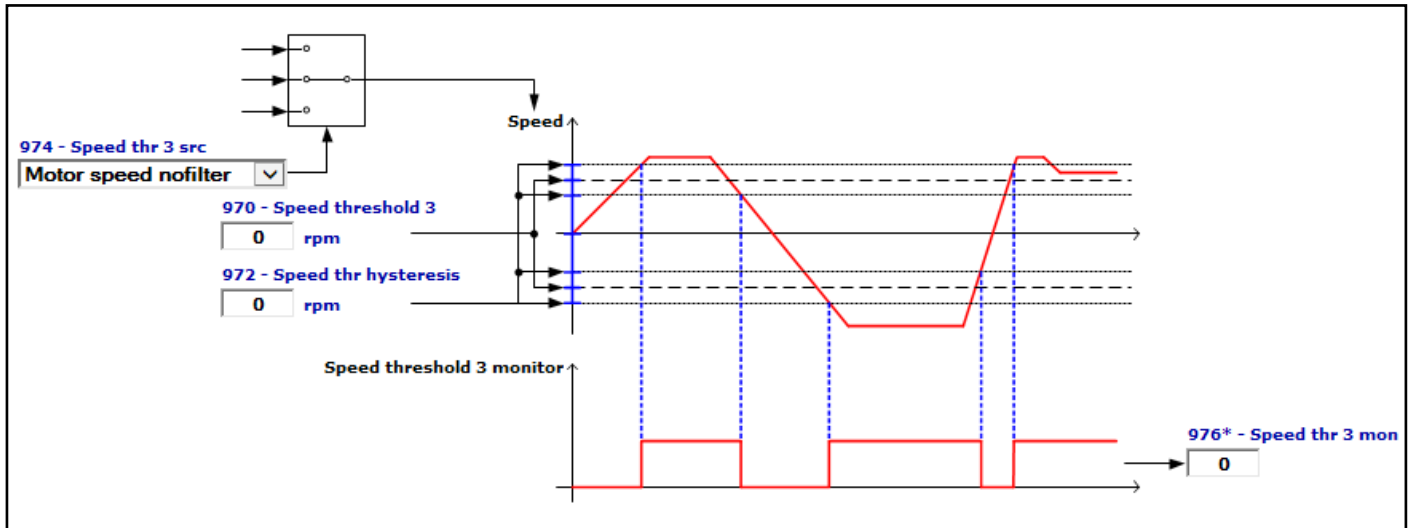
Jog function



Monitor function

SPEED/REFERENCE ZERO	SpeedRefZero
SPEED THRESHOLD 1-2	SpeedThr1_2
SPEED THRESHOLD 3	SpeedThr3
SET SPEED	SetSpeed
CURRENT THRESHOLD	CurrThr





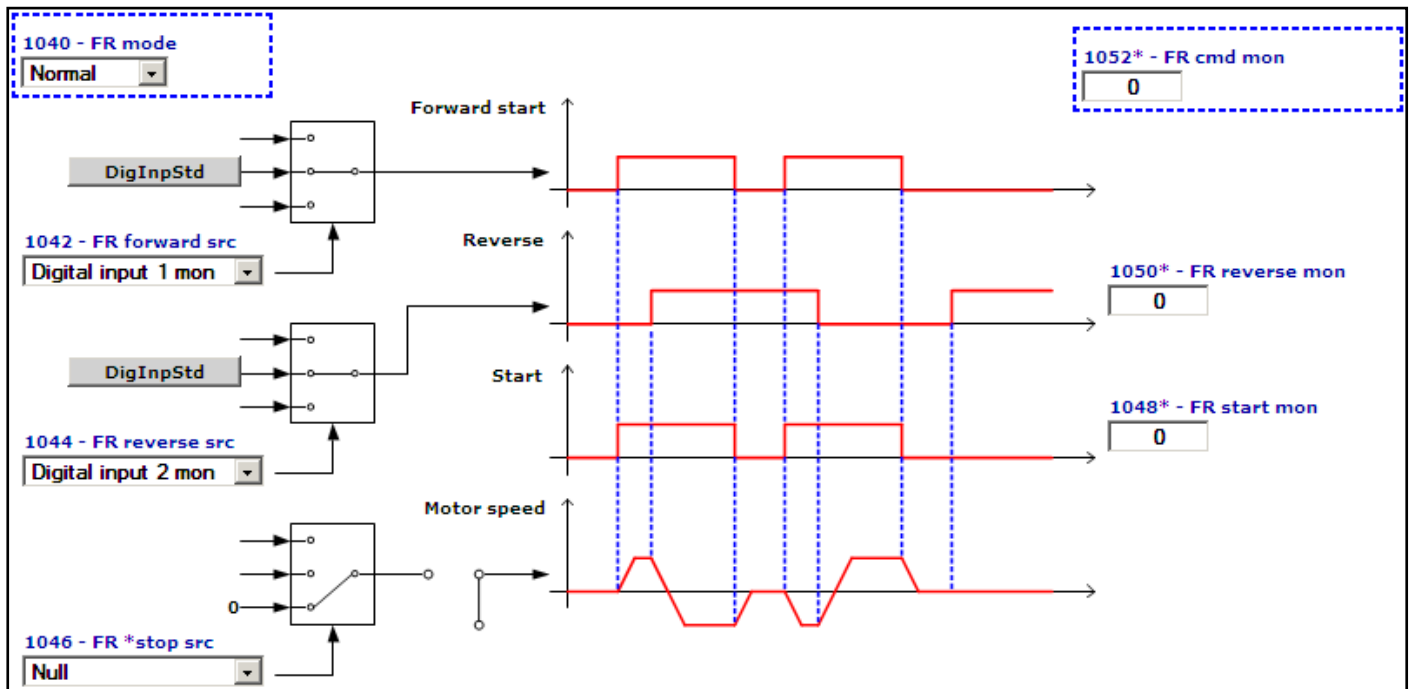
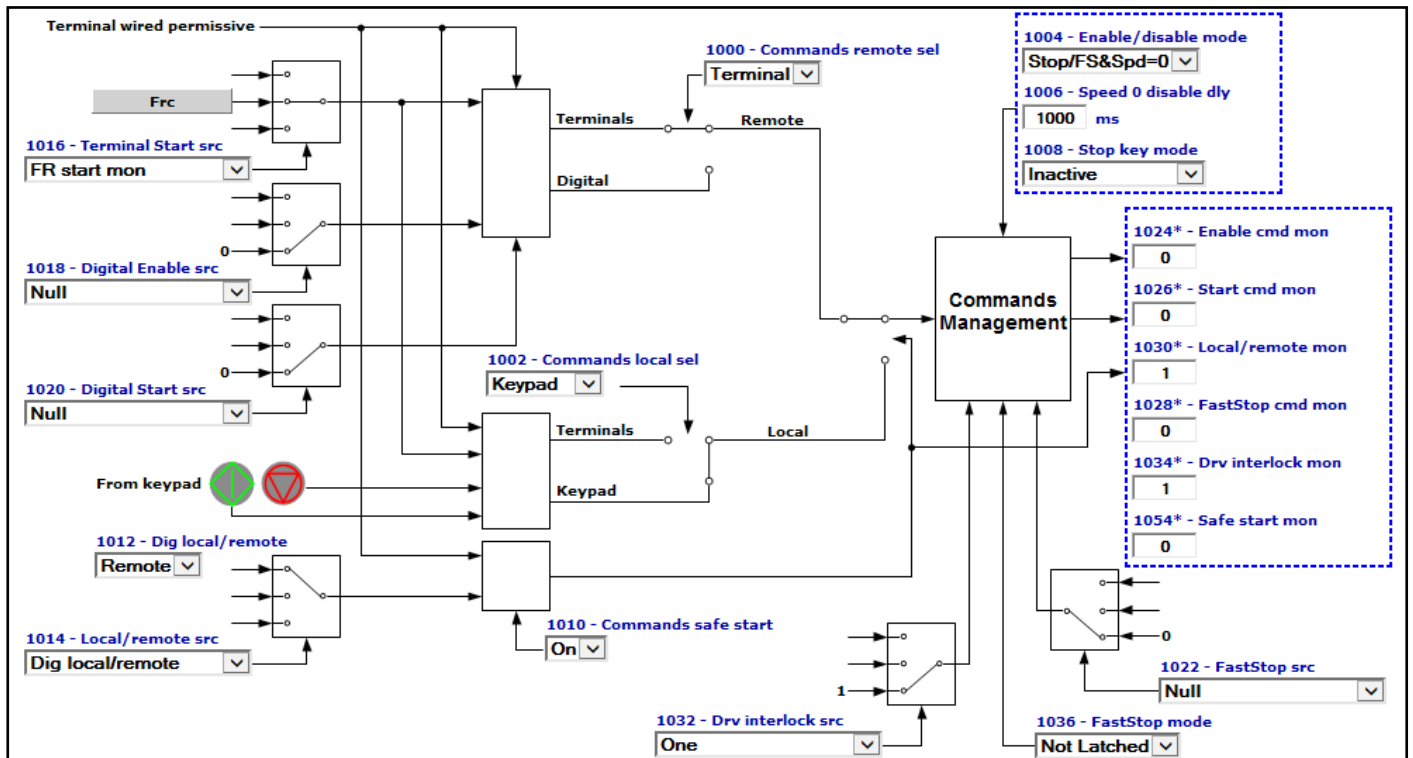
Commands

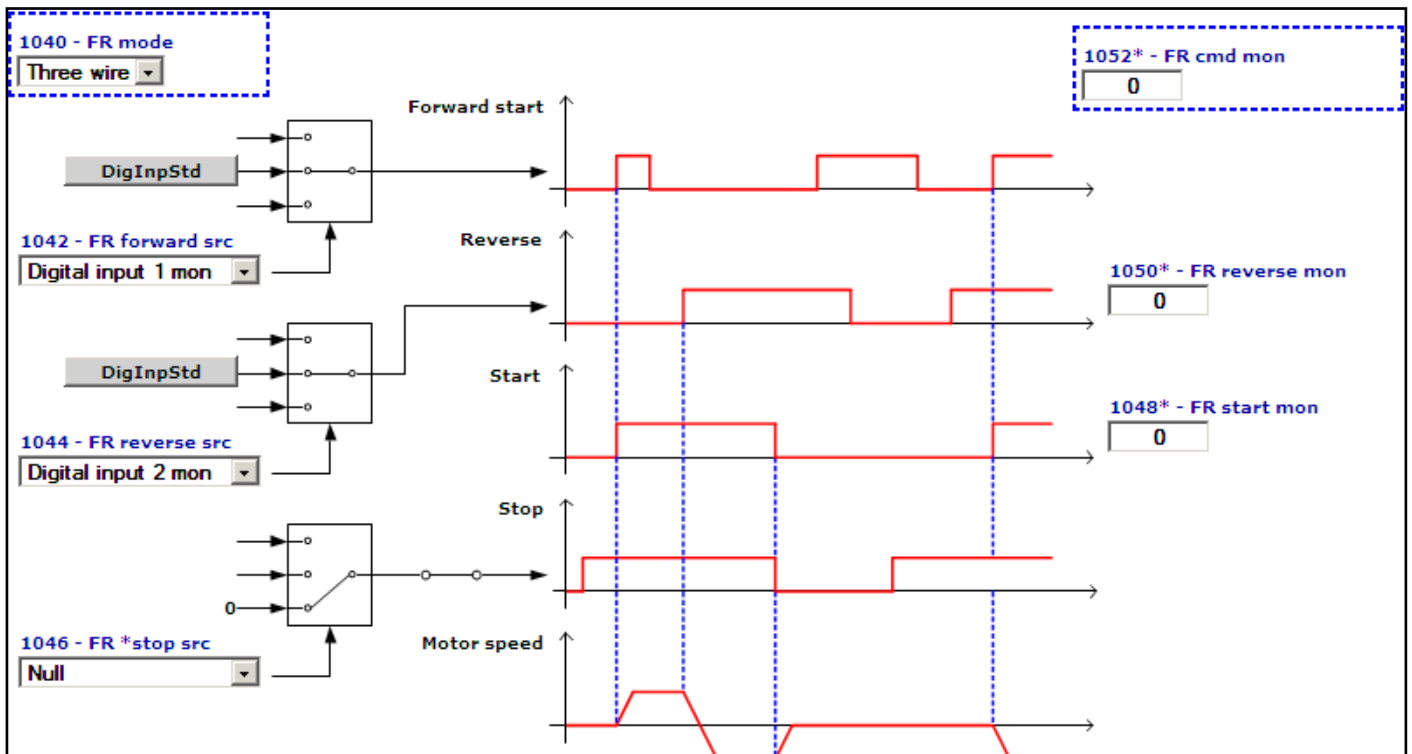
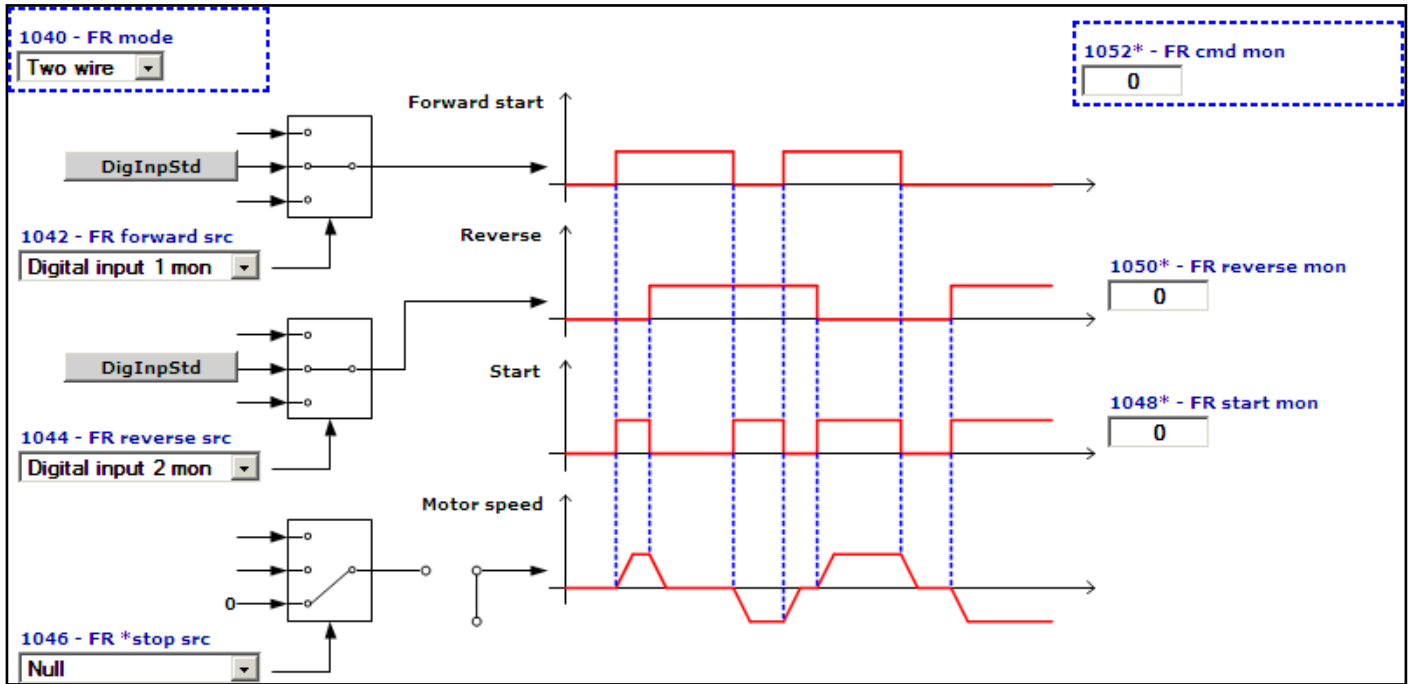
COMMANDS MANAGEMENT

CommManage

FORWARD REVERSE CONTROL

Frc





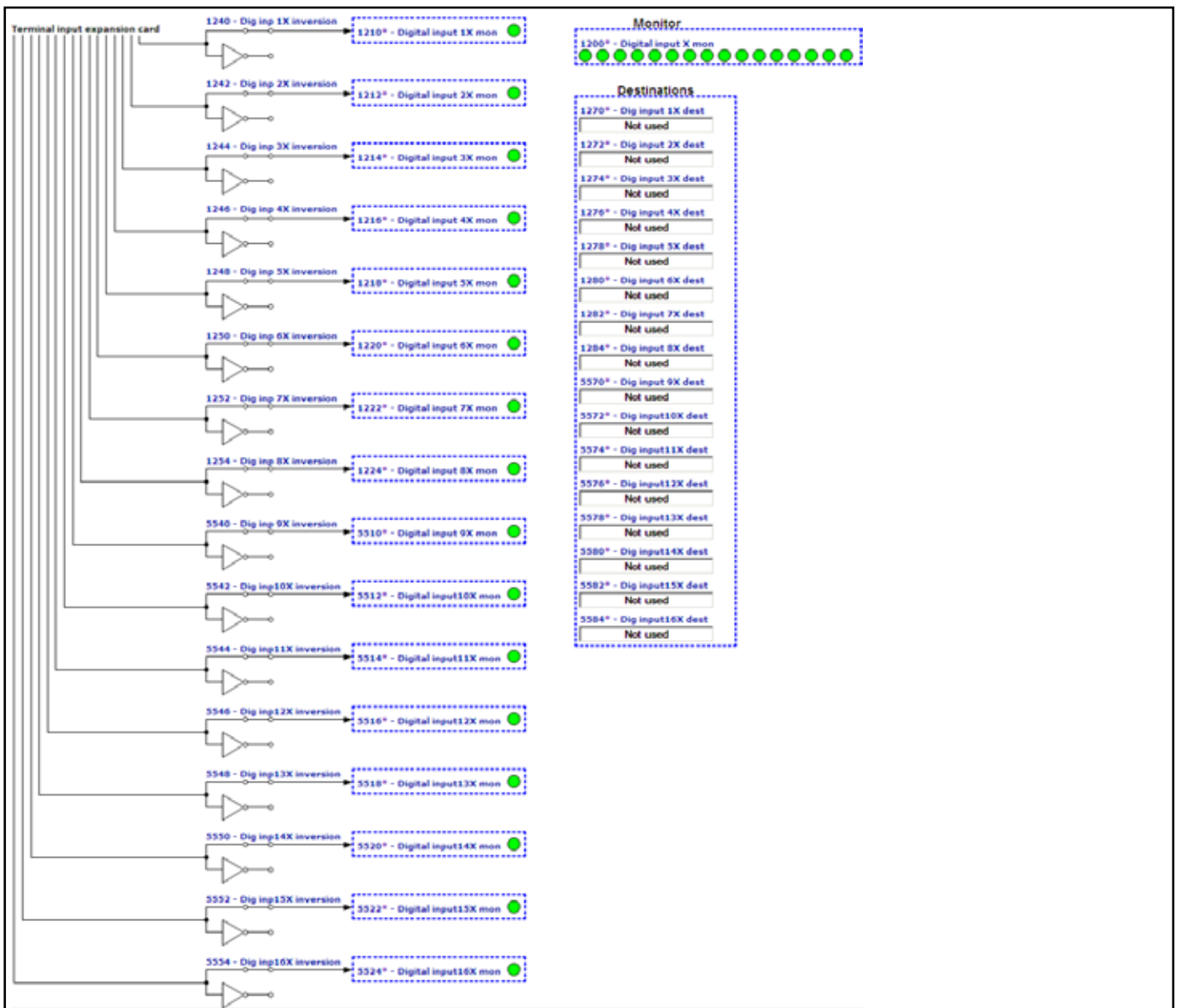
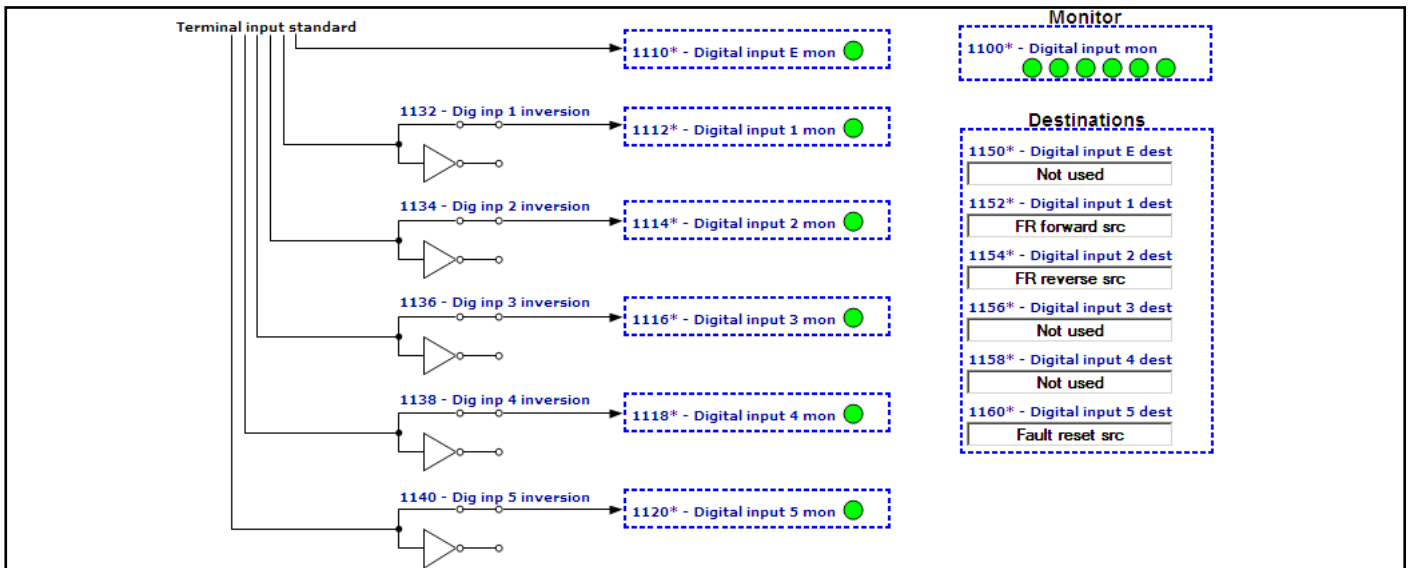
Digital inputs

DIGITAL INPUTS STANDARD

DigInpStd

DIGITAL INPUTS EXPANSION CARD

DigInpExp



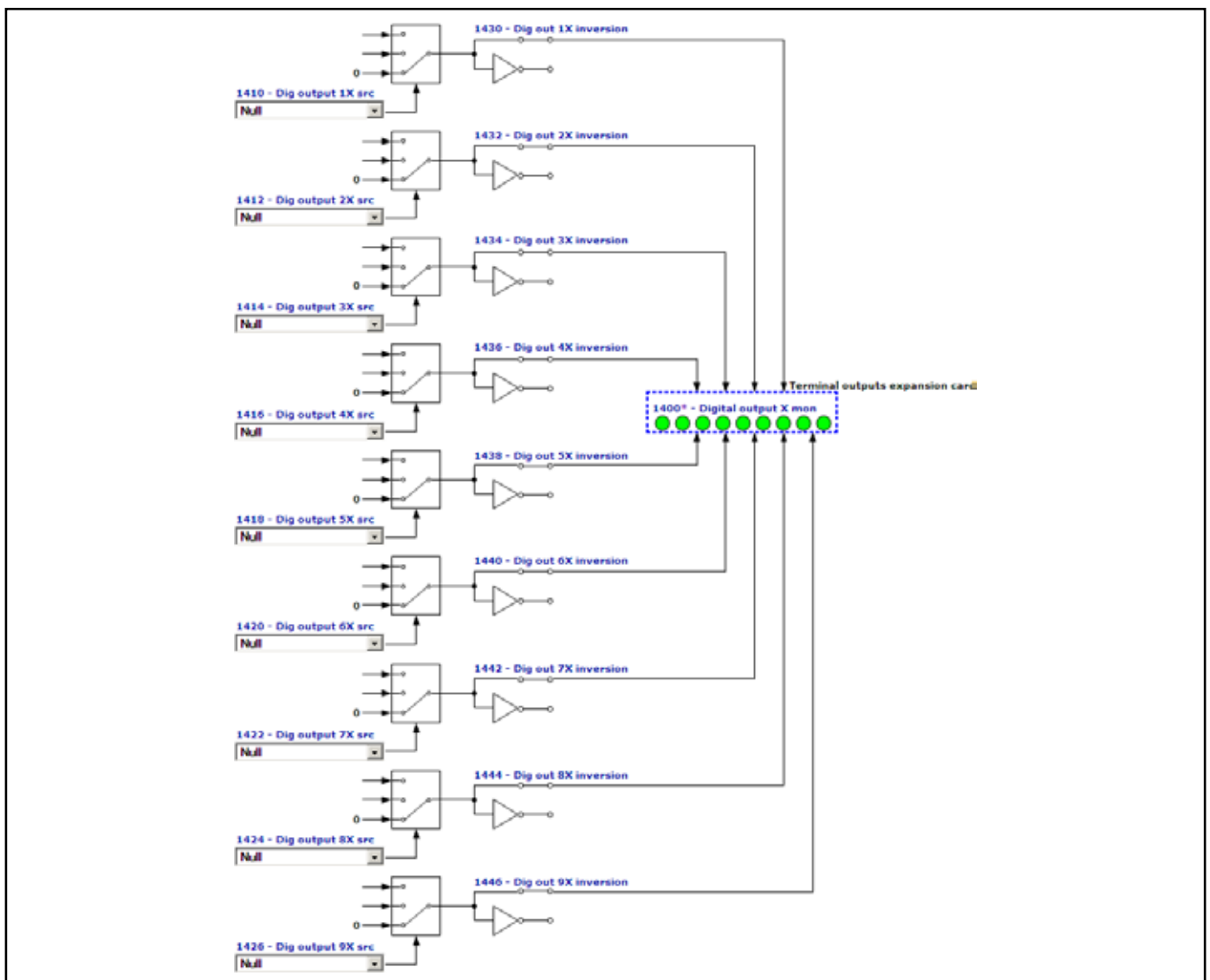
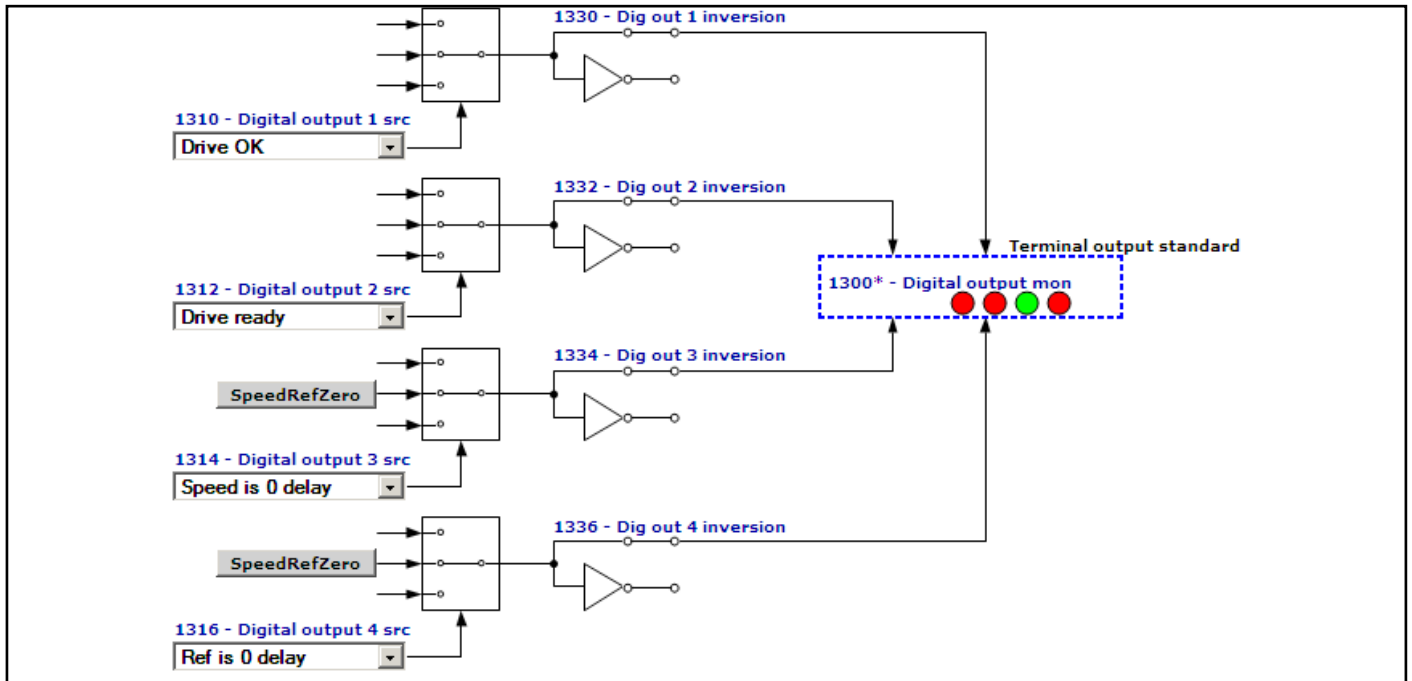
Digital outputs

DIGITAL OUTPUTS STANDARD

DigOutStd

DIGITAL OUTPUTS EXPANSION CARD

DigOutExp



Analog inputs

ANALOG INPUT 1 STANDARD

AnInp1Std

ANALOG INPUT 2 STANDARD

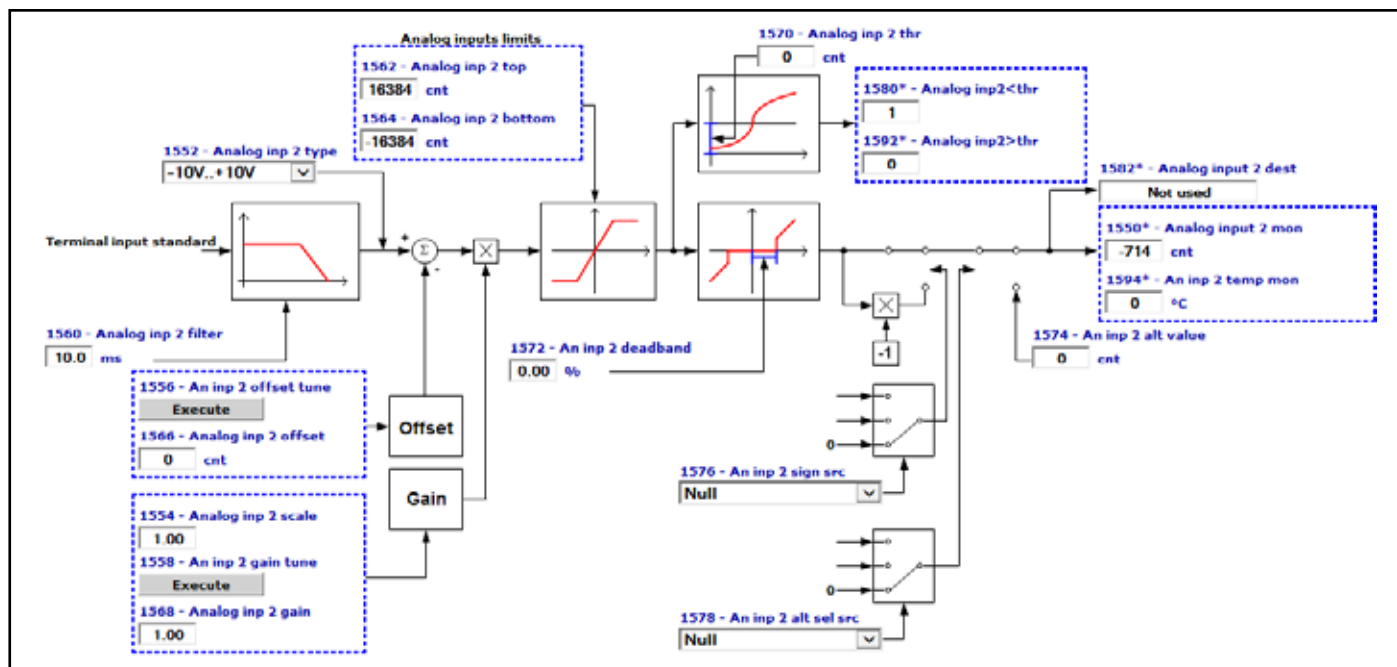
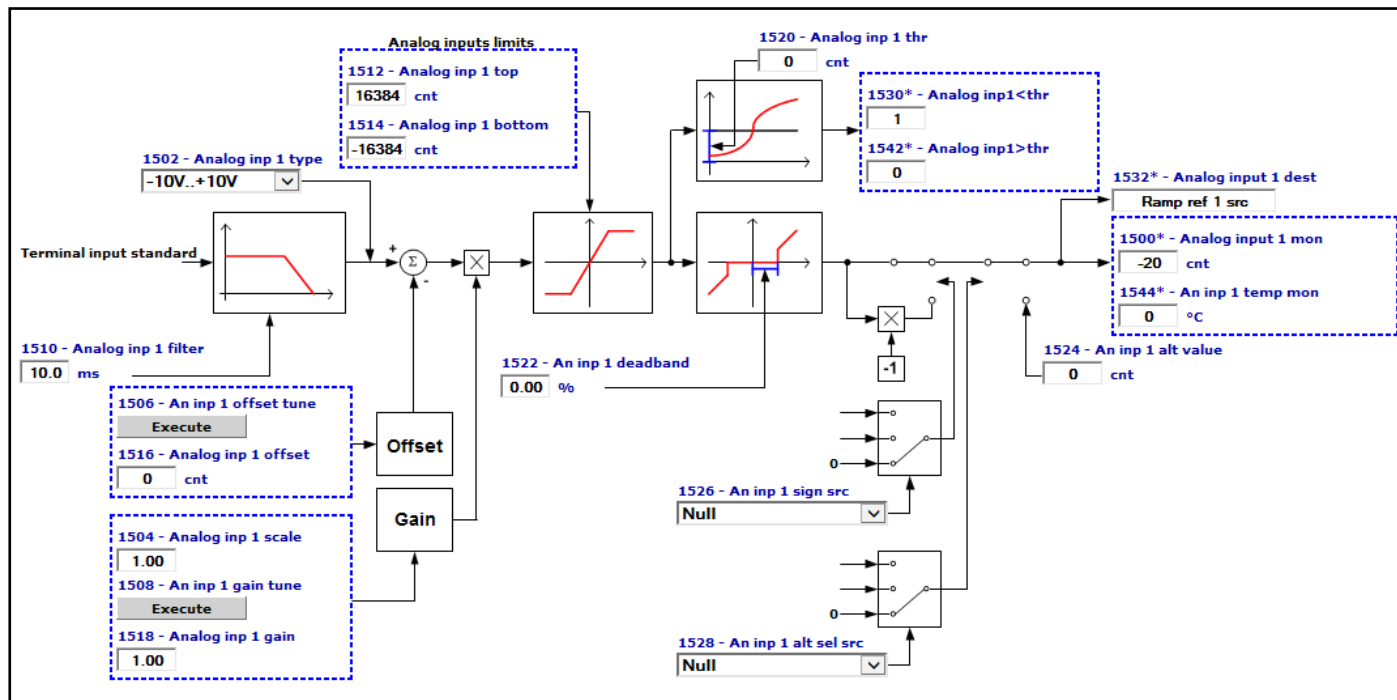
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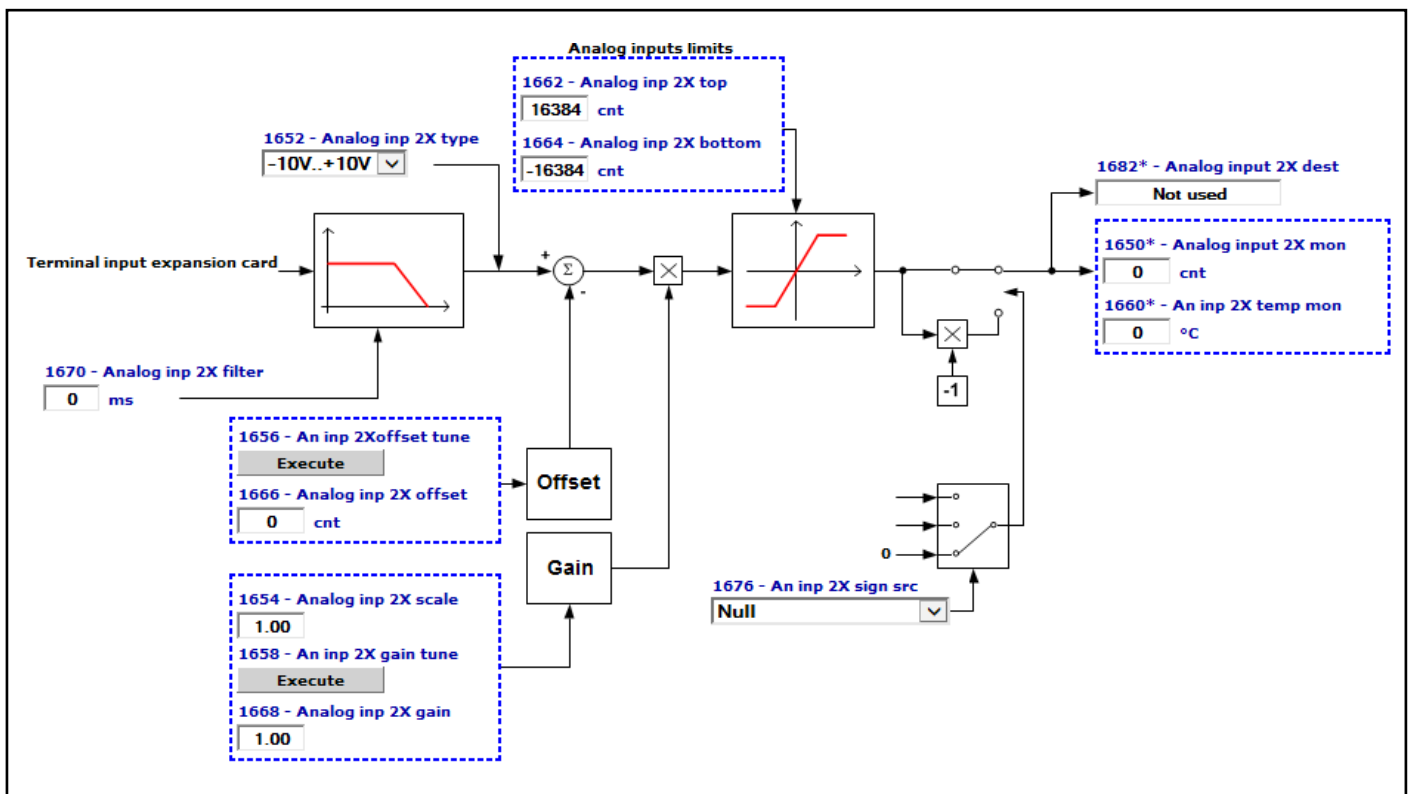
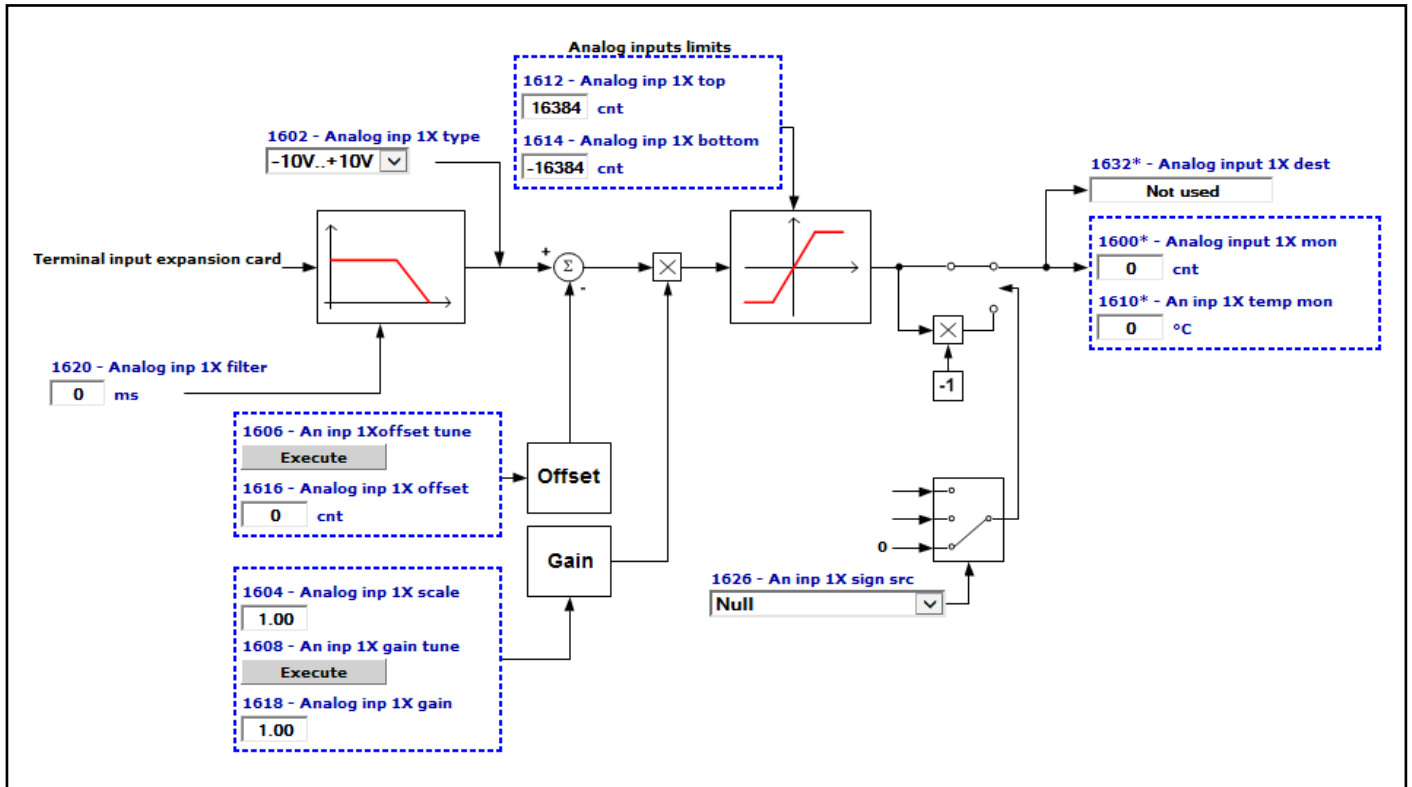
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AnInp1Exp

ANALOG INPUT 2 EXPANSION CARD

AnInp2Exp





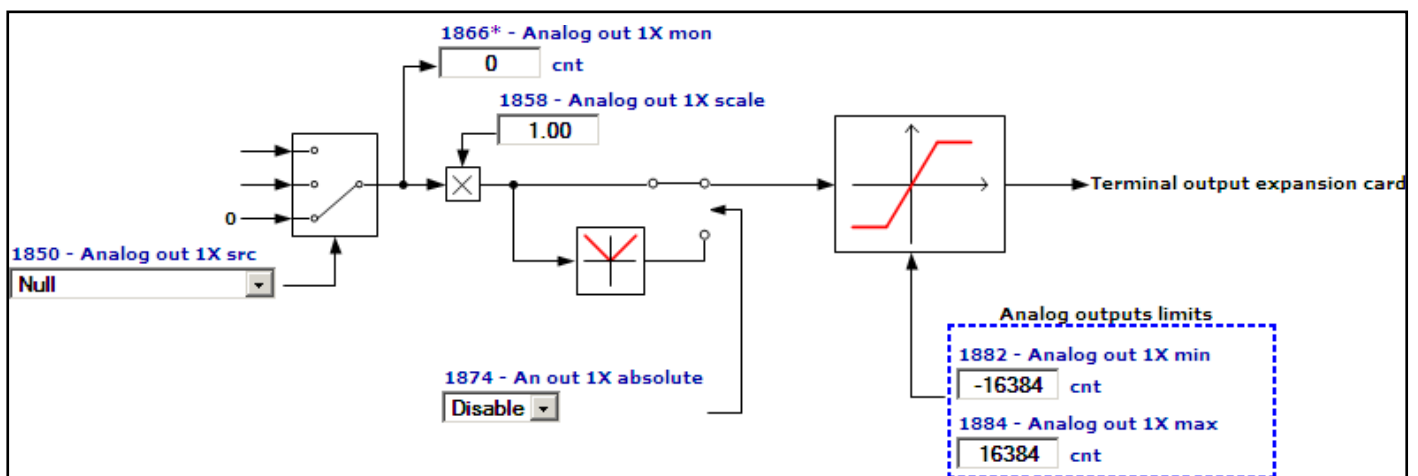
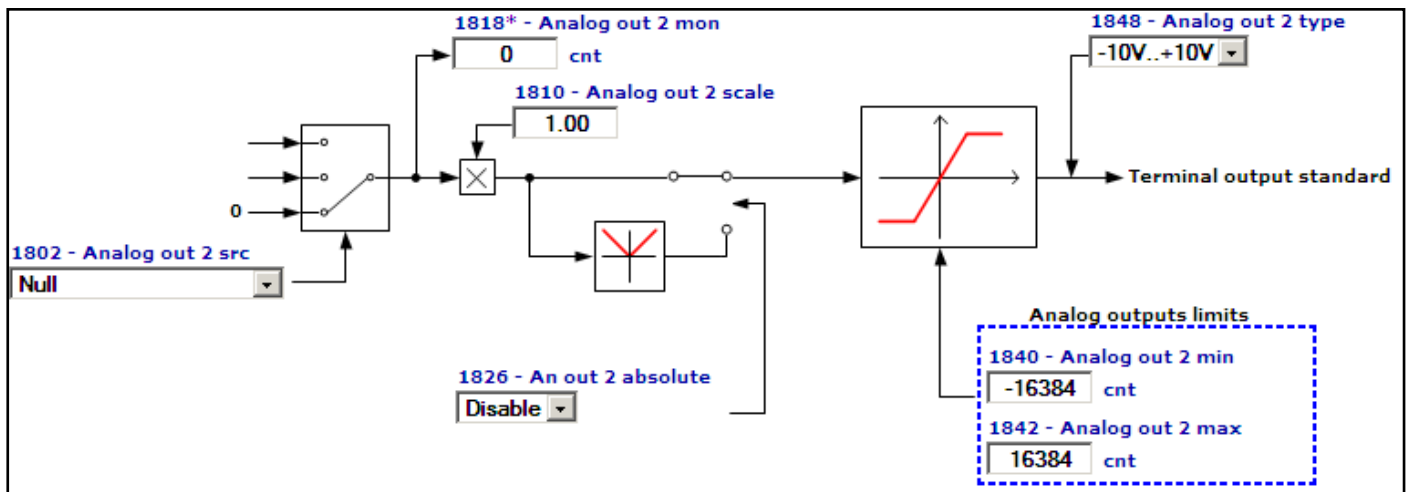
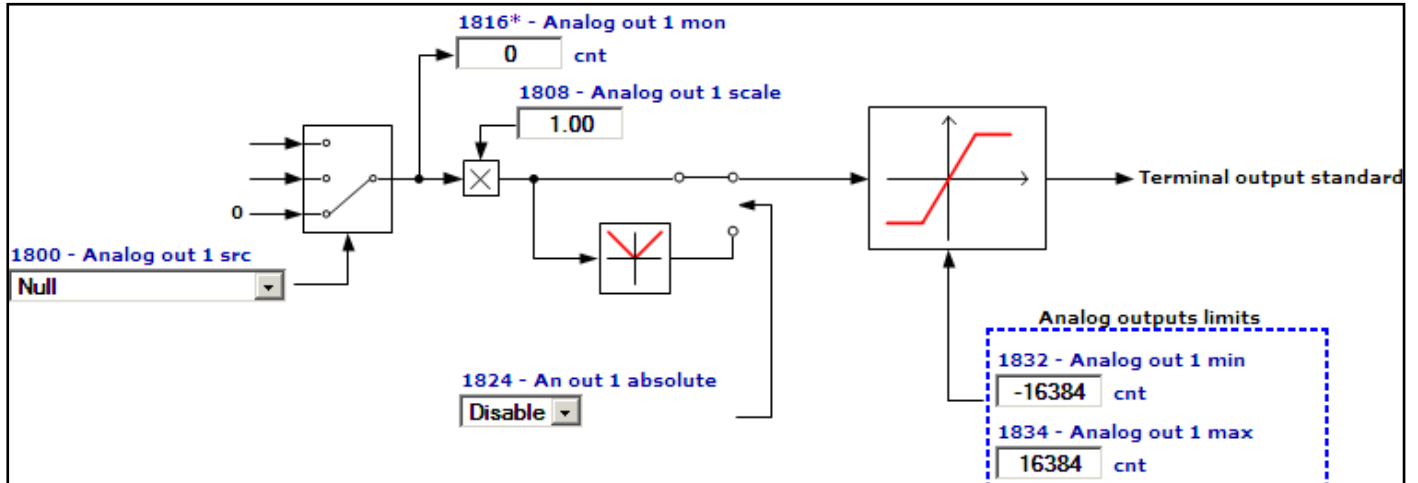
Analog outputs

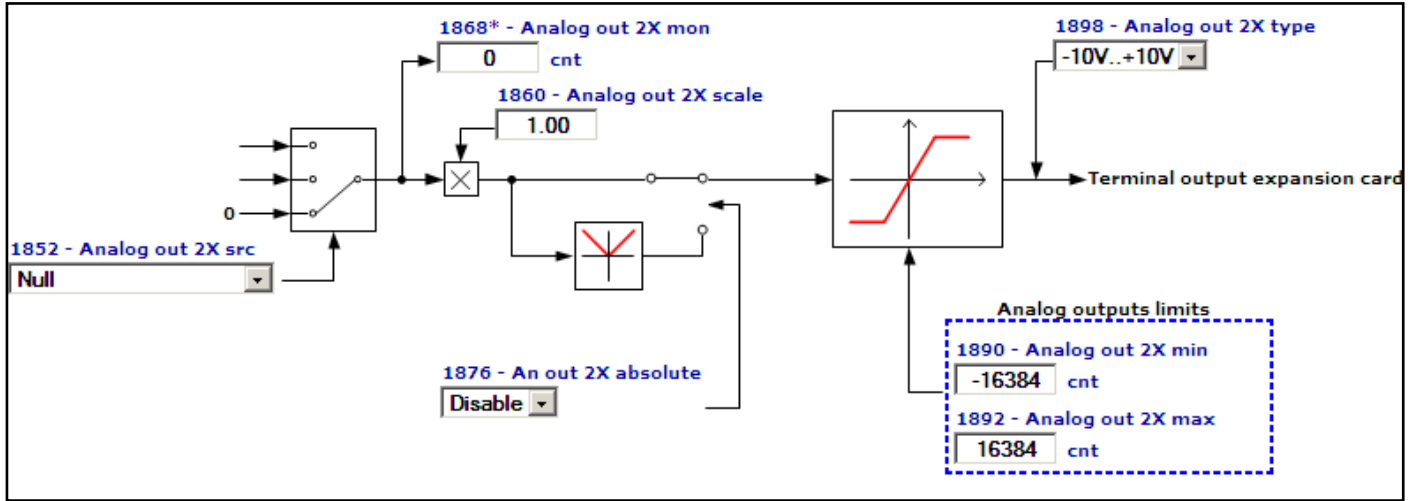
ANALOG OUTPUT 1 STANDARD **AnOut1Std**

ANALOG OUTPUT 2 STANDARD **AnOut2Std**

ANALOG OUTPUT 1 EXPANSION CARD **AnOut1Exp**

ANALOG OUTPUT 2 EXPANSION CARD **AnOut2Exp**





Encoder config

ENCODER 1 CONFIGURATION

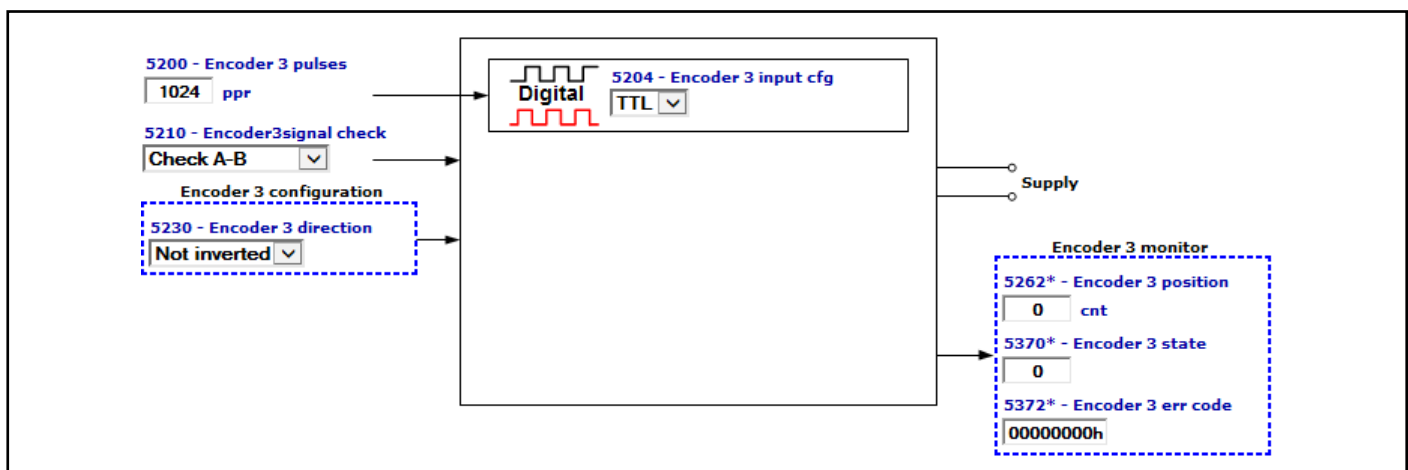
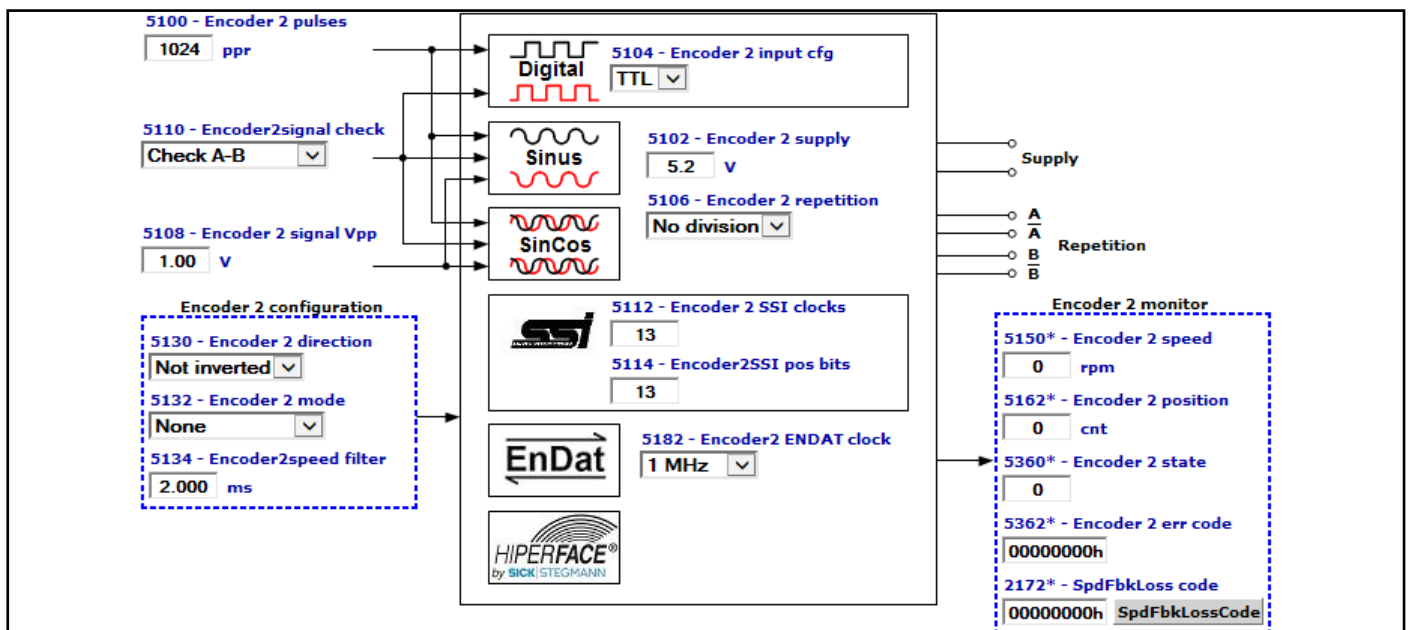
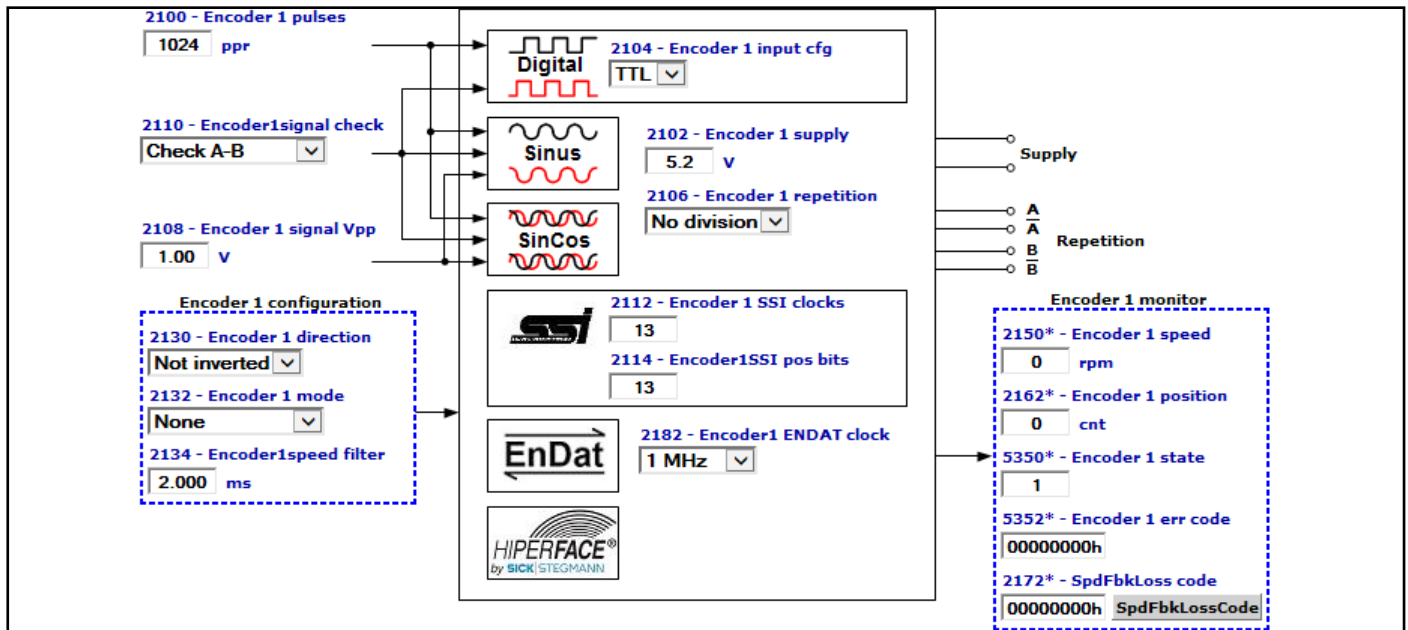
Encoder1

ENCODER 2 CONFIGURATION

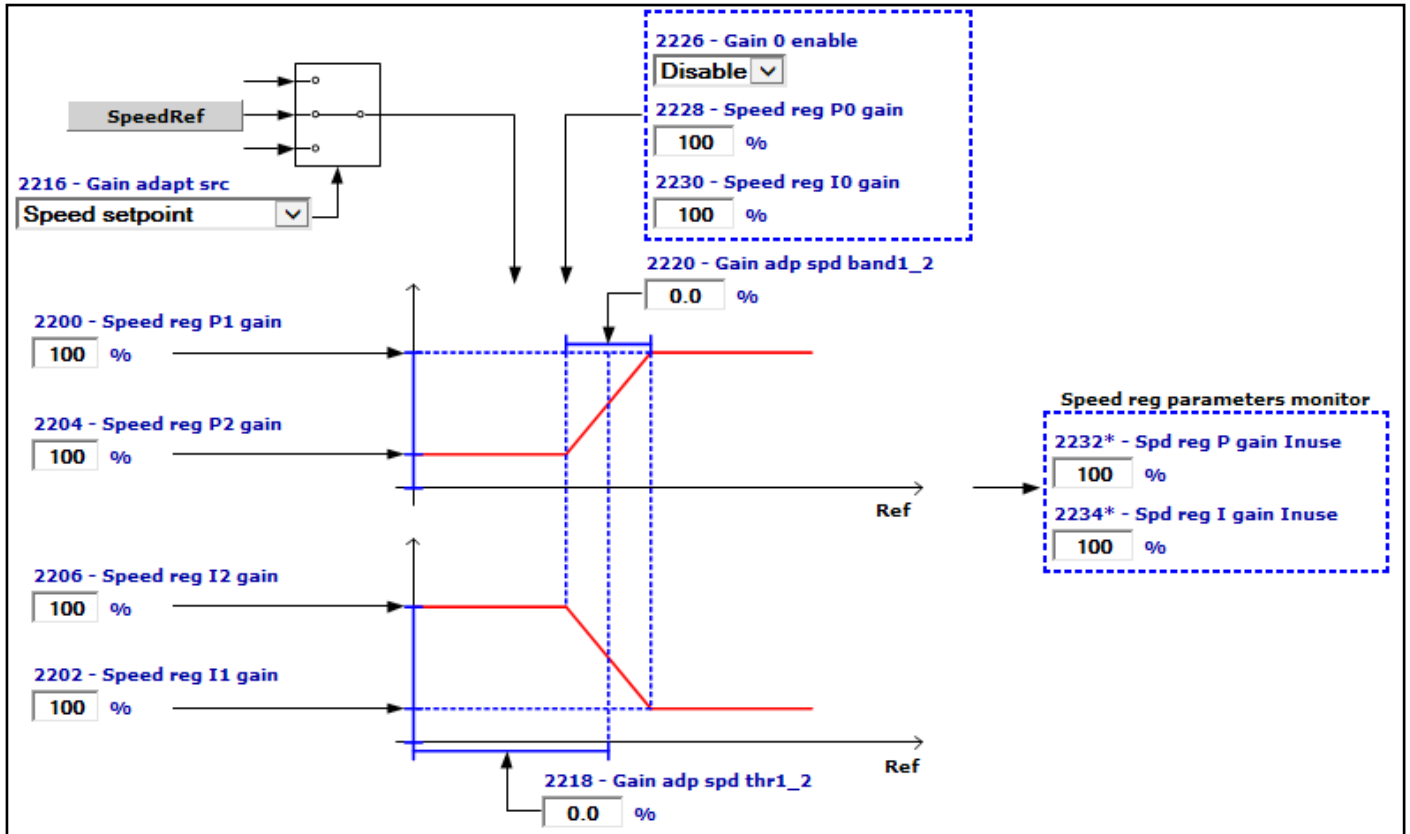
Encoder2

ENCODER 3 CONFIGURATION

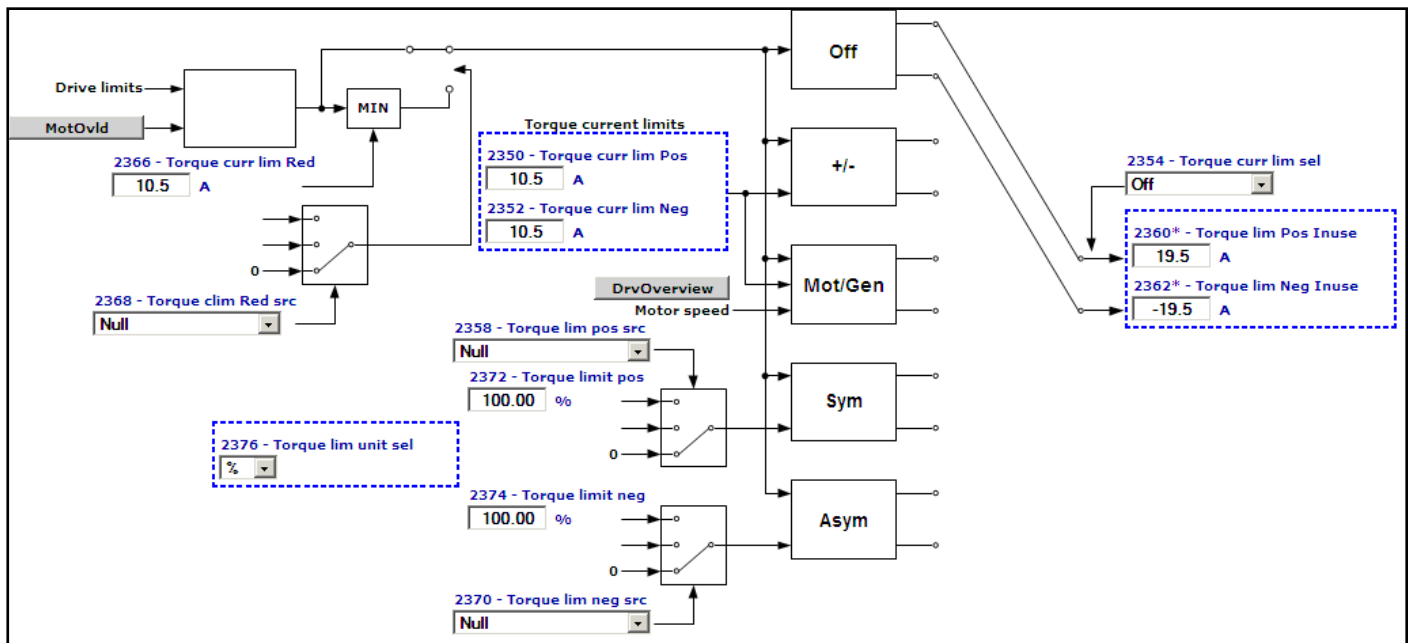
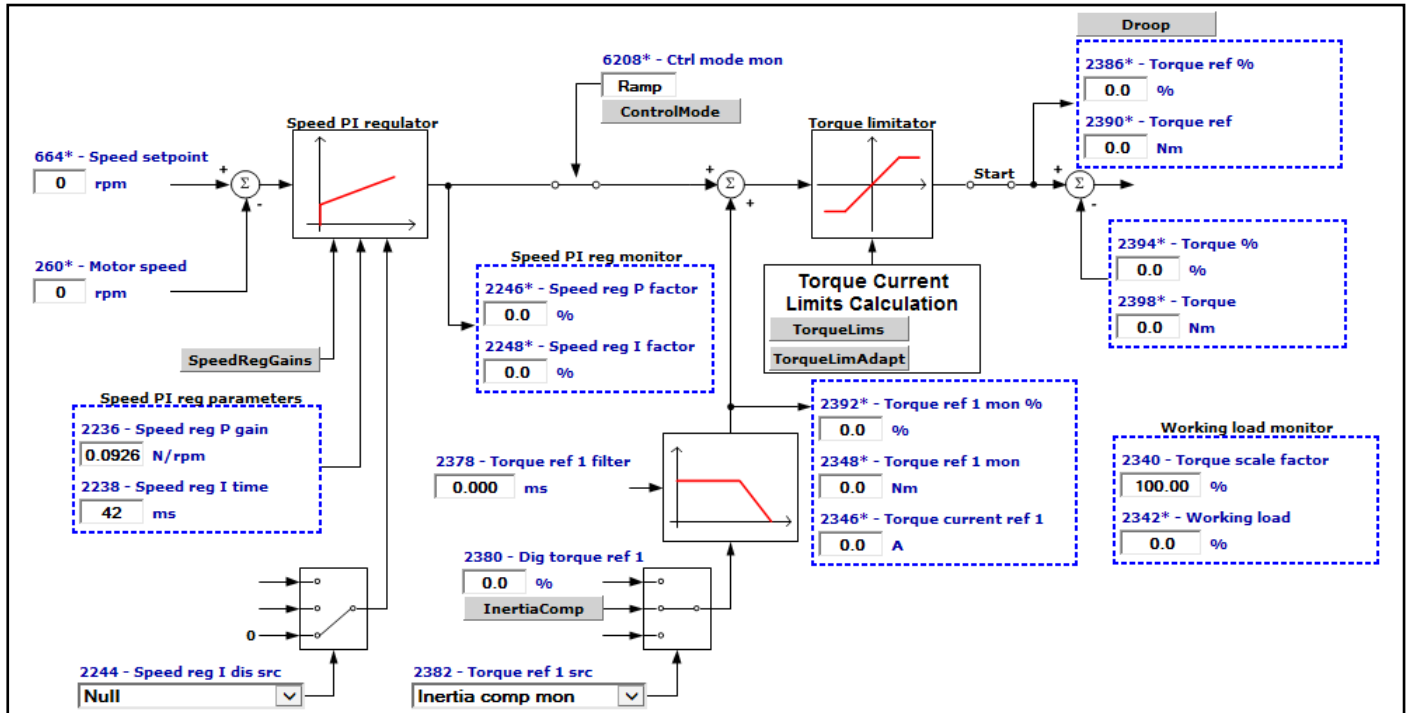
Encoder3



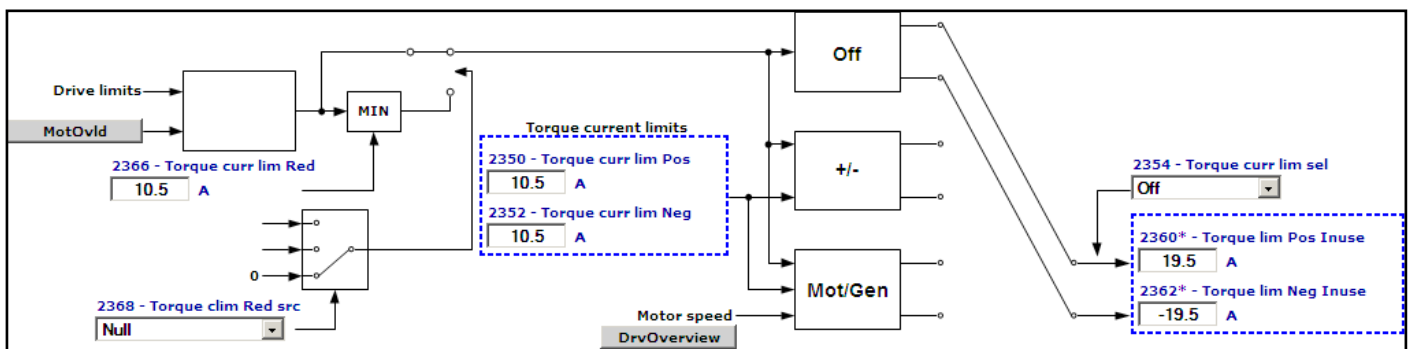
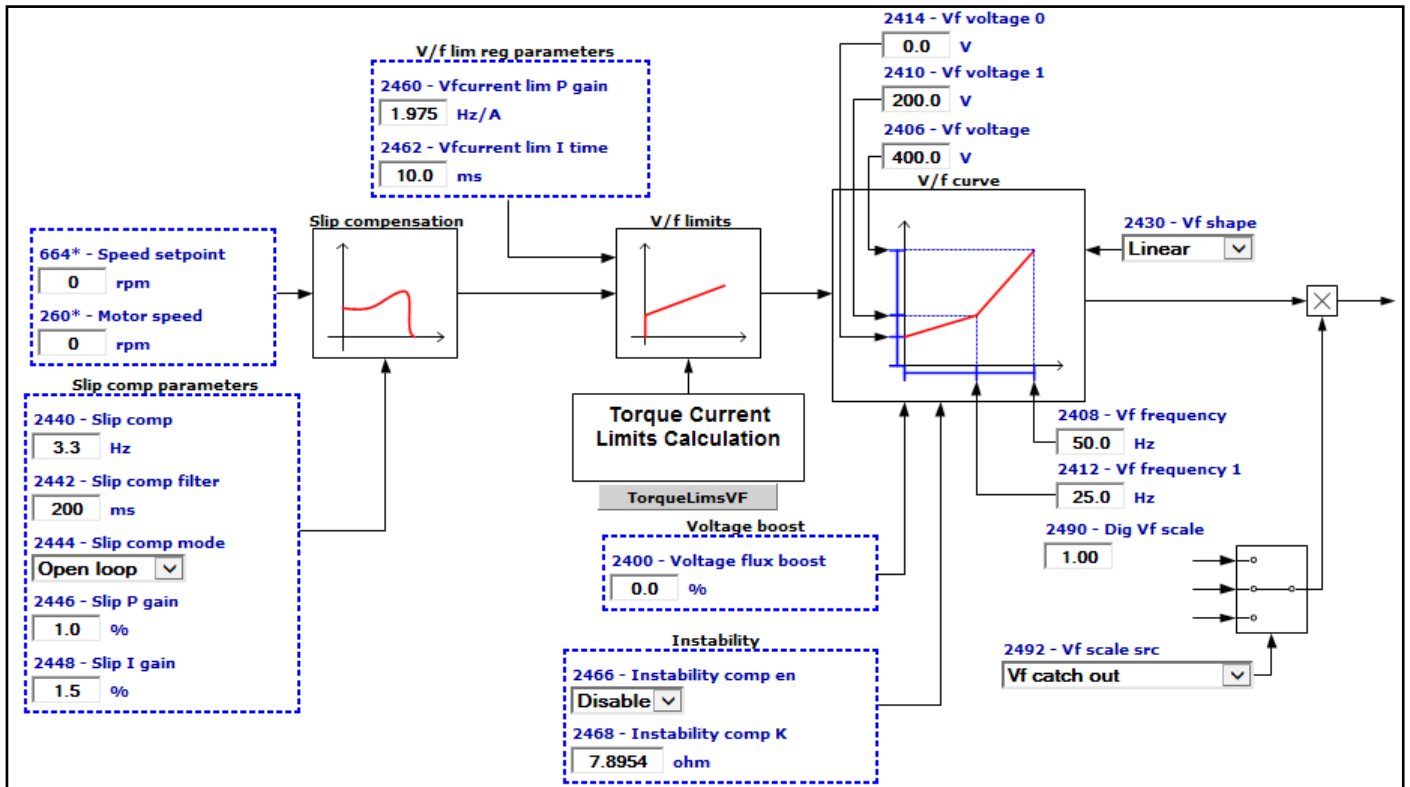
Speed reg gains



Torque config

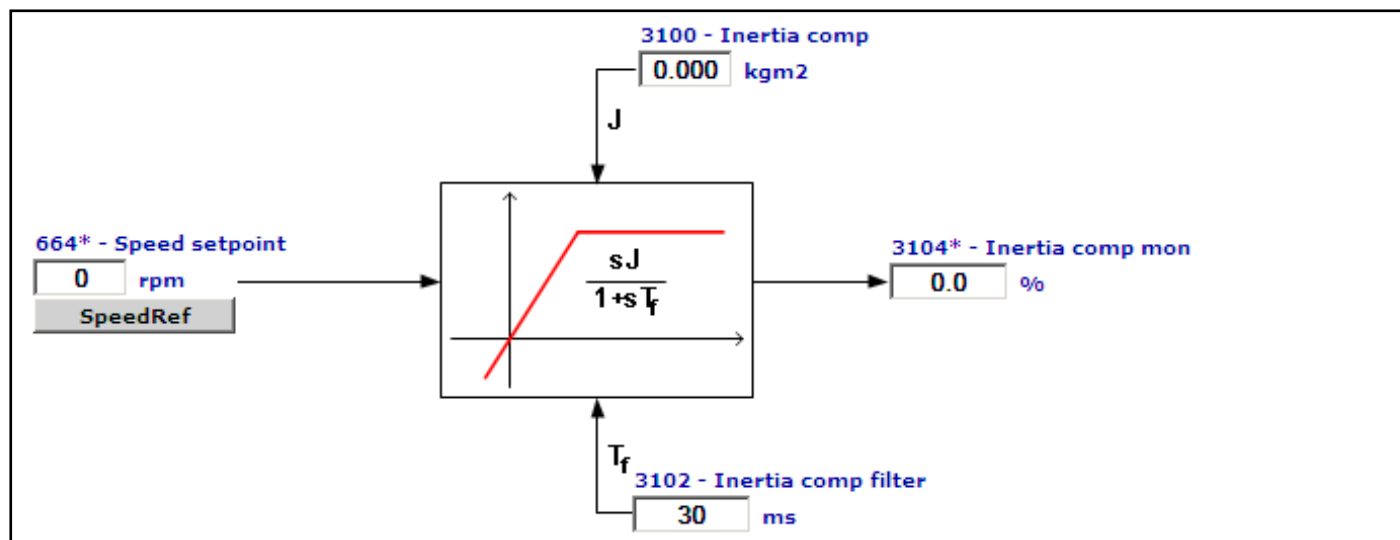
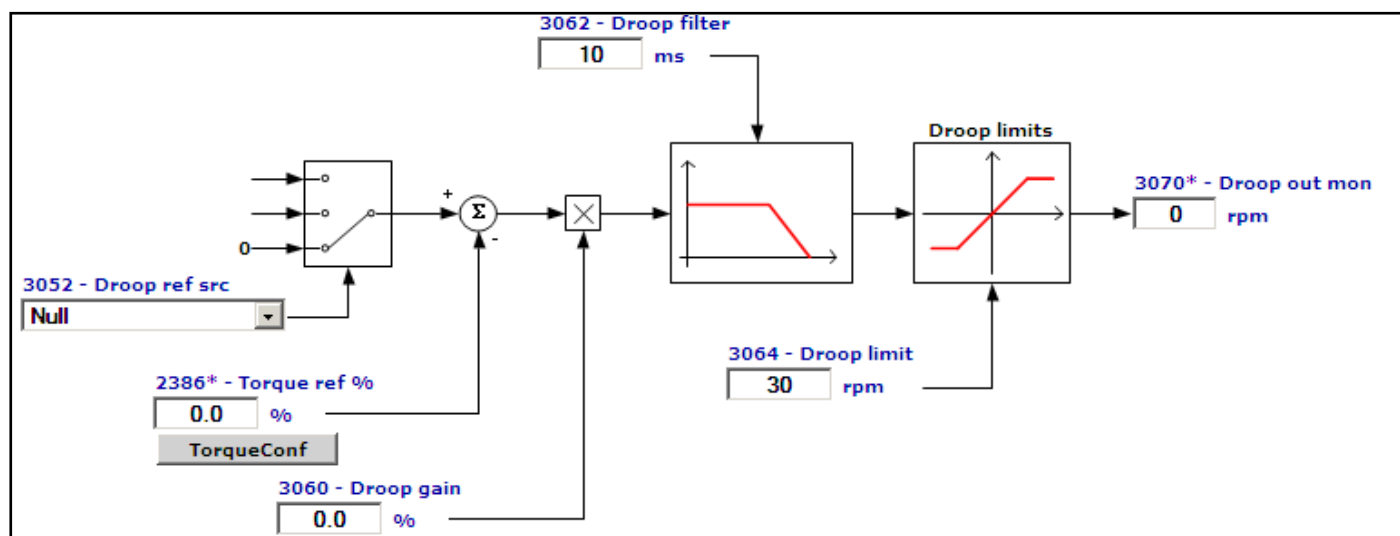


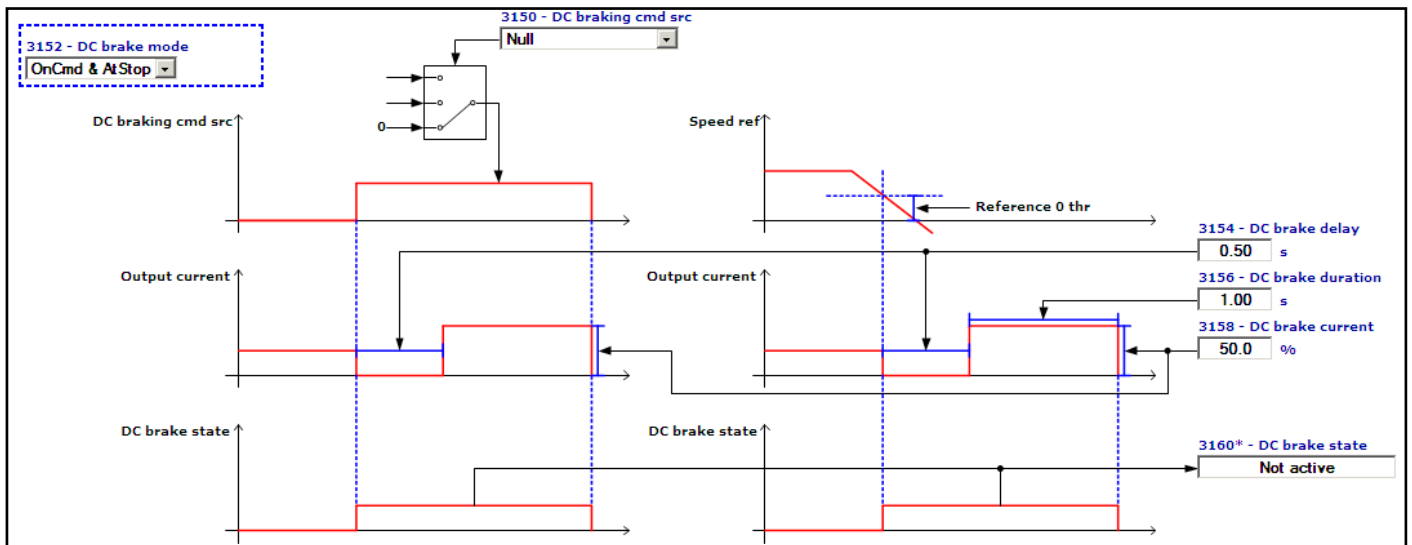
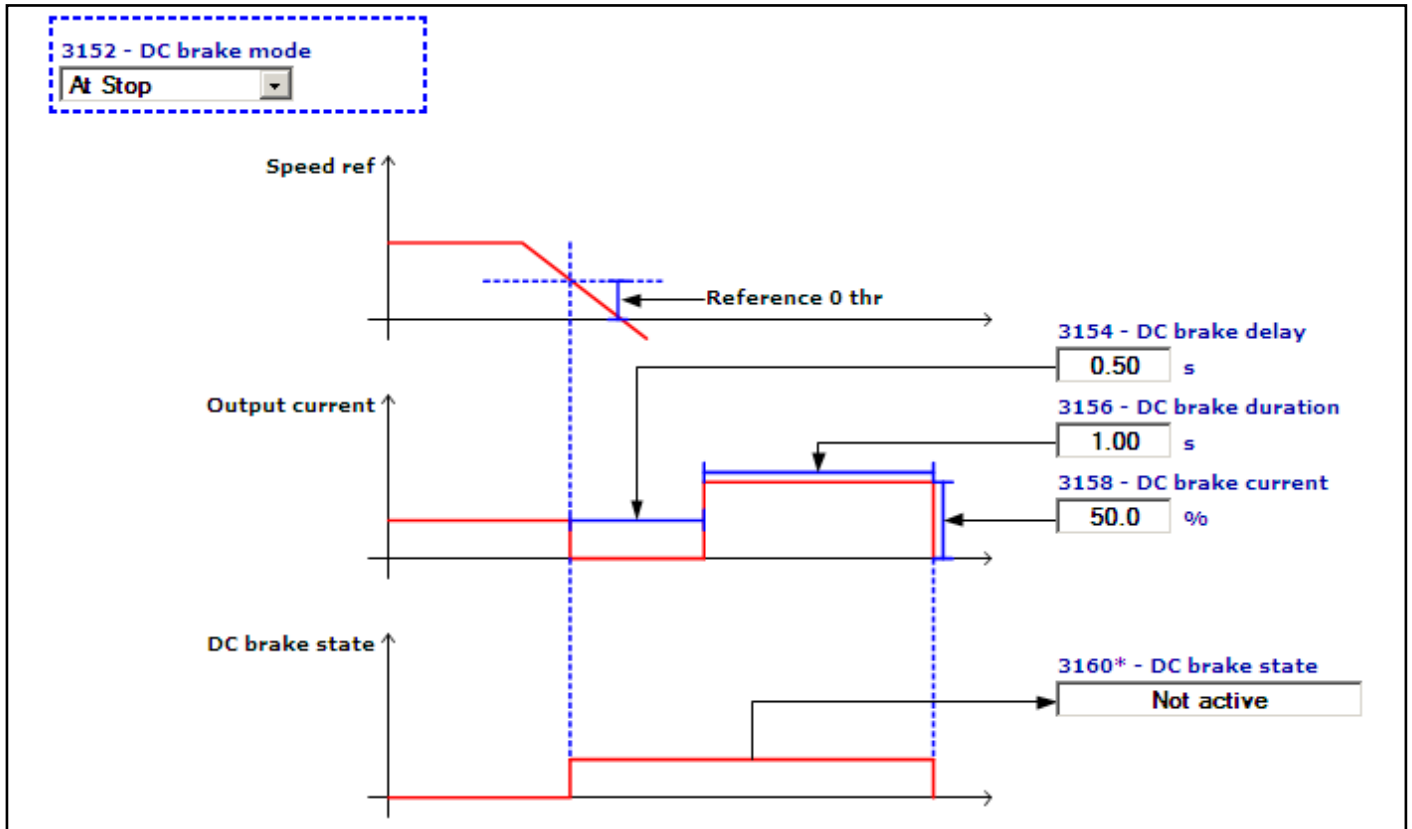
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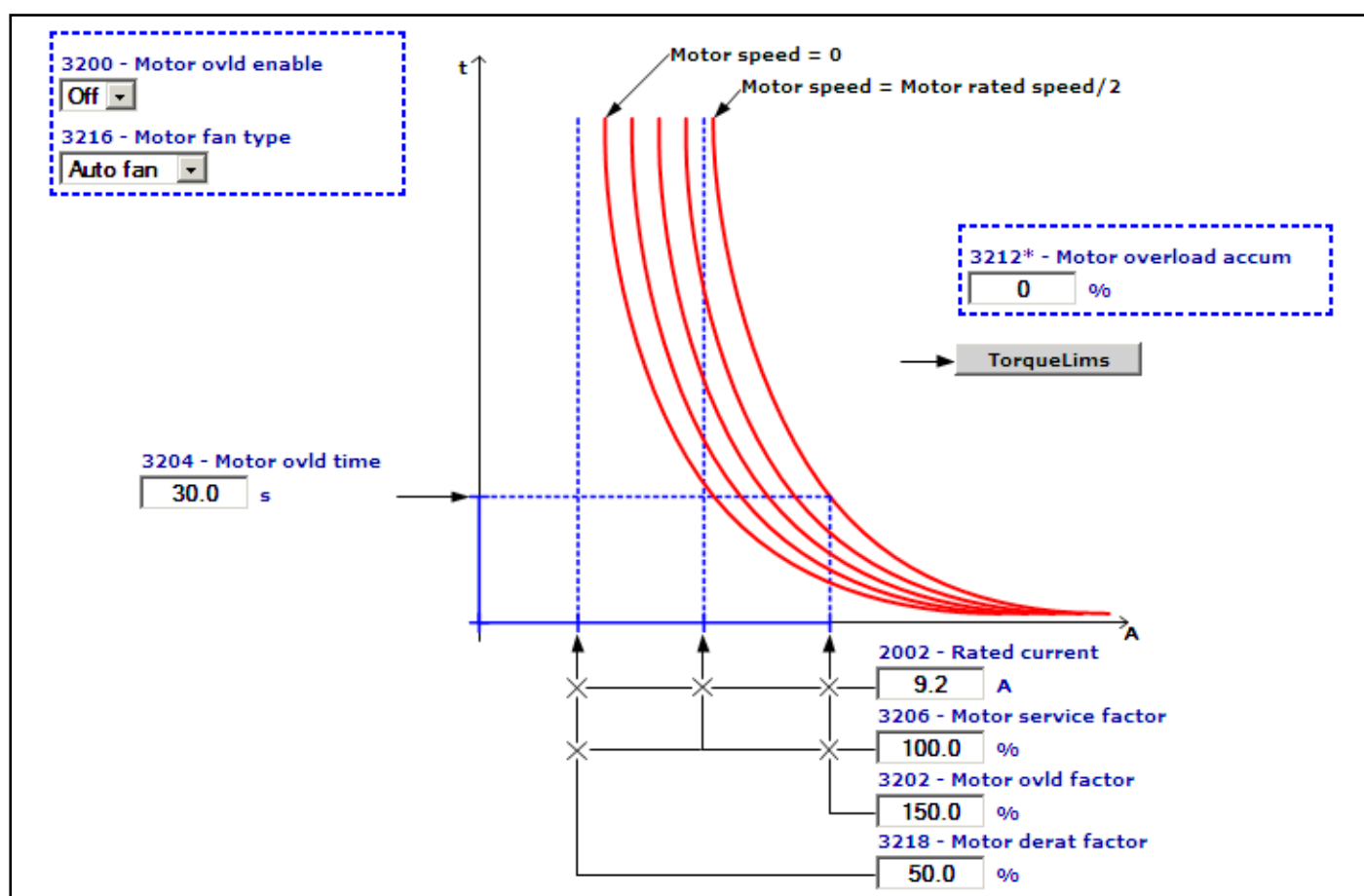
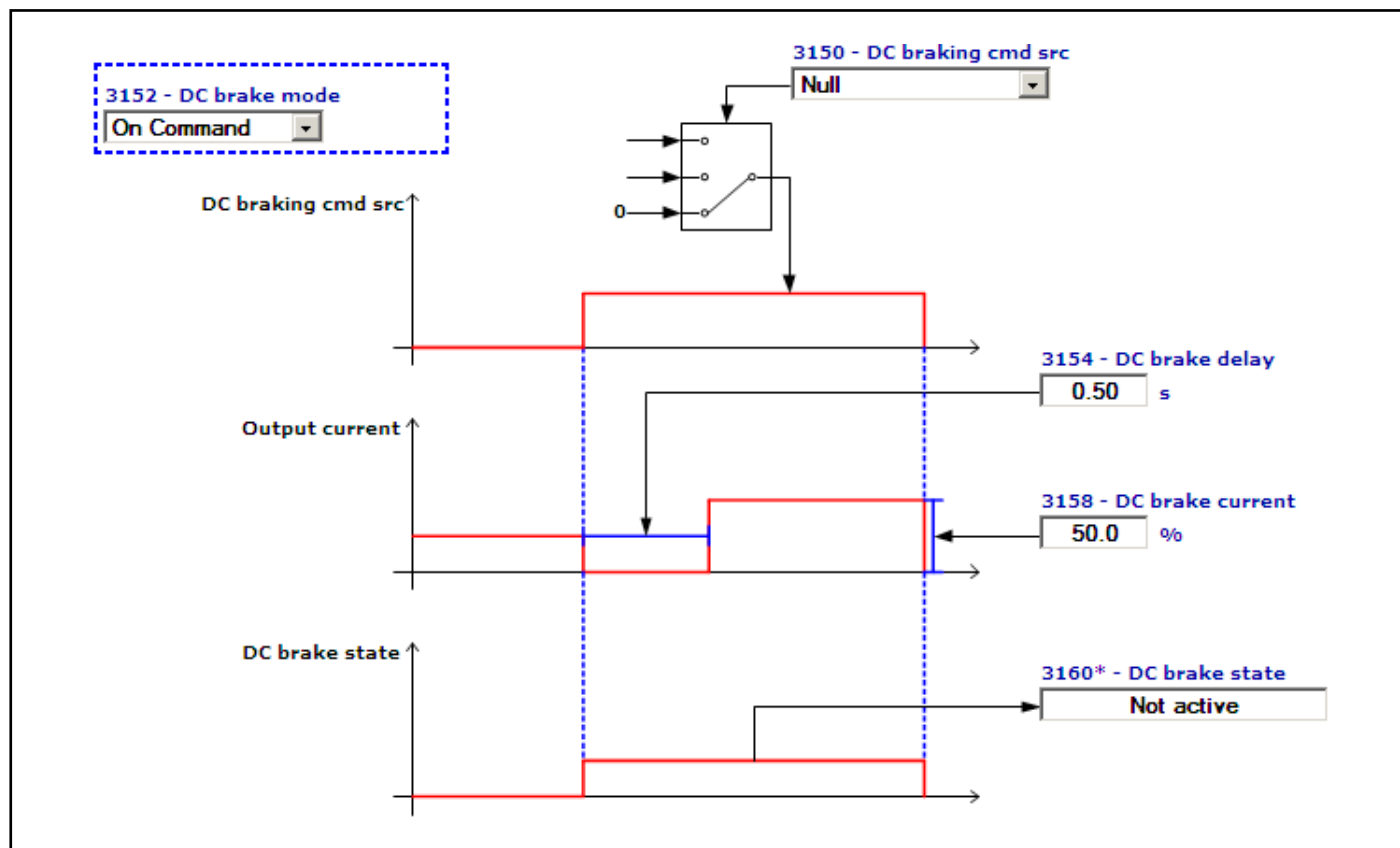


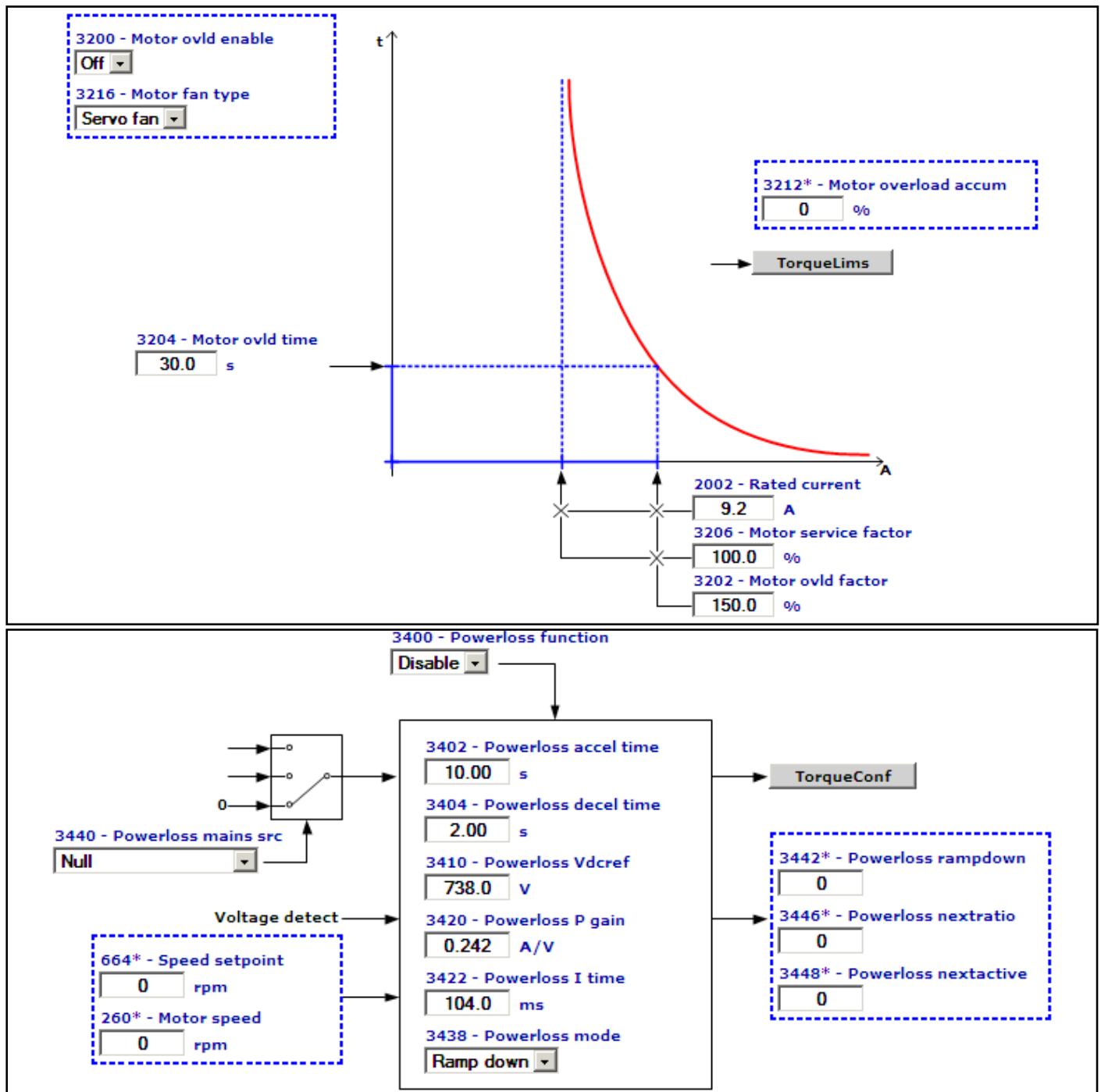
Functions

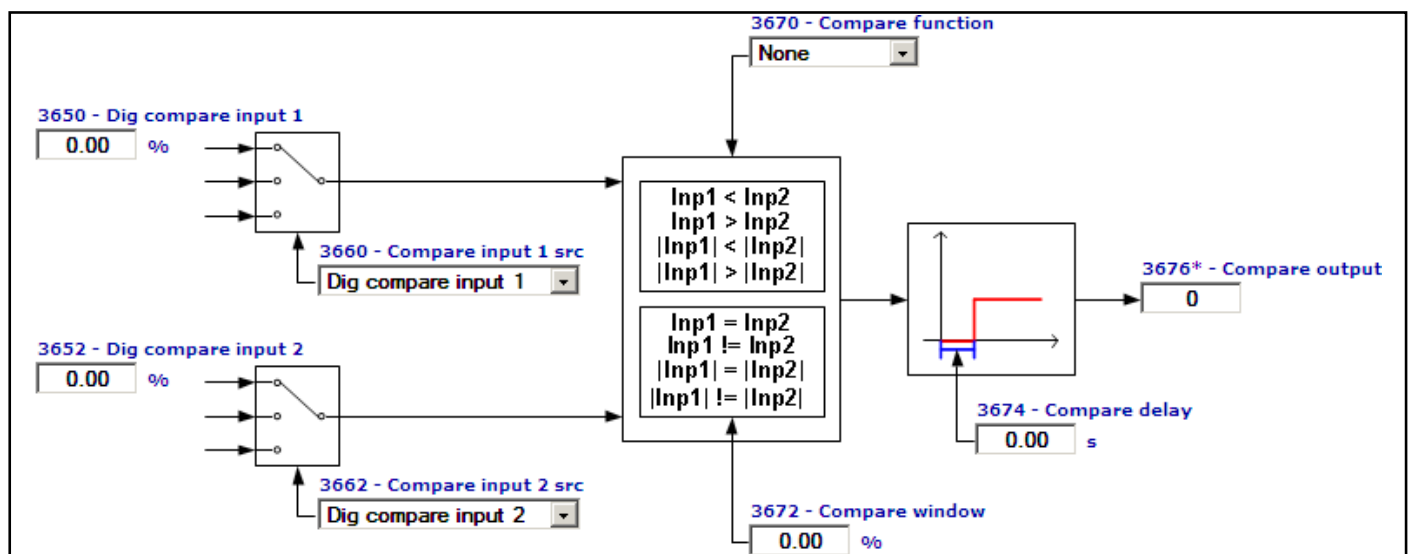
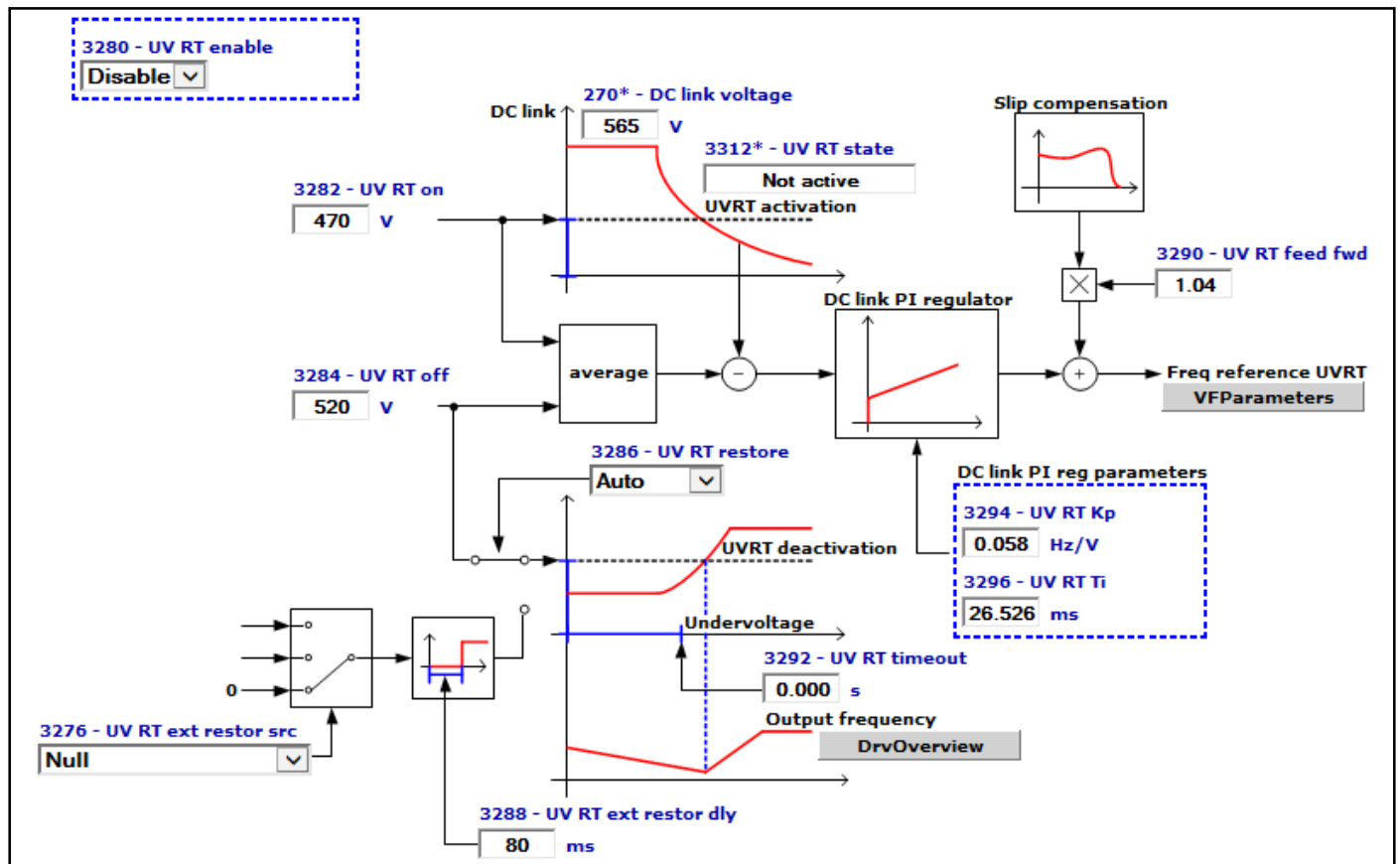
DROOP	Droop
INERTIA COMP	InertiaComp
DC BRAKING	DCBraking
MOTOR OVERLOAD	MotOvld
BRES OVERLOAD	BresOvld
DOUBLE PAR SET	DoubleParSet
POWER LOSS	PowerLoss
UV RIDE THROUGH	UVRT
COMPARE	Compare
BRAKE CONTROL	BrakeCtrl
DIMENSION FACT	DimFactor
CONTROL MODE	ControlMode
TEMP CONTROL	TempControl
LC CONTROL	LCControl
TIMERS	Timers
TORQUE LIMADAPT	TorqueLimAdapt





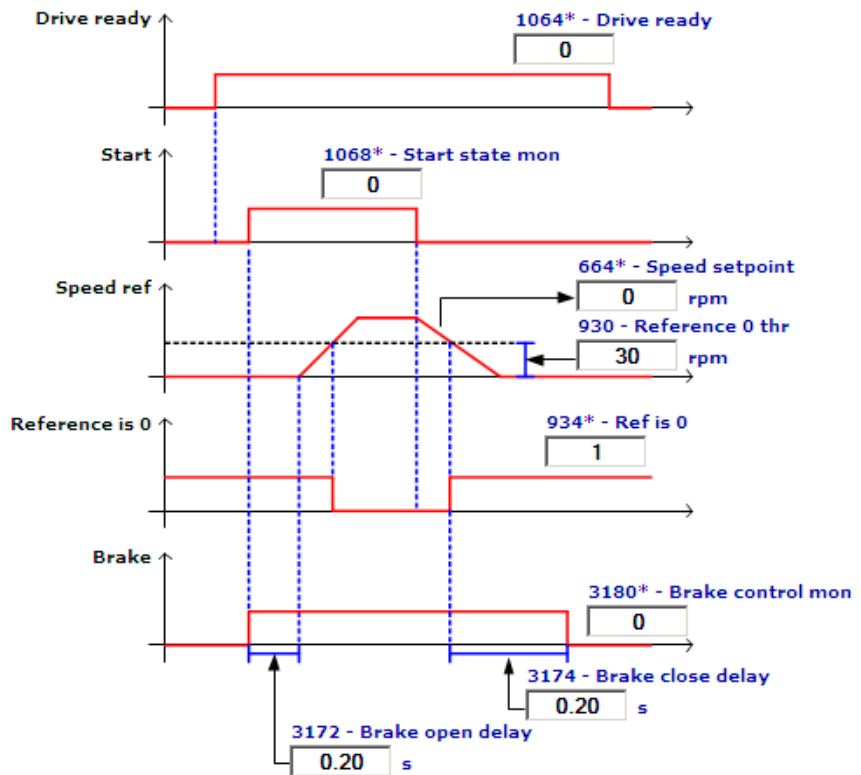






3170 - Brake control funct

Standard



3170 - Brake control funct

Hoist mode 1

3194 - Brake ramp freeze

Enable

3184 - Brake open thr

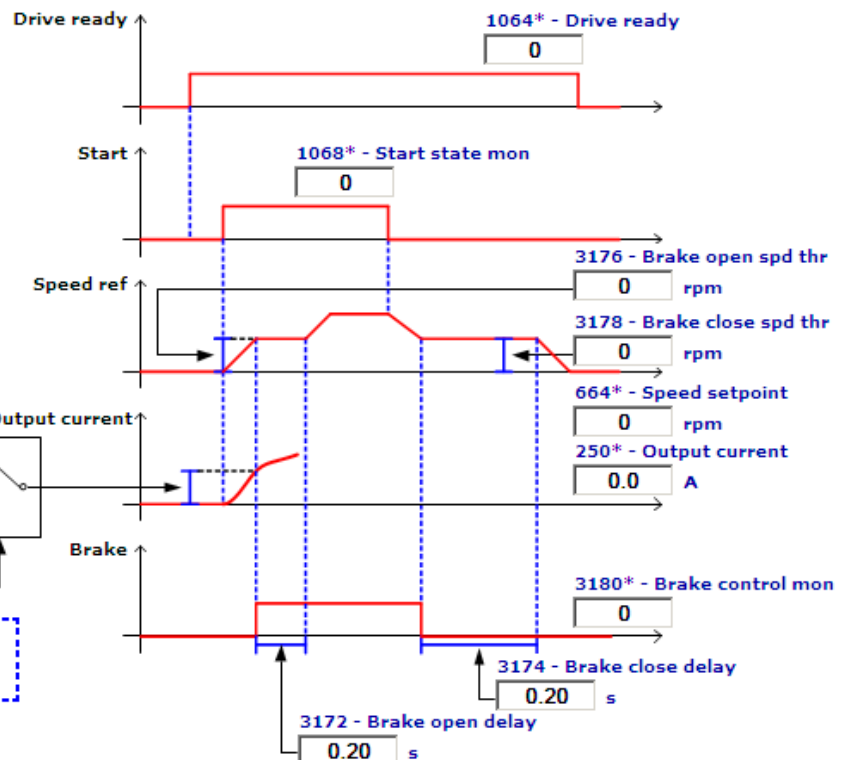
10.0 %

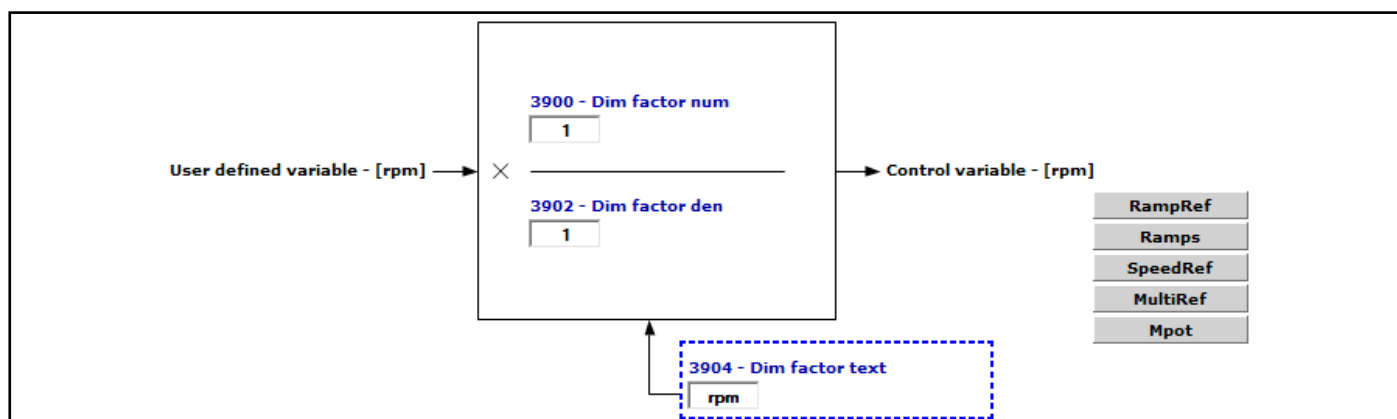
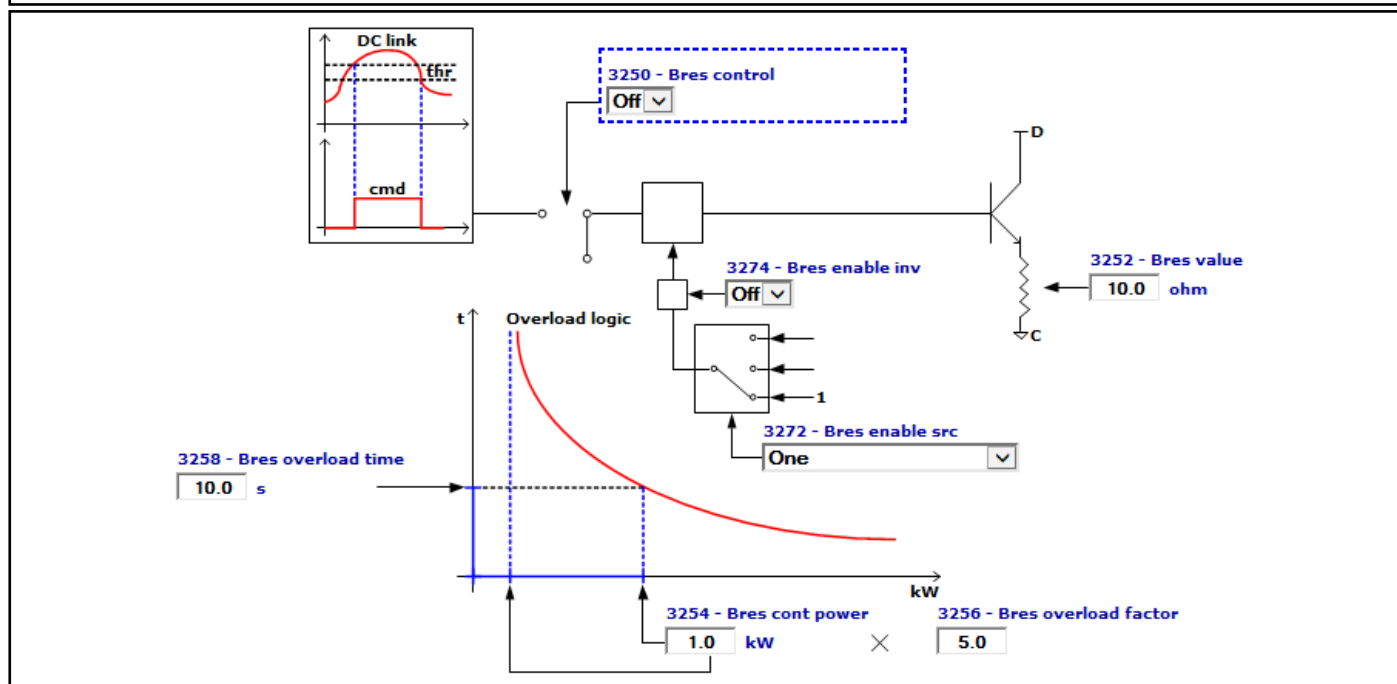
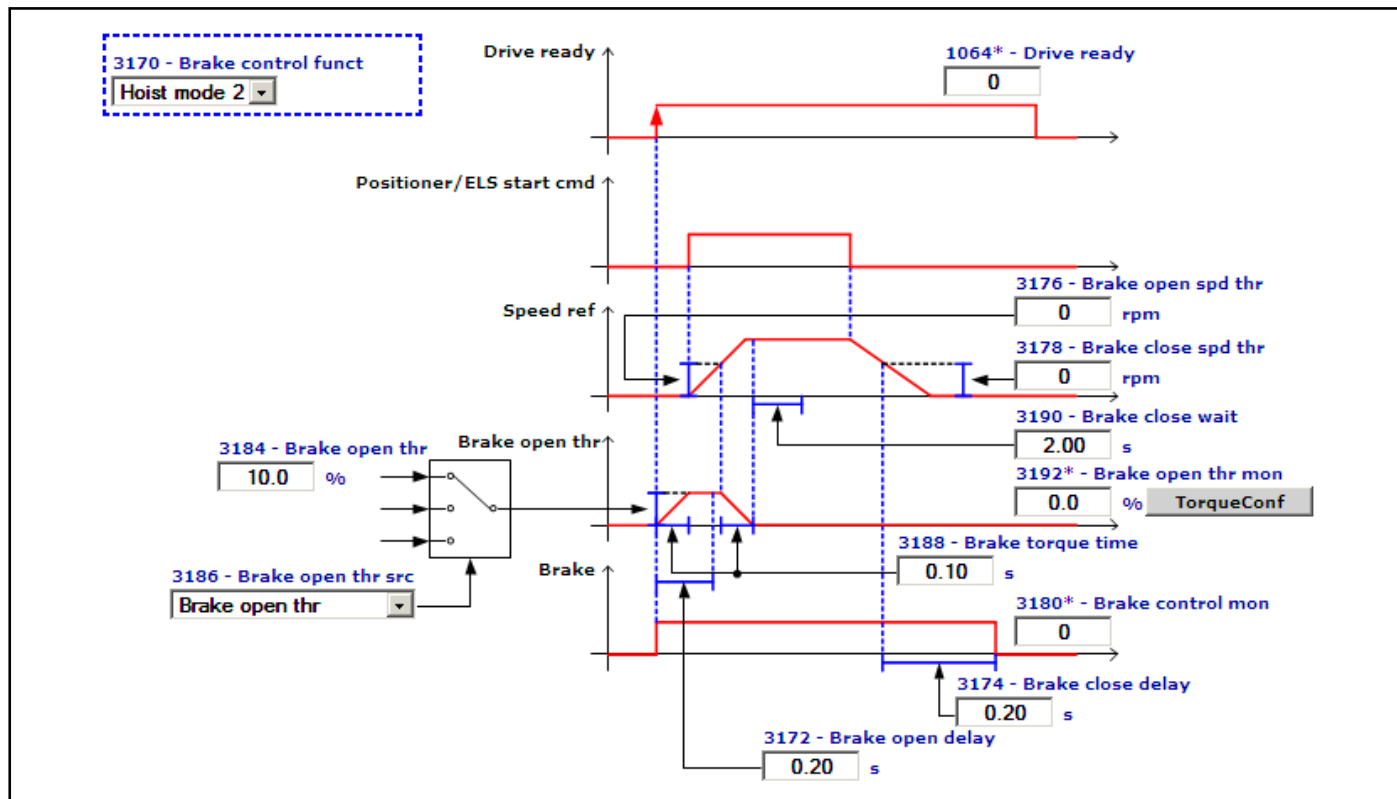
3186 - Brake open thr src

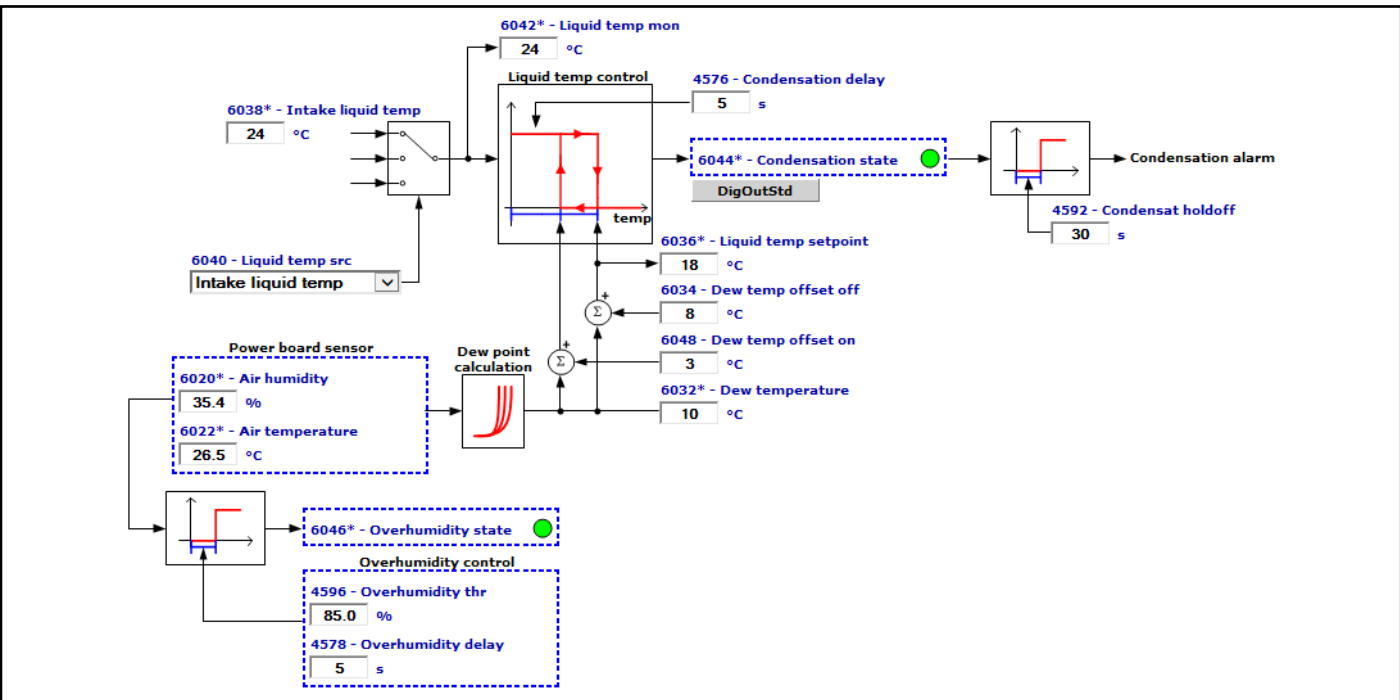
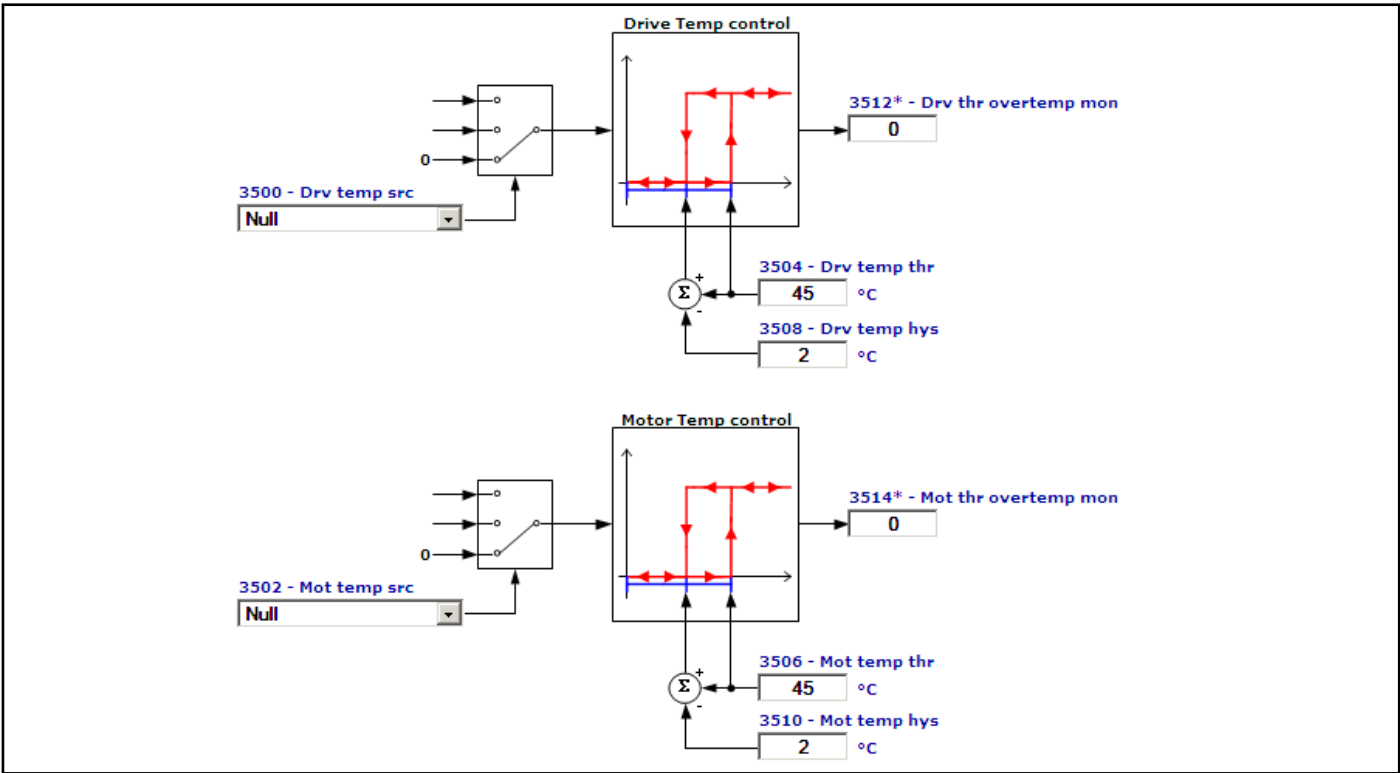
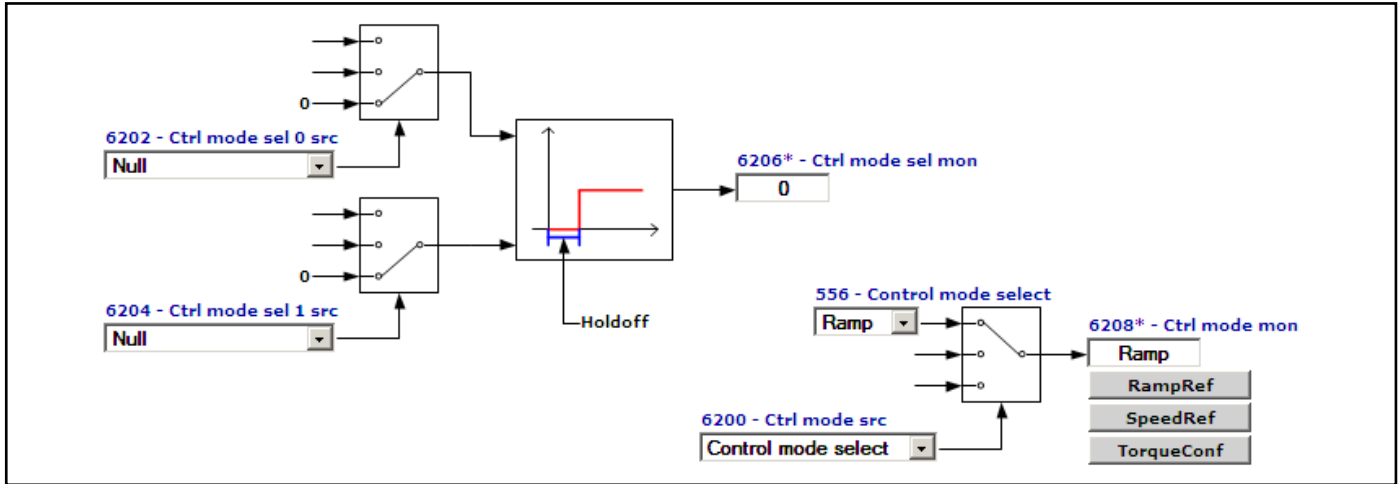
Brake open thr

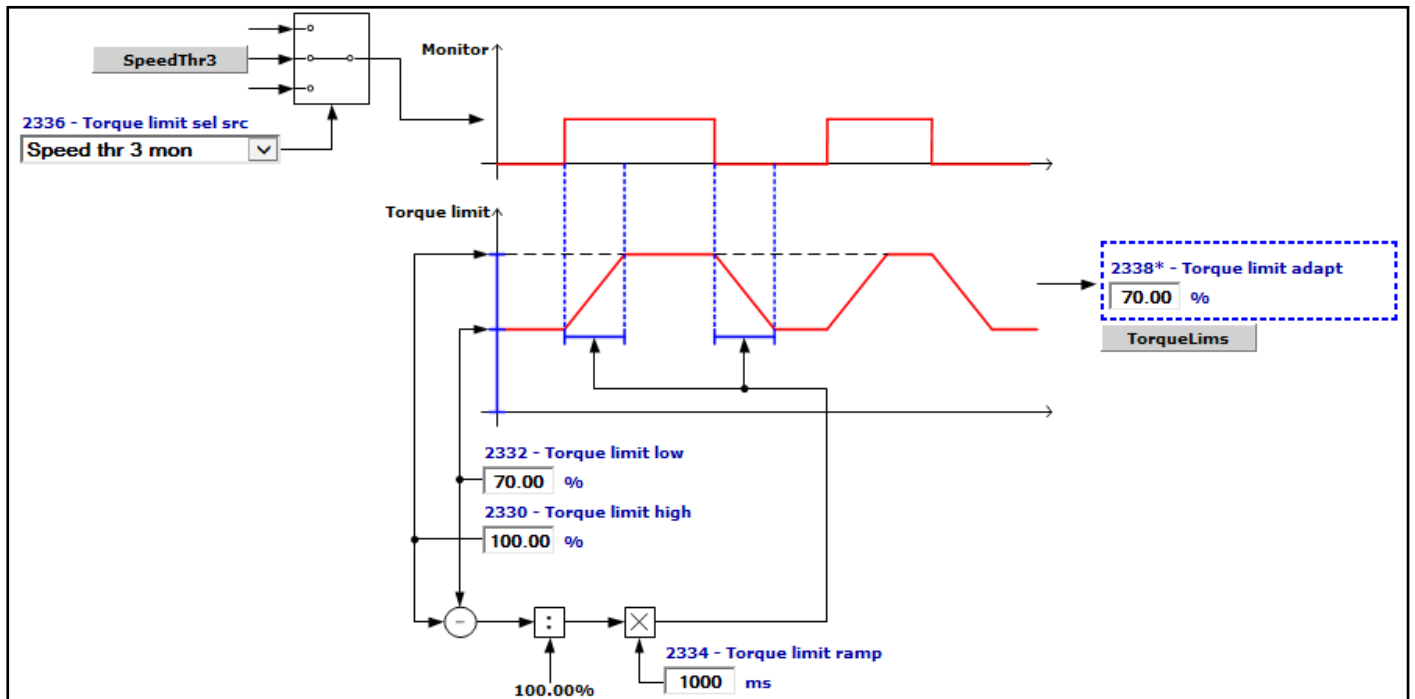
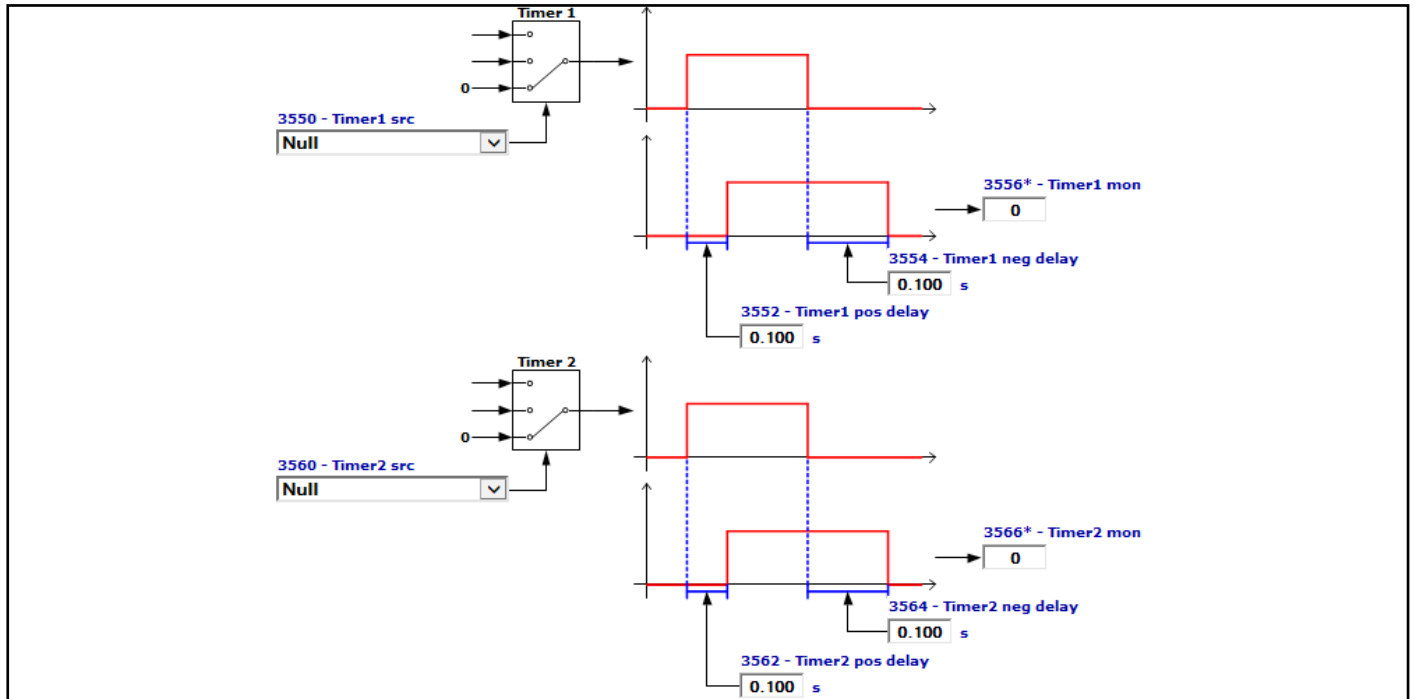
3182 - Brake open thr sel

Output curr









Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
F - Parameters List (Expert)									
Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
1 - MONITOR									
1.1	250	Output current	A	FLOAT	16/32 0.0	0.0	0.0	R	FVS
1.2	252	Output voltage	V	FLOAT	16/32 0.0	0.0	0.0	R	FVS
1.3	254	Output frequency	Hz	FLOAT	16/32 0.0	0.0	0.0	R	FVS
1.4	256	Output power	kW	FLOAT	16/32 0.0	0.0	0.0	R	FVS
1.5	288	Output cosphi		FLOAT	0.0	0.0	0.0	ER	FVS
1.6	3394	Output active curr	A	FLOAT	0.0	0.0	0.0	ER	FVS
1.7	628	Ramp setpoint	FF	INT16	16/32 0	0	0	R	FVS
1.8	664	Speed setpoint	FF	INT16	16/32 0	0	0	R	FVS
1.9	260	Motor speed	FF	INT16	16/32 0	0	0	R	FVS
1.10	270	DC link voltage	V	FLOAT	16/32 0.0	0.0	0.0	ER	FVS
1.11	272	Heatsink temperature	degC	INT16	16 0	0	0	ER	FVS
1.12	290	Motor temperature	degC	FLOAT	16 0.0	0.0	0.0	ER	FVS
1.13	292	Sensor inp X mon	degC	FLOAT	16 0.0	0.0	0.0	ER	FVS
1.14	1544	An inp 1 temp mon	degC	FLOAT	16 0.0	0.0	0.0	ER	FVS
1.15	1594	An inp 2 temp mon	degC	FLOAT	16 0.0	0.0	0.0	ER	FVS
1.16	1610	An inp 1X temp mon	degC	FLOAT	16 0.0	0.0	0.0	ER	FVS
1.17	1660	An inp 2X temp mon	degC	FLOAT	16 0.0	0.0	0.0	ER	FVS
1.18	2342	Working load	perc	FLOAT	0.0	0.0	0.0	ER	F_S
1.19	280	Torque current ref	A	FLOAT	16/32 0.0	0.0	0.0	ER	FVS
1.20	282	Magnet current ref	A	FLOAT	16/32 0.0	0.0	0.0	ER	F_S
1.21	284	Torque current	A	FLOAT	16/32 0.0	0.0	0.0	ER	F_S
1.22	286	Magnet current	A	FLOAT	16/32 0.0	0.0	0.0	ER	FVS
1.23	3212	Motor overload accum	perc	UINT16	16/32 0	0	100	ER	FVS
1.24	368	Drive overload accum	perc	UINT16	16/32 0	0	100	ER	FVS
1.25	3260	Bres overload accum	perc	UINT16	16/32 0	0	100	ER	FVS
1.26	1066	Enable state mon		BIT	16 0	0	1	R	FVS
1.27	1068	Start state mon		BIT	16 0	0	1	R	FVS
1.28	1070	FastStop state mon		BIT	16 0	0	1	R	FVS
1.29	1100	Digital input mon		UINT16	16 0	0	0	R	FVS
1.30	1300	Digital output mon		UINT16	0	0	0	R	FVS
1.31	1200	Digital input X mon		UINT16	16 0	0	0	R	FVS
1.32	1400	Digital output X mon		UINT16	0	0	0	R	FVS
1.33	5400	Dig inp 0Ext mon		UINT32	32 0	0	4294967295	ER	FVS
1.34	5402	Dig inp 1Ext mon		UINT32	32 0	0	4294967295	ER	FVS
1.35	5450	Digital out 0Ext mon		UINT32	32 0	0	0	ER	FVS
1.36	5452	Digital out 1Ext mon		UINT32	32 0	0	0	ER	FVS

2 - DRIVE INFO

2.1	480	Control type	ENUM	Asy	0	0	R	FVS
			2	Synchronous				
			1	Asynchronous				
2.2	482	Drive size	UINT16	0	0	0	RS	FVS
2.3	484	Drive family	ENUM	No power	0	0	RS	FVS
			0	No power				
			1	380V..480V				
			2	500V..575V				
			3	690V				
			4	230V				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				5	380V..480V LC				
2.4	486	Drive region		ENUM	EU	0	1	R	FVS
				0	EU				
				1	USA				
2.5	488	Drive cont current	A	FLOAT	CALCF	0.0	0.0	RZS	FVS
2.6	490	Firmware ver.rel		UINT16	0	0	0	R	FVS
2.7	496	Firmware type		UINT16	0	0	0	R	FVS
2.8	504	Application ver.rel		UINT16	0	0	0	ER	FVS
2.9	506	Application type		UINT16	0	0	0	ER	FVS
2.10	508	Application subver		UINT16	0	0	0	ER	FVS
2.11	510	Time drive power on	h.min	UINT32	0	0	0	ER	FVS
2.12	512	Time drive enable	h.min	UINT32	0	0	0	ER	FVS
2.13	514	Number power up		UINT16	0	0	0	ER	FVS
2.14	516	Time fan on	h.min	UINT32	0	0	0	ER	FVS
2.15	526	Power file ver.rel		UINT16	0	0	0	ER	FVS
2.16	530	Slot1 card type		ENUM	None	0	0	R	FVS
2.17	532	Slot2 card type		ENUM	None	0	0	R	FVS
2.18	534	Slot3 card type		ENUM	None	0	0	R	FVS
				0	None				
				769	I/O 1				
				1793	I/O 2				
				2305	I/O 3				
				3329	I/O 4				
				1544	Enc 1				
				1800	Enc 2				
				520	Enc 3				
				776	Enc 4				
				1032	Enc 5				
				2056	Enc 7				
				4	Can/Dnet				
				260	Profibus				
				516	RTE				
				576	FastLink				
				320	I/O Ext				
				832	I/O FastLink				
				255	Unknown				
				2312	Enc 8				
				1288	Enc 6				
				5633	I/O 6				
				6401	I/O 7				
				7681	I/O 8				
2.19	546	Fw enc sl2 ver.rel		UINT16	0	0	0	R	FVS
2.20	548	Fw enc sl2 type		UINT16	0	0	0	R	FVS
2.21	5300	Fw enc sl1-3 ver.rel		UINT16	0	0	0	R	FVS
2.22	5302	Fw enc sl1-3 type		UINT16	0	0	0	R	FVS
2.23	5724	Fw FastLink ver.rel		UINT16	0	0	0	ER	FVS
2.24	5726	Fw FastLink type		UINT16	0	0	0	ER	FVS

3 - STARTUP WIZARD

4 - DRIVE CONFIG

4.1	550	Save parameters		BIT	0	0	1	RW	FVS
4.2	552	Regulation mode		ENUM	V/f control	0	3	RWZ	FVS
				0	V/f control				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				1	Flux vector OL				
				2	Flux vector CL				
				3	Autotune				
4.3	554	Access mode		ENUM	Expert	0	1	RW	FVS
				0	Easy				
				1	Expert				
4.4	558	Application select		ENUM	None	0	2	ERWZ	FVS
				0	None				
				1	Application 1				
				2	Application 2				
4.5	560	Mains voltage		ENUM	400 V	SIZE	SIZE	ERWZS	FVS
				0	None				
				1	230 V				
				2	380 V				
				3	400 V				
				4	415 V				
				5	440 V				
				6	460 V				
				7	480 V				
				8	500 V				
				9	575 V				
				10	690 V				
4.6	586	DC supply		ENUM	None	0	7	ERWZS	FVS
				0	None				
				1	540V(380-480V)				
				2	650V(380-480V)				
				3	750V(380-480V)				
				10	675V(690V)				
				11	810V(690V)				
				12	935V(690V)				
				13	1120V(690V)				
4.7	450	Undervoltage	V	FLOAT	CALCF	CALCF	CALCF	ERWZS	FVS
4.8	562	Switching frequency		ENUM	SIZE	SIZE	SIZE	ERWS	FVS
				0	1 kHz				
				1	2 kHz				
				2	4 kHz				
				3	6 kHz				
				4	8 kHz				
				5	10 kHz				
				6	12 kHz				
				7	16 kHz				
4.9	564	Ambient temperature		ENUM	40 degC	0	1	ERWZ	FVS
				0	40 degC				
				1	50 degC				
4.10	566	Drive overload mode		ENUM	Heavy duty	1	2	ERWZ	FVS
				1	Heavy duty				
				2	Light duty				
4.11	568	Switching freq mode		ENUM	Constant	0	1	ERWZS	FVS
				0	Constant				
				1	Variable				
4.12	454	Chopper ON	V	FLOAT	CALCF	CALCF	CALCF	ERWZS	FVS
4.13	570	Password		UINT32	0	0	99999	ERW	FVS
4.14	572	Application key		UINT32	0	0	4294967295	ERW	FVS
4.15	574	Startup display		INT16	-1	-1	20000	ERW	FVS
4.16	576	Display backlight		BIT	0	0	1	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
4.17	578	Language select		ENUM	1		0	9	RWZ	FVS
				0	English					
				1	Italian					
				2	French					
				3	German					
				4	Spanish					
				5	Polish					
				6	Romanian					
				7	Russian					
				8	Turkish					
				9	Portuguese					
4.18	580	Load default		BIT	0		0	1	RWZ	FVS
4.19	590	Save par to keypad		BIT	0		0	1	RW	FVS
4.20	592	Load par from keypad		BIT	0		0	1	RWZ	FVS
4.21	594	Keypad memory select		UINT16	1		1	5	ERW	FVS
4.22	6100	Load synch control		BIT	0		0	1	ERW	FVS

5 - REFERENCES

5.1	600	Dig ramp ref 1	FF	INT16	16/32	0	CALCI	CALCI	RW	FVS
5.2	602	Dig ramp ref 2	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS
5.3	604	Dig ramp ref 3	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS
5.4	610	Ramp ref 1 src		LINK	16/32	1500	0	16384	RW	FVS
				L_MLTREF						
5.5	612	Ramp ref 2 src		LINK	16/32	602	0	16384	ERW	FVS
				L_MLTREF						
5.6	614	Ramp ref 3 src		LINK	16/32	894	0	16384	ERW	FVS
				L_MLTREF						
5.7	616	Ramp ref invert src		LINK	16	1050	0	16384	ERW	FVS
				L_DIGSEL2						
5.8	620	Ramp ref 1 mon	FF	INT16		0	0	0	R	FVS
5.9	622	Ramp ref 2 mon	FF	INT16		0	0	0	ER	FVS
5.10	624	Ramp ref 3 mon	FF	INT16		0	0	0	ER	FVS
5.11	634	Ramp ref top lim	FF	INT32		0	0	CALCI	ERWZ	FVS
5.12	636	Ramp ref bottom lim	FF	INT32		0	0	CALCI	ERWZ	FVS
5.13	630	Reference skip set	rpm	INT16		0	0	CALCI	ERW	FVS
5.14	632	Reference skip band	rpm	INT16		0	0	CALCI	ERW	FVS
5.15	640	Dig speed ref 1	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS
5.16	642	Dig speed ref 2	FF	INT16	16/32	0	CALCI	CALCI	ERW	FVS
5.17	650	Speed ref 1 src		LINK	16/32	640	0	16384	ERW	FVS
				L_MLTREF						
5.18	652	Speed ref 2 src		LINK	16/32	642	0	16384	ERW	FVS
				L_MLTREF						
5.19	654	Speed ref invert src		LINK	16	6000	0	16384	ERWZ	FVS
				L_DIGSEL2						
5.20	660	Speed ref 1 mon	FF	INT16		0	0	0	ER	FVS
5.21	662	Speed ref 2 mon	FF	INT16		0	0	0	ER	FVS
5.22	670	Speed ref top lim	FF	INT32		CALCI	0	CALCI	ERWZ	FVS
5.23	672	Speed ref bottom lim	FF	INT32		CALCI	CALCI	0	ERWZ	FVS
5.24	666	Speed ref filter	ms	UINT16		0	0	1000	ERW	FVS
5.25	680	Full scale speed	rpm	INT16		CALCI	50	32000	RWZ	FVS
5.26	222	Theta ref src		LINK	16/32	220	0	16384	ERW	F_S
				L_MLTREF						
5.27	226	Flux ref src		LINK	16/32	224	0	16384	ERW	F_S

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
L_MLTREF									
6 - RAMPS									
6.1	700	Acceleration time 0	s	FLOAT	10.0	0.01	1000.0	RW	FVS
6.2	702	Deceleration time 0	s	FLOAT	10.0	0.01	1000.0	RW	FVS
6.3	704	Acceleration time 1	s	FLOAT	10.0	0.01	1000.0	ERW	FVS
6.4	706	Deceleration time 1	s	FLOAT	10.0	0.01	1000.0	ERW	FVS
6.5	708	Acceleration time 2	s	FLOAT	10.0	0.01	1000.0	ERW	FVS
6.6	710	Deceleration time 2	s	FLOAT	10.0	0.01	1000.0	ERW	FVS
6.7	712	Acceleration time 3	s	FLOAT	10.0	0.01	1000.0	ERW	FVS
6.8	714	Deceleration time 3	s	FLOAT	10.0	0.01	1000.0	ERW	FVS
6.9	720	Ramp type		ENUM	Linear	0	3	ERWZ	FVS
				0	Linear				
				1	S-Shape				
				2	Bypass				
				3	Off				
6.10	722	Multi ramp sel 0 src		LINK	16 6000	0	16384	ERW	FVS
				L_DIGSEL2					
6.11	724	Multi ramp sel 1 src		LINK	16 6000	0	16384	ERW	FVS
				L_DIGSEL2					
6.12	726	Multi ramp sel mon		UINT16	0	0	3	ER	FVS
6.13	730	Accel jerk time 0	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.14	732	Decel jerk time 0	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.15	734	Accel jerk time 1	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.16	736	Decel jerk time 1	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.17	738	Accel jerk time 2	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.18	740	Decel jerk time 2	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.19	742	Accel jerk time 3	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.20	744	Decel jerk time 3	s	FLOAT	1.0	0.02	10.0	ERW	FVS
6.21	750	Ramp in zero src		LINK	16 6000	0	16384	ERW	FVS
				L_DIGSEL2					
6.22	752	Ramp out zero src		LINK	16 6000	0	16384	ERW	FVS
				L_DIGSEL2					
6.23	754	Ramp freeze src		LINK	16 3480	0	16384	ERW	FVS
				L_DIGSEL2					

7 - MULTI REFERENCE

7.1	800	Multi reference 0	FF	INT16	16/32 0	CALCI	CALCI	RW	FVS
7.2	802	Multi reference 1	FF	INT16	16/32 0	CALCI	CALCI	RW	FVS
7.3	804	Multi reference 2	FF	INT16	0	CALCI	CALCI	RW	FVS
7.4	806	Multi reference 3	FF	INT16	0	CALCI	CALCI	RW	FVS
7.5	808	Multi reference 4	FF	INT16	0	CALCI	CALCI	RW	FVS
7.6	810	Multi reference 5	FF	INT16	0	CALCI	CALCI	RW	FVS
7.7	812	Multi reference 6	FF	INT16	0	CALCI	CALCI	RW	FVS
7.8	814	Multi reference 7	FF	INT16	0	CALCI	CALCI	RW	FVS
7.9	816	Multi reference 8	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.10	818	Multi reference 9	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.11	820	Multi reference 10	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.12	822	Multi reference 11	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.13	824	Multi reference 12	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.14	826	Multi reference 13	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.15	828	Multi reference 14	FF	INT16	0	CALCI	CALCI	ERW	FVS
7.16	830	Multi reference 15	FF	INT16	0	CALCI	CALCI	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
7.17	832	Multi ref 0 src		LINK	16/32	800	0	16384	RW	FVS
				L_MLTREF						
7.18	834	Multi ref 1 src		LINK	16/32	802	0	16384	RW	FVS
				L_MLTREF						
7.19	840	Multi ref sel 0 src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
7.20	842	Multi ref sel 1 src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
7.21	844	Multi ref sel 2 src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
7.22	846	Multi ref sel 3 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
7.23	850	Multi ref sel mon		UINT16		0	0	15	R	FVS
7.24	852	Multi ref out mon	FF	INT16	16/32	0	0	0	R	FVS

8 - MOTORPOTENTIOMETER

8.1	870	Mpot setpoint	FF	INT16	16/32	0	CALCI	CALCI	R	FVS
8.2	872	Mpot acceleration	s	FLOAT		5.0	0.01	1000.0	RW	FVS
8.3	874	Mpot deceleration	s	FLOAT		5.0	0.01	1000.0	RW	FVS
8.4	876	Mpot top lim	FF	INT16		CALCI	CALCI	CALCI	ERW	FVS
8.5	878	Mpot bottom lim	FF	INT16		0	CALCI	CALCI	ERW	FVS
8.6	880	Mpot init cfg		ENUM		Zero	0	3	ERW	FVS
				0		Last Power Off				
				1		Zero				
				2		Lower Limit				
				3		Upper Limit				
8.7	882	Mpot preset cfg		ENUM		None	0	11	ERW	FVS
				0		None				
				1		Input=0				
				2		Input=low lim				
				3		Input&ref=0				
				4		Input&ref=low				
				5		Output=0				
				6		Output=low lim				
				7		Output&ref=0				
				8		Output&ref=low				
				9		Input=upp lim				
				10		Input&ref=upp				
				11		Freeze input				
8.8	884	Mpot up src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
8.9	886	Mpot down src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
8.10	888	Mpot invert src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
8.11	890	Mpot preset src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
8.12	892	Mpot mode		ENUM		Fine&Last val	0	3	ERW	FVS
				0		Ramp&Last val				
				1		Ramp&Follow				
				2		Fine&Last val				
				3		Fine&Follow				
8.13	894	Mpot output mon	rpm	INT16	16/32	0	0	0	ER	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
9 - JOG FUNCTION									
9.1	910	Jog setpoint	rpm	INT16	0	CALCI	CALCI	RW	FVS
9.2	912	Jog acceleration	s	FLOAT	5.0	0.01	1000.0	RW	FVS
9.3	914	Jog deceleration	s	FLOAT	5.0	0.01	1000.0	RW	FVS
9.4	916	Jog cmd + src		LINK	16 6000	0	16384	RW	FVS
				L_DIGSEL2					
9.5	918	Jog cmd - src		LINK	16 6000	0	16384	RW	FVS
				L_DIGSEL2					
9.6	920	Jog output mon	rpm	INT16	16/32 0	0	0	ER	FVS

10 - MONITOR FUNCTION

10.1	930	Reference 0 thr	rpm	INT16	30	0	CALCI	RW	FVS
10.2	932	Reference 0 delay	ms	UINT16	400	0	10000	RW	FVS
10.3	940	Speed 0 thr	rpm	INT16	30	0	CALCI	RW	FVS
10.4	942	Speed 0 delay	ms	UINT16	400	0	10000	RW	FVS
10.5	950	Speed threshold 1	rpm	INT32	0	CALCI	CALCI	RW	FVS
10.6	952	Speed threshold 2	rpm	INT32	0	CALCI	CALCI	RW	FVS
10.7	954	Speed threshold dly	ms	UINT16	0	0	50000	RW	FVS
10.8	960	Set speed ref src		LINK	16/32 628	0	16384	ERW	FVS
				L_CMP					
10.9	962	Set speed error	rpm	INT16	100	0	CALCI	RW	FVS
10.10	964	Set speed delay	ms	UINT16	0	0	50000	RW	FVS
10.11	968	Dig set speed ref	rpm	INT16	16/32 0	CALCI	CALCI	ERW	FVS
10.12	970	Speed threshold 3	rpm	INT32	0	0	CALCI	RW	FVS
10.13	972	Speed thr hysteresis	rpm	INT16	0	0	CALCI	RW	FVS
10.14	974	Speed thr 3 src		LINK	16/32 262	0	16384	ERW	FVS
				L_REF					
10.15	980	Current threshold	perc	INT16	100	0	200	RW	FVS
10.16	982	Current thr hyster	perc	INT16	0	0	100	RW	FVS

11 - COMMANDS

11.1	1000	Commands remote sel		ENUM	Terminal	0	1	RWZ	FVS
				0	Terminal				
				1	Digital				
11.2	1002	Commands local sel		ENUM	Keypad	0	1	ERWZ	FVS
				0	Terminal				
				2	Keypad				
11.3	1004	Enable/disable mode		ENUM	Stop/FS&Spd=0	0	3	ERWZ	FVS
				0	Off				
				1	Stop/FS&Spd=0				
				2	Stop&Spd=0				
				3	FS&Spd=0				
11.4	1006	Speed 0 disable dly	ms	UINT16	1000	0	10000	ERW	FVS
11.5	1008	Stop key mode		ENUM	Inactive	0	1	ERW	FVS
				0	Inactive				
				1	EmgStop&Alarm				
11.6	1010	Commands safe start		BIT	1	0	1	ERW	FVS
11.7	1012	Dig local/remote		ENUM	Remote	0	1	ERW	FVS
				0	Local				
				1	Remote				
11.8	1014	Local/remote src		LINK	16 1012	0	16384	ERW	FVS
				L_DIGSEL3					
11.9	1016	Terminal Start src		LINK	16 1048	0	16384	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
				L_DIGSEL2						
11.10	1018	Digital Enable src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
11.11	1020	Digital Start src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
11.12	1022	FastStop src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
11.13	1024	Enable cmd mon		BIT	16	0	0	1	R	FVS
11.14	1026	Start cmd mon		BIT	16	0	0	1	R	FVS
11.15	1028	FastStop cmd mon		BIT	16	0	0	1	R	FVS
11.16	1054	Safe start mon		BIT	16	0	0	1	ER	FVS
11.17	1040	FR mode		ENUM		Two wire	0	2	ERWZ	FVS
				0		Normal				
				1		Two wire				
				2		Three wire				
11.18	1042	FR forward src		LINK	16	1112	0	16384	ERW	FVS
				L_DIGSEL2						
11.19	1044	FR reverse src		LINK	16	1114	0	16384	ERW	FVS
				L_DIGSEL2						
11.20	1046	FR *stop src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
11.21	1048	FR start mon		BIT	16	0	0	1	ER	FVS
11.22	1050	FR reverse mon		BIT	16	0	0	1	ER	FVS
11.23	1052	FR cmd mon		UINT16		0	0	0	ER	FVS
11.24	1032	Drv interlock src		LINK	16	6002	0	16384	ERW	FVS
				L_DIGSEL2						
11.25	1034	Drv interlock mon		BIT	16	0	0	1	ER	FVS
11.26	1036	FastStop mode		ENUM		Not Latched	0	1	ERW	FVS
				0		Not Latched				
				1		Latched				

12 - DIGITAL INPUTS

12.1	1132	Dig inp 1 inversion		BIT		0	0	1	RW	FVS
12.2	1134	Dig inp 2 inversion		BIT		0	0	1	RW	FVS
12.3	1136	Dig inp 3 inversion		BIT		0	0	1	RW	FVS
12.4	1138	Dig inp 4 inversion		BIT		0	0	1	RW	FVS
12.5	1140	Dig inp 5 inversion		BIT		0	0	1	RW	FVS
12.6	1150	Digital input E dest		ILINK		0	0	0	ER	FVS
12.7	1152	Digital input 1 dest		ILINK		0	0	0	ER	FVS
12.8	1154	Digital input 2 dest		ILINK		0	0	0	ER	FVS
12.9	1156	Digital input 3 dest		ILINK		0	0	0	ER	FVS
12.10	1158	Digital input 4 dest		ILINK		0	0	0	ER	FVS
12.11	1160	Digital input 5 dest		ILINK		0	0	0	ER	FVS
12.12	1240	Dig inp 1X inversion		BIT		0	0	1	RW	FVS
12.13	1242	Dig inp 2X inversion		BIT		0	0	1	RW	FVS
12.14	1244	Dig inp 3X inversion		BIT		0	0	1	RW	FVS
12.15	1246	Dig inp 4X inversion		BIT		0	0	1	RW	FVS
12.16	1248	Dig inp 5X inversion		BIT		0	0	1	RW	FVS
12.17	1250	Dig inp 6X inversion		BIT		0	0	1	RW	FVS
12.18	1252	Dig inp 7X inversion		BIT		0	0	1	RW	FVS
12.19	1254	Dig inp 8X inversion		BIT		0	0	1	RW	FVS
12.20	5540	Dig inp 9X inversion		BIT		0	0	1	ERW	FVS
12.21	5542	Dig inp10X inversion		BIT		0	0	1	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
12.22	5544	Dig inp11X inversion		BIT	0	0	1	ERW	FVS
12.23	5546	Dig inp12X inversion		BIT	0	0	1	ERW	FVS
12.24	5548	Dig inp13X inversion		BIT	0	0	1	ERW	FVS
12.25	5550	Dig inp14X inversion		BIT	0	0	1	ERW	FVS
12.26	5552	Dig inp15X inversion		BIT	0	0	1	ERW	FVS
12.27	5554	Dig inp16X inversion		BIT	0	0	1	ERW	FVS
12.28	1270	Dig input 1X dest		ILINK	0	0	0	ER	FVS
12.29	1272	Dig input 2X dest		ILINK	0	0	0	ER	FVS
12.30	1274	Dig input 3X dest		ILINK	0	0	0	ER	FVS
12.31	1276	Dig input 4X dest		ILINK	0	0	0	ER	FVS
12.32	1278	Dig input 5X dest		ILINK	0	0	0	ER	FVS
12.33	1280	Dig input 6X dest		ILINK	0	0	0	ER	FVS
12.34	1282	Dig input 7X dest		ILINK	0	0	0	ER	FVS
12.35	1284	Dig input 8X dest		ILINK	0	0	0	ER	FVS
12.36	5570	Dig input 9X dest		ILINK	0	0	0	ER	FVS
12.37	5572	Dig input10X dest		ILINK	0	0	0	ER	FVS
12.38	5574	Dig input11X dest		ILINK	0	0	0	ER	FVS
12.39	5576	Dig input12X dest		ILINK	0	0	0	ER	FVS
12.40	5578	Dig input13X dest		ILINK	0	0	0	ER	FVS
12.41	5580	Dig input14X dest		ILINK	0	0	0	ER	FVS
12.42	5582	Dig input15X dest		ILINK	0	0	0	ER	FVS
12.43	5584	Dig input16X dest		ILINK	0	0	0	ER	FVS

13 - DIGITAL OUTPUTS

13.1	1310	Digital output 1 src		LINK	16	1062	0	16384	RW	FVS
				L_DIGSEL1						
13.2	1312	Digital output 2 src		LINK	16	1064	0	16384	RW	FVS
				L_DIGSEL1						
13.3	1314	Digital output 3 src		LINK	16	946	0	16384	RW	FVS
				L_DIGSEL1						
13.4	1316	Digital output 4 src		LINK	16	936	0	16384	RW	FVS
				L_DIGSEL1						
13.5	1330	Dig out 1 inversion		BIT	0	0	0	1	RW	FVS
13.6	1332	Dig out 2 inversion		BIT	0	0	0	1	RW	FVS
13.7	1334	Dig out 3 inversion		BIT	0	0	0	1	RW	FVS
13.8	1336	Dig out 4 inversion		BIT	0	0	0	1	RW	FVS
13.9	1410	Dig output 1X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.10	1412	Dig output 2X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.11	1414	Dig output 3X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.12	1416	Dig output 4X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.13	1418	Dig output 5X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.14	1420	Dig output 6X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.15	1422	Dig output 7X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.16	1424	Dig output 8X src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL1						
13.17	1426	Dig output 9X src		LINK	16	6000	0	16384	RW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				L_DIGSEL1					
13.18	1430	Dig out 1X inversion		BIT	0	0	1	RW	FVS
13.19	1432	Dig out 2X inversion		BIT	0	0	1	RW	FVS
13.20	1434	Dig out 3X inversion		BIT	0	0	1	RW	FVS
13.21	1436	Dig out 4X inversion		BIT	0	0	1	RW	FVS
13.22	1438	Dig out 5X inversion		BIT	0	0	1	RW	FVS
13.23	1440	Dig out 6X inversion		BIT	0	0	1	RW	FVS
13.24	1442	Dig out 7X inversion		BIT	0	0	1	RW	FVS
13.25	1444	Dig out 8X inversion		BIT	0	0	1	RW	FVS
13.26	1446	Dig out 9X inversion		BIT	0	0	1	RW	FVS

14 - ANALOG INPUTS

14.1	1500	Analog input 1 mon	cnt	INT16	16/32 0	-16384	16384	R	FVS
14.2	1502	Analog inp 1 type		ENUM	-10V..+10V 0	0	4	RW	FVS
				0	-10V..+10V				
				1	0.20mA , 0.10V				
				2	4..20mA				
				3	0.1V..10.1V				
				4	KTY84				
14.3	1504	Analog inp 1 scale		FLOAT	1.0	-10.0	10.0	RW	FVS
14.4	1506	An inp 1 offset tune		BIT	0	0	1	RW	FVS
14.5	1508	An inp 1 gain tune		BIT	0	0	1	RW	FVS
14.6	1510	Analog inp 1 filter	ms	FLOAT	10.0	1.0	1000.0	ERW	FVS
14.7	1512	Analog inp 1 top	cnt	INT16	16384	-32768	+32767	ERW	FVS
14.8	1514	Analog inp 1 bottom	cnt	INT16	-16384	-32768	+32767	ERW	FVS
14.9	1516	Analog inp 1 offset	cnt	INT16	0	-32768	+32767	ERW	FVS
14.10	1518	Analog inp 1 gain		FLOAT	1.0	-10.0	10.0	ERW	FVS
14.11	1520	Analog inp 1 thr	cnt	INT16	0	-16384	+16384	ERW	FVS
14.12	1522	An inp 1 deadband	perc	FLOAT	0.0	0.0	100.0	ERW	FVS
14.13	1524	An inp 1 alt value	cnt	INT16	16/32 0	-16384	16384	ERW	FVS
14.14	1526	An inp 1 sign src		LINK	16 6000	0	16384	ERW	FVS
				L_DIGSEL2					
14.15	1528	An inp 1 alt sel src		LINK	16 6000	0	16384	ERW	FVS
				L_DIGSEL2					
14.16	1532	Analog input 1 dest		ILINK	0	0	0	ER	FVS
14.17	1550	Analog input 2 mon	cnt	INT16	16/32 0	-16384	16384	R	FVS
14.18	1552	Analog inp 2 type		ENUM	-10V..+10V 0	0	4	RW	FVS
				0	-10V..+10V				
				1	0.20mA , 0.10V				
				2	4..20mA				
				3	0.1V..10.1V				
				4	KTY84				
14.19	1554	Analog inp 2 scale		FLOAT	1.0	-10.0	10.0	RW	FVS
14.20	1556	An inp 2 offset tune		BIT	0	0	1	RW	FVS
14.21	1558	An inp 2 gain tune		BIT	0	0	1	RW	FVS
14.22	1560	Analog inp 2 filter	ms	FLOAT	10.0	1.0	1000.0	ERW	FVS
14.23	1562	Analog inp 2 top	cnt	INT16	16384	-32768	+32767	ERW	FVS
14.24	1564	Analog inp 2 bottom	cnt	INT16	-16384	-32768	+32767	ERW	FVS
14.25	1566	Analog inp 2 offset	cnt	INT16	0	-32768	+32767	ERW	FVS
14.26	1568	Analog inp 2 gain		FLOAT	1.0	-10.0	10.0	ERW	FVS
14.27	1570	Analog inp 2 thr	cnt	INT16	0	-16384	+16384	ERW	FVS
14.28	1572	An inp 2 deadband	perc	FLOAT	0.0	0.0	100.0	ERW	FVS
14.29	1574	An inp 2 alt value	cnt	INT16	16/32 0	-16384	16384	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.30	1576	An inp 2 sign src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
14.31	1578	An inp 2 alt sel src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
14.32	1582	Analog input 2 dest		ILINK		0	0	0	ER	FVS
14.33	1600	Analog input 1X mon	cnt	INT16	16/32	0	-16384	16384	R	FVS
14.34	1602	Analog inp 1X type		ENUM		-10V..+10V	0	8	RW	FVS
				0		-10V..+10V				
				1		0..10V				
				2		4..20mA				
				3		0..20mA				
				4		PT1000				
				5		NI1000				
				6		PT100				
				7		0.1V..10.1V				
				8		KTY84				
14.35	1604	Analog inp 1X scale		FLOAT		1.0	-20.0	20.0	RW	FVS
14.36	1606	An inp 1Xoffset tune		BIT		0	0	1	RW	FVS
14.37	1608	An inp 1X gain tune		BIT		0	0	1	RW	FVS
14.38	1620	Analog inp 1X filter	ms	UINT16		0	0	1000	ERW	FVS
14.39	1612	Analog inp 1X top	cnt	INT16		16384	-32768	+32767	ERW	FVS
14.40	1614	Analog inp 1X bottom	cnt	INT16		-16384	-32768	+32767	ERW	FVS
14.41	1616	Analog inp 1X offset	cnt	INT16		0	-32768	+32767	ERW	FVS
14.42	1618	Analog inp 1X gain		FLOAT		1.0	-20.0	20.0	ERW	FVS
14.43	1626	An inp 1X sign src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
14.44	1632	Analog input 1X dest		ILINK		0	0	0	ER	FVS
14.45	1650	Analog input 2X mon	cnt	INT16	16/32	0	-16384	16384	R	FVS
14.46	1652	Analog inp 2X type		ENUM		-10V..+10V	0	8	RW	FVS
				0		-10V..+10V				
				1		0..10V				
				2		4..20mA				
				3		0..20mA				
				4		PT1000				
				5		NI1000				
				6		PT100				
				7		0.1V..10.1V				
				8		KTY84				
14.47	1654	Analog inp 2X scale		FLOAT		1.0	-20.0	20.0	RW	FVS
14.48	1656	An inp 2Xoffset tune		BIT		0	0	1	RW	FVS
14.49	1658	An inp 2X gain tune		BIT		0	0	1	RW	FVS
14.50	1670	Analog inp 2X filter	ms	UINT16		0	0	1000	ERW	FVS
14.51	1662	Analog inp 2X top	cnt	INT16		16384	-32768	+32767	ERW	FVS
14.52	1664	Analog inp 2X bottom	cnt	INT16		-16384	-32768	+32767	ERW	FVS
14.53	1666	Analog inp 2X offset	cnt	INT16		0	-32768	+32767	ERW	FVS
14.54	1668	Analog inp 2X gain		FLOAT		1.0	-20.0	20.0	ERW	FVS
14.55	1676	An inp 2X sign src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
14.56	1682	Analog input 2X dest		ILINK		0	0	0	ER	FVS
14.57	5410	Analog inp 0Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.58	5412	Analog inp 1Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.59	5414	Analog inp 2Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.60	5416	Analog inp 3Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.61	5418	Analog inp 4Ext mon		INT16	16	0	-32768	32767	ER	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
14.62	5420	Analog inp 5Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.63	5422	Analog inp 6Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.64	5424	Analog inp 7Ext mon		INT16	16	0	-32768	32767	ER	FVS
14.65	1586	Sensor inp X type		ENUM		None	0	3	ERW	FVS
				0		None				
				1		Klixon				
				2		KTY84				
				3		PTC				

15 - ANALOG OUTPUTS

15.1	1800	Analog out 1 src		LINK	16/32	6000	0	16384	RW	FVS
				L_ANOUT						
15.2	1802	Analog out 2 src		LINK	16/32	6000	0	16384	RW	FVS
				L_ANOUT						
15.3	1808	Analog out 1 scale		FLOAT		1.0	-10.0	10.0	RW	FVS
15.4	1810	Analog out 2 scale		FLOAT		1.0	-10.0	10.0	RW	FVS
15.5	1816	Analog out 1 mon	cnt	INT16		0	0	0	ER	FVS
15.6	1818	Analog out 2 mon	cnt	INT16		0	0	0	ER	FVS
15.7	1824	An out 1 absolute		ENUM		Disable	0	1	ERW	FVS
				0		Disable				
				1		Enable				
15.8	1826	An out 2 absolute		ENUM		Disable	0	1	ERW	FVS
				0		Disable				
				1		Enable				
15.9	1832	Analog out 1 min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.10	1834	Analog out 1 max	cnt	INT16		16384	-32768	+32767	ERW	FVS
15.11	1840	Analog out 2 min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.12	1842	Analog out 2 max	cnt	INT16		16384	-32768	+32767	ERW	FVS
15.13	1848	Analog out 2 type		ENUM		-10V..+10V	0	2	ERW	FVS
				0		0..20mA				
				1		4..20mA				
				2		-10V..+10V				
15.14	1850	Analog out 1X src		LINK	16/32	6000	0	16384	RW	FVS
				L_ANOUT						
15.15	1852	Analog out 2X src		LINK	16/32	6000	0	16384	RW	FVS
				L_ANOUT						
15.16	1858	Analog out 1X scale		FLOAT		1.0	-20.0	20.0	RW	FVS
15.17	1860	Analog out 2X scale		FLOAT		1.0	-20.0	20.0	RW	FVS
15.18	1866	Analog out 1X mon	cnt	INT16		0	0	0	ER	FVS
15.19	1868	Analog out 2X mon	cnt	INT16		0	0	0	ER	FVS
15.20	1874	An out 1X absolute		ENUM		Disable	0	1	ERW	FVS
				0		Disable				
				1		Enable				
15.21	1876	An out 2X absolute		ENUM		Disable	0	1	ERW	FVS
				0		Disable				
				1		Enable				
15.22	1882	Analog out 1X min	cnt	INT16		-16384	-32768	+32767	ERW	FVS
15.23	1884	Analog out 1X max	cnt	INT16		16384	-32768	+32767	ERW	FVS
15.24	1886	Analog out 1X type		ENUM		-10V..+10V	0	3	ERW	FVS
				0		0..20mA				
				1		4..20mA				
				2		-10V..+10V				
				3		0..10V				
15.25	1890	Analog out 2X min	cnt	INT16		-16384	-32768	+32767	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
15.26	1892	Analog out 2X max	cnt	INT16	16384	-32768	+32767	ERW	FVS
15.27	1898	Analog out 2X type		ENUM	-10V..+10V	0	3	ERW	FVS
				0	0..20mA				
				1	4..20mA				
				2	-10V..+10V				
				3	0..10V				
15.28	5460	Dig Analog out 0 ext		INT16	16 0	-32768	32767	ERW	FVS
15.29	5462	Dig Analog out 1 ext		INT16	16 0	-32768	32767	ERW	FVS
15.30	5464	Dig Analog out 2 ext		INT16	16 0	-32768	32767	ERW	FVS
15.31	5466	Dig Analog out 3 ext		INT16	16 0	-32768	32767	ERW	FVS
15.32	5468	Dig Analog out 4 ext		INT16	16 0	-32768	32767	ERW	FVS
15.33	5470	Dig Analog out 5 ext		INT16	16 0	-32768	32767	ERW	FVS
15.34	5472	Dig Analog out 6 ext		INT16	16 0	-32768	32767	ERW	FVS
15.35	5474	Dig Analog out 7 ext		INT16	16 0	-32768	32767	ERW	FVS

16 - MOTOR DATA

16.1	2000	Rated voltage	V	FLOAT	SIZE	50.0	690.0	RWZS	FVS
16.2	2002	Rated current	A	FLOAT	SIZE	0.3	2200.0	RWZS	FVS
16.3	2004	Rated speed	rpm	FLOAT	SIZE	10.0	32000.0	RWZS	FVS
16.4	2006	Rated frequency	Hz	FLOAT	SIZE	10.0	1000.0	RWZS	FVS
16.5	2008	Pole pairs		UINT16	SIZE	1	20	RWZS	FVS
16.6	2010	Rated power	kW	FLOAT	SIZE	0.05	2000.0	RWZS	FVS
16.7	2012	Rated power factor		FLOAT	SIZE	0.6	0.95	RWZS	FVS
16.8	2020	Take parameters		BIT	0	0	1	RWZ	FVS
16.9	2022	Autotune rotation		BIT	0	0	1	RWZ	FVS
16.10	2024	Autotune still		BIT	0	0	1	RWZ	FVS
16.11	2026	Autotune mode		ENUM	Reduced	0	1	ERWZ	FVS
				0	Reduced				
				1	Extended				
16.12	2028	Take par status		ENUM	Required	0	0	R	FVS
				0	Required				
				1	Done				
16.13	2030	Autotune status		ENUM	Required	0	0	R	FVS
				0	Required				
				1	Done				
16.14	2050	Measured Rs	ohm	FLOAT	CALCF	0.0005	200.0	ERWS	FVS
16.15	2052	Measured DTL	V	FLOAT	0.0	0.0	100.0	ERWS	FVS
16.16	2054	Measured DTS	V/A	FLOAT	0.0	0.0	100.0	ERWS	FVS
16.17	2056	Measured Lsig	mH	FLOAT	CALCF	0.01	700	ERWS	FVS
16.18	2058	Measured ImN	A	FLOAT	CALCF	0.1	1500.0	ERWS	FVS
16.19	2060	Measured ImX	A	FLOAT	CALCF	0.0	0.0	ERWS	FVS
16.20	2062	Measured FlxN	Wb	FLOAT	CALCF	0.05	10.0	ERWS	FVS
16.21	2064	Measured FlxX	Wb	FLOAT	CALCF	0.0	0.0	ERWS	FVS
16.22	2066	Measured P1		FLOAT	0.5	0.0	1.0	ERWS	FVS
16.23	2068	Measured P2		FLOAT	9.0	3.0	18.0	ERWS	FVS
16.24	2070	Measured P3		FLOAT	0.87	0.0	1.0	ERWS	FVS
16.25	2072	Measured Rr	ohm	FLOAT	CALCF	0.0005	200.0	ERWS	FVS
16.26	2078	Take tune parameters		BIT	0	0	1	ERWZ	FVS

17 - ENCODER

17.1 - ENCODER/ENCODER CONFIG

17.1.1	5310	Encoder sel src		LINK	16 6000	0	16384	ERW	FVS
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Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				L_DIGSEL2					
17.1.2	5314	Encoder sel mon		UINT16	0	0	1	ER	FVS
17.1.3	2172	SpdFbkLoss code		UINT32	0	0	0	ER	FVS

17.2 - ENCODER/ENCODER 1

17.2.1	2100	Encoder 1 pulses	ppr	UINT16	CALCI	CALCI	CALCI	RWZ	FVS
17.2.2	2102	Encoder 1 supply	V	FLOAT	5.2	5.2	CALCF	ERWZ	FVS
17.2.3	2104	Encoder 1 input cfg		ENUM	TTL	0	1	ERWZ	FVS
				0	HTL				
				1	TTL				
17.2.4	2106	Encoder 1 repetition		ENUM	No division	0	3	ERWZ	FVS
				0	No division				
				1	Divide 2				
				2	Divide 4				
				3	Divide 8				
17.2.5	2108	Encoder 1 signal Vpp	V	FLOAT	1.0	0.8	1.2	ERWZ	FVS
17.2.6	2110	Encoder1signal check		ENUM	Check A-B	0	3	ERWZ	FVS
				0	Check disabled				
				1	Check A-B				
				2	Check A-B-Z				
				4	Check A-B-SE				
17.2.7	2112	Encoder 1 SSI clocks		UINT16	13	11	25	ERWZ	FVS
17.2.8	2114	Encoder1SSI pos bits		UINT16	13	11	25	ERWZ	FVS
17.2.9	2182	Encoder1 ENDAT clock		ENUM	1 MHz	0	1	ERWZ	FVS
				0	1 MHz				
				1	500 kHz				
17.2.10	2130	Encoder 1 direction		ENUM	Not inverted	0	1	RWZ	FVS
				0	Not inverted				
				1	Inverted				
17.2.11	2132	Encoder 1 mode		ENUM	None	CALCI	CALCI	ERWZ	FVS
				0	None				
				1	Digital FP				
				2	Digital F				
				3	Sinus				
				4	Sinus SINCOS				
				5	Sinus ENDAT				
				6	Sinus SSI				
				7	Sinus HIPER				
				8	Resolver				
				9	Abs SINCOS				
				10	ENDAT				
				11	SSI				
17.2.12	2134	Encoder1speed filter	ms	FLOAT	2.0	0.125	20.0	ERW	FVS
17.2.13	2150	Encoder 1 speed	rpm	INT16	16/32 0	0	0	ER	FVS
17.2.14	2162	Encoder 1 position	cnt	UINT16	16 0	0	0	ER	FVS
17.2.15	5350	Encoder 1 state		UINT16	0	0	0	ER	FVS
17.2.16	5352	Encoder 1 err code		UINT32	0	0	0	ER	FVS

17.3 - ENCODER/ENCODER 2

17.3.1	5100	Encoder 2 pulses	ppr	UINT16	CALCI	CALCI	CALCI	ERWZ	FVS
17.3.2	5102	Encoder 2 supply	V	FLOAT	5.2	5.2	CALCF	ERWZ	FVS
17.3.3	5104	Encoder 2 input cfg		ENUM	TTL	0	1	ERWZ	FVS
				0	HTL				
				1	TTL				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
17.3.4	5106	Encoder 2 repetition		ENUM	No division	0	3	ERWZ	FVS
				0	No division				
				1	Divide 2				
				2	Divide 4				
				3	Divide 8				
17.3.5	5108	Encoder 2 signal Vpp	V	FLOAT	1.0	0.8	1.2	ERWZ	FVS
17.3.6	5110	Encoder2signal check		ENUM	Check A-B	0	3	ERWZ	FVS
				0	Check disabled				
				1	Check A-B				
				2	Check A-B-Z				
				4	Check A-B-SE				
17.3.7	5112	Encoder 2 SSI clocks		UINT16	13	11	25	ERWZ	FVS
17.3.8	5114	Encoder2SSI pos bits		UINT16	13	11	25	ERWZ	FVS
17.3.9	5182	Encoder2 ENDAT clock		ENUM	1 MHz	0	1	ERWZ	FVS
				0	1 MHz				
				1	500 kHz				
17.3.10	5130	Encoder 2 direction		ENUM	Not inverted	0	1	ERWZ	FVS
				0	Not inverted				
				1	Inverted				
17.3.11	5132	Encoder 2 mode		ENUM	None	CALCI	CALCI	ERWZ	FVS
				0	None				
				1	Digital FP				
				2	Digital F				
				3	Sinus				
				4	Sinus SINCOS				
				5	Sinus ENDAT				
				6	Sinus SSI				
				7	Sinus HIPER				
				8	Resolver				
				9	Abs SINCOS				
				10	ENDAT				
				11	SSI				
17.3.12	5134	Encoder2speed filter	ms	FLOAT	2.0	0.125	20.0	ERW	FVS
17.3.13	5150	Encoder 2 speed	rpm	INT16	16/32	0	0	ER	FVS
17.3.14	5162	Encoder 2 position	cnt	UINT16	16	0	0	ER	FVS
17.3.15	5360	Encoder 2 state		UINT16	0	0	0	ER	FVS
17.3.16	5362	Encoder 2 err code		UINT32	0	0	0	ER	FVS

17.4 - ENCODER/ENCODER 3

17.4.1	5200	Encoder 3 pulses	ppr	UINT16	1024	128	32768	ERWZ	FVS
17.4.2	5204	Encoder 3 input cfg		ENUM	TTL	0	1	ERWZ	FVS
				0	HTL				
				1	TTL				
17.4.3	5210	Encoder3signal check		ENUM	Check A-B	0	3	ERWZ	FVS
				0	Check disabled				
				1	Check A-B				
				2	Check A-B-Z				
				4	Check A-B-SE				
17.4.4	5230	Encoder 3 direction		ENUM	Not inverted	0	1	ERWZ	FVS
				0	Not inverted				
				1	Inverted				
17.4.5	5262	Encoder 3 position	cnt	UINT16	16	0	0	ER	FVS
17.4.6	5370	Encoder 3 state		UINT16	0	0	0	ER	FVS
17.4.7	5372	Encoder 3 err code		UINT32	0	0	0	ER	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
17.5 - ENCODER/RESOLVER									
17.5.1	2116	Resolver pole pairs		UINT16	1	1	8	ERWZ	FVS
17.5.2	2118	Resolver frequency	Hz	UINT16	8000	2000.0	10000.0	ERWZ	FVS
17.5.3	2120	Resolver T ratio K		FLOAT	0.5	0.2	1.0	ERWZ	FVS
17.5.4	2122	Resolver repetition		ENUM	16384 ppr	0	3	ERWZ	FVS
				0	256 ppr				
				1	1024 ppr				
				2	4096 ppr				
				3	16384 ppr				
17.5.5	2124	Resolver LOS thr	V	FLOAT	2.200	0.000	4.820	ERWZ	FVS
17.5.6	2128	Resolver MIS thr	V	FLOAT	0.380	0.000	4.820	ERWZ	FVS
17.5.7	2094	Resolver freeze0 src		LINK	16 6000	0	16384	ERWZ	FVS
				L_RESFREEZE					
17.5.8	2096	Resolver freeze1 src		LINK	16 6000	0	16384	ERWZ	FVS
				L_RESFREEZE					

18 - SPEED REG GAINS

18.1	2200	Speed reg P1 gain	perc	INT16	100	0	1000	RW	F_S
18.2	2202	Speed reg I1 gain	perc	INT16	100	0	1000	RW	F_S
18.3	2204	Speed reg P2 gain	perc	INT16	100	0	1000	ERW	F_S
18.4	2206	Speed reg I2 gain	perc	INT16	100	0	1000	ERW	F_S
18.5	2216	Gain adapt src		LINK	16/32 664	0	16384	ERW	F_S
				L_REF					
18.6	2218	Gain adp spd thr1_2	perc	FLOAT	0.0	0.0	100.0	ERW	F_S
18.7	2220	Gain adp spd band1_2	perc	FLOAT	0.0	0.0	100.0	ERW	F_S
18.8	2226	Gain 0 enable		ENUM	Disable	0	1	ERW	F_S
				0	Disable				
				1	Enable				
18.9	2228	Speed reg P0 gain	perc	INT16	100	0	1000	ERW	F_S
18.10	2230	Speed reg I0 gain	perc	INT16	100	0	1000	ERW	F_S
18.11	2232	Spd reg P gain Inuse	perc	INT16	16/32 100	0	1000	ER	F_S
18.12	2234	Spd reg I gain Inuse	perc	INT16	16/32 100	0	1000	ER	F_S
18.13	2236	Speed reg P gain	N/rpm	FLOAT	CALCF	0.0	500.0	ERWS	F_S
18.14	2238	Speed reg I time	ms	FLOAT	CALCF	1.0	5000.0	ERWS	F_S
18.15	2244	Speed reg I dis src		LINK	16/32 6000	0	16384	ERW	F_S
				L_DIGSEL2					
18.16	2246	Speed reg P factor	perc	FLOAT	16/32 0	0	0	ER	F_S
18.17	2248	Speed reg I factor	perc	FLOAT	16/32 0	0	0	ER	F_S
18.18	2240	Inertia	kgm2	FLOAT	SIZE	0.001	100.0	RWZS	F_S
18.19	2242	Bandwidth	rad/s	FLOAT	SIZE	1.0	500.0	RWZS	F_S

19 - REGULATOR PARAM

19.1	2250	Current reg P gain	V/A	FLOAT	CALCF	0.0	0.0	ERWS	F_S
19.2	2252	Current reg I time	ms	FLOAT	CALCF	0.01	10000.0	ERWS	F_S
19.3	2260	Flux reg P gain	A/Wb	FLOAT	CALCF	0.0	0.0	ERWS	F__
19.4	2262	Flux reg I time	ms	FLOAT	CALCF	0.1	10000.0	ERWS	F__
19.5	2264	Flux reg P gain OL	A/Wb	FLOAT	CALCF	0.0	0.0	ERWS	__S
19.6	2266	Flux reg I time OL	ms	FLOAT	CALCF	0.1	30000	ERWS	__S
19.7	2270	Voltage reg P gain	Wb/V	FLOAT	CALCF	0.0	0.0	ERWS	F_S
19.8	2272	Voltage reg I time	s	FLOAT	CALCF	0.1	100.0	ERWS	F_S
19.9	2280	Dead time limit	V	FLOAT	SIZE	0.0	50.0	ERWS	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
19.10	2282	Dead time slope	V/A	FLOAT	SIZE	0.0	200.0	ERWS	FVS
19.11	2290	Voltage base	V	FLOAT	CALCF	50.0	690.0	ERWS	F_S
19.12	2292	Voltage margin	perc	FLOAT	5.0	0.0	10.0	ERWS	F_S
19.13	2300	Minimum speed OL	rpm	INT16	30	0	CALCI	ERW	S
19.14	2302	Min speed delay OL	ms	UINT16	200	0	5000	ERW	S
19.15	2304	Speed filter OL	ms	FLOAT	5.0	0.1	20.0	ERWZ	S
19.16	2306	Flux observ gainH OL		FLOAT	250.0	10.0	5000.0	ERW	S
19.17	2322	Freq observ gainH OL	rad/s	FLOAT	50.0	0.0	5000.0	ERW	S
19.18	2316	Flux observ gainL OL		FLOAT	100.0	0.0	5000.0	ERW	S
19.19	2324	Freq observ gainL OL	rad/s	FLOAT	1.0	0.0	5000.0	ERW	S
19.20	2308	OverFlux perc	perc	FLOAT	100.0	100.0	140.0	ERW	S
19.21	2310	Flux weakening OL		ENUM	Enable	0	1	ERWZ	S
				0	Disable				
				1	Enable				
19.22	2312	OverFlux spd thr	rpm	FLOAT	400	10.0	1000.0	ERW	S
19.23	2314	Flux step		FLOAT	20.0	1	2000	ERW	S
19.24	2320	Magnetization time	ms	UINT16	256	128	4096	ERWZ	FVS
19.25	2504	Torque comp offset	Nm	FLOAT	0.0	0	1000	ERW	F_S
19.26	2506	Measured motor temp	degC	FLOAT	20.0	-20.0	150.0	ERW	F_S
19.27	2510	Motor temp comp en		ENUM	Disable	0	1	ERWZ	F_S
				0	Disable				
				1	Enable				
19.28	2512	Torque offset speed	perc	UINT16	75	10	100	ERWZ	S
19.29	2514	Torque offset ramp	s	FLOAT	10.0	10	200	ERWZ	S
19.30	2516	Torque offset tune		BIT	0	0	1	ERWZ	S

20 - TORQUE CONFIG

20.1	2350	Torque curr lim Pos	A	FLOAT	16/32 CALCF	0.0	CALCF	ERWS	FVS
20.2	2352	Torque curr lim Neg	A	FLOAT	16/32 CALCF	0.0	CALCF	ERWS	FVS
20.3	2354	Torque curr lim sel		ENUM	Off	0	4	ERWZ	FVS
				0	Off				
				1	T clim +/-				
				2	T clim mot/gen				
				3	T lim sym				
				4	T lim pos/neg				
20.4	2358	Torque lim pos src		LINK	16/32 6000	0	16384	ERWZ	F_S
				L_PLIM					
20.5	2370	Torque lim neg src		LINK	16/32 6000	0	16384	ERWZ	F_S
				L_NLIM					
20.6	2372	Torque limit pos	perc	FLOAT	16/32 CALCF	0.0	CALCF	ERW	F_S
20.7	2374	Torque limit neg	perc	FLOAT	16/32 CALCF	0.0	CALCF	ERW	F_S
20.8	2376	Torque lim unit sel		ENUM	Perc	0	1	ERW	F_S
				0	%				
				1	Nm				
20.9	2360	Torque lim Pos Inuse	A	FLOAT	16/32 0.0	0.0	0.0	ER	FVS
20.10	2362	Torque lim Neg Inuse	A	FLOAT	16/32 0.0	0.0	0.0	ER	FVS
20.11	2378	Torque ref 1 filter	ms	FLOAT	0.0	0.0	1000.0	ERW	F_S
20.12	2380	Dig torque ref 1	perc	FLOAT	16/32 0.0	-300.0	300.0	ERW	F_S
20.13	2382	Torque ref 1 src		LINK	16/32 3104	0	16384	ERWZ	F_S
				L_VREF					
20.14	2392	Torque ref 1 mon %	perc	FLOAT	16/32 0.0	0.0	0.0	ER	F_S
20.15	2346	Torque current ref 1	A	FLOAT	16/32 0.0	0.0	0.0	ER	F_S
20.16	2348	Torque ref 1 mon	Nm	FLOAT	0.0	0.0	0.0	ER	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
20.17	2384	Torque ref filter	ms	FLOAT		1.0	0.125	10.0	ERW	F_S
20.18	2386	Torque ref %	perc	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
20.19	2390	Torque ref	Nm	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
20.20	2394	Torque %	perc	FLOAT	16/32	0.0	0.0	0.0	ER	F_S
20.21	2398	Torque	Nm	FLOAT		0.0	0.0	0.0	ER	F_S
20.22	2366	Torque curr lim Red	A	FLOAT	16/32	CALCF	0.0	CALCF	ERWS	FVS
20.23	2368	Torque clim Red src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL2						
20.24	2340	Torque scale factor	perc	FLOAT		100.00	1.00	200.00	ERW	F_S

21 - VF PARAMETERS

21.1	2404	Voltage torque boost		ENUM		Disable	0	1	ERWZ	_V_
				0		Disable				
				1		Enable				
21.2	2406	Vf voltage	V	FLOAT		CALCF	10.0	690.0	ERWZS	_V_
21.3	2408	Vf frequency	Hz	FLOAT		CALCF	10.0	2000.0	ERWZS	_V_
21.4	2410	Vf voltage 1	V	FLOAT		CALCF	CALCF	CALCF	ERWZS	_V_
21.5	2412	Vf frequency 1	Hz	FLOAT		CALCF	0.0	CALCF	ERWZS	_V_
21.6	2414	Vf voltage 0	V	FLOAT		CALCF	0.0	CALCF	ERWZS	_V_
21.7	2430	Vf shape		ENUM		Linear	0	2	ERWZS	_V_
				0		Linear				
				1		Custom				
				2		Quadratic				
21.8	2440	Slip comp	Hz	FLOAT		CALCF	0.0	10.0	RWS	_V_
21.9	2442	Slip comp filter	ms	UINT16		200	50	5000	ERW	_V_
21.10	2444	Slip comp mode		ENUM		Open loop	0	1	ERWZ	_V_
				0		Open loop				
				1		Closed loop				
21.11	2446	Slip P gain	perc	FLOAT		1.0	0.0	100.0	ERWS	_V_
21.12	2448	Slip I gain	perc	FLOAT		1.5	0.0	100.0	ERWS	_V_
21.13	2460	Vfcurrent lim P gain	Hz/A	FLOAT		CALCF	0.0	1000.0	ERWS	_V_
21.14	2462	Vfcurrent lim I time	ms	FLOAT		CALCF	1.0	50.0	ERWS	_V_
21.15	2466	Instability comp en		ENUM		Disable	0	1	ERWZ	_V_
				0		Disable				
				1		Enable				
21.16	2468	Instability comp K	ohm	FLOAT		CALCF	0	200.0	ERWS	_V_
21.17	2480	Vf min frequency	Hz	FLOAT		1.0	0.2	5.0	ERW	_V_
21.18	2482	Vf min freq delay	ms	UINT16		800	0	5000	ERW	_V_
21.19	2490	Dig Vf scale		FLOAT	16/32	1.0	0.0	1.0	ERWZ	_V_
21.20	2492	Vf scale src		LINK	16/32	3374	0	16384	ERW	_V_
				L_VREF						

22 - FUNCTIONS

22.1 - FUNCTIONS/SPEED RATIO

22.1.1	3000	Dig speed ratio		INT16	16/32	100	CALCI	CALCI	ERW	FVS
22.1.2	3002	Speed ratio src		LINK	16/32	3000	0	16384	ERW	FVS
				L_VREF						
22.1.3	3008	Speed ratio div		ENUM		Div 1	0	3	ERW	FVS
				1		1				
				10		10				
				100		100				
				1000		1000				
22.1.4	3010	Speed ratio mon	perc	FLOAT		0	0	0	ER	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
22.2 - FUNCTIONS/DROOP									
22.2.1	3052	Droop ref src		LINK L_LIM	16/32 6000	0	16384	ERW	F_S
22.2.2	3060	Droop gain	perc	FLOAT	0.0	0.0	100.0	ERW	F_S
22.2.3	3062	Droop filter	ms	UINT16	10	1	100	ERW	F_S
22.2.4	3064	Droop limit	rpm	INT16	16/32 30	0	CALCI	ERWZ	F_S
22.2.5	3070	Droop out mon	rpm	INT16	16/32 0	0	0	ER	F_S

22.3 - FUNCTIONS/INERTIA COMP

22.3.1	3100	Inertia comp	kgm2	FLOAT	0.0	0.0	100.0	ERWS	F_S
22.3.2	3102	Inertia comp filter	ms	UINT16	30	1	100	ERW	F_S
22.3.3	3104	Inertia comp mon	perc	FLOAT	16/32 0.0	0.0	0.0	ER	F_S

22.4 - FUNCTIONS/DC BRAKING

22.4.1	3150	DC braking cmd src		LINK L_DIGSEL2	16 6000	0	16384	ERW	FVS
22.4.2	3152	DC brake mode		ENUM	Off	0	7	ERWZ	FVS
				0	Off				
				1	Stop				
				2	Cmd				
				3	Cmd&Stop				
				4	Start				
				5	Start&Stop				
				6	Cmd&Start				
				7	Cmd&Start&Stop				
22.4.3	3154	DC brake delay	s	FLOAT	0.5	0.00	30.0	ERW	FVS
22.4.4	3156	DC brake duration	s	FLOAT	1.0	0.01	30.0	ERW	FVS
22.4.5	3158	DC brake current	perc	FLOAT	50.0	0.0	150.0	ERW	FVS
22.4.6	3160	DC brake state		ENUM	16 Not active	0	1	ER	FVS
				0	Not active				
				1	Active				

22.5 - FUNCTIONS/AC BRAKING

22.5.1	2484	AC braking		ENUM	Disable	0	1	ERWZ	_V_
				0	Disable				
				1	Enable				
22.5.2	2486	AC brake Kp	V/A	FLOAT	CALCF	0.0	100.0	ERWS	_V_
22.5.3	2488	AC brake Ti	ms	FLOAT	CALCF	1.0	1000.0	ERWS	_V_
22.5.4	2478	AC brake active ref	perc	FLOAT	-2	-10	10	ERWS	_V_
22.5.5	2494	AC brake with UVRT		ENUM	Enable	0	1	ERW	_V_
				0	Disable				
				1	Enable				

22.6 - FUNCTIONS/MOTOR OVERLOAD

22.6.1	3200	Motor ovld enable		BIT	0	0	1	ERW	FVS
22.6.2	3202	Motor ovld factor	perc	FLOAT	150.0	100.0	300.0	ERWS	FVS
22.6.3	3204	Motor ovld time	s	FLOAT	30.0	10.0	300.0	ERWS	FVS
22.6.4	3206	Motor service factor	perc	FLOAT	100.0	25.0	200.0	ERWS	FVS
22.6.5	3216	Motor fan type		ENUM	Servo fan	0	1	ERW	FVS
				0	Auto fan				
				1	Servo fan				
22.6.6	3218	Motor derat factor	perc	FLOAT	50.0	0.0	100.0	ERWS	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
22.7 - FUNCTIONS/BRES OVERLOAD									
22.7.1	3250	Bres control		BIT	0	0	1	ERWZS	FVS
22.7.2	3252	Bres value	ohm	FLOAT	SIZE	3.0	1000.0	ERWS	FVS
22.7.3	3254	Bres cont power	kW	FLOAT	SIZE	0.1	100.0	ERWS	FVS
22.7.4	3256	Bres overload factor		FLOAT	SIZE	1.5	10.0	ERWS	FVS
22.7.5	3258	Bres overload time	s	FLOAT	SIZE	0.5	50.0	ERWS	FVS
22.7.6	3272	Bres enable src		LINK	16 6002	0	16384	ERW	FVS
				L_DIGSEL1					
22.7.7	3274	Bres enable inv		BIT	0	0	1	ERW	FVS

22.8 - FUNCTIONS/DOUBLE PAR SET

22.8.1	3300	Par set enable		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
22.8.2	3302	Par set select src		LINK	16 6000	0	16384	ERWZ	FVS
				L_DIGSEL2					
22.8.3	3304	Par set select mon		ENUM	16 Set 0	0	0	ER	FVS
				0	Set 0				
				1	Set 1				
22.8.4	3306	Par set 0 to 1 copy		BIT	0	0	1	ERW	FVS

22.9 - FUNCTIONS/SPEED CAPTURE

22.9.1	3350	Speed capture		ENUM	Disable	0	2	ERW	FV_
				0	Disable				
				1	Alarm restart				
				2	Enable&restart				
22.9.2	3364	Vf catch start freq	Hz	FLOAT	CALCF	-500.0	500.0	ERWZ	_V_
22.9.3	3366	Vf catch enable dly	ms	UINT16	CALCF	10	30000	ERWZ	_V_
22.9.4	3368	Vf catch reflux time	s	FLOAT	CALCF	0.1	100.0	ERW	_V_
22.9.5	3370	Vf catch Kp gain	Hz/A	FLOAT	CALCF	0.0	100.0	ERW	_V_
22.9.6	3372	Vf catch Ti time	ms	UINT16	CALCI	10	10000	ERW	_V_
22.9.7	3376	Vf catch lastref dly	ms	UINT16	0	0	30000	ERWZ	_V_
22.9.8	3388	Vf catch search volt	perc	UINT16	10	1	20	ERW	_V_
22.9.9	3390	Vf catch search curr	perc	FLOAT	0.6	-1.0	10.0	ERWS	_V_
22.9.10	3392	lactive filter	ms	FLOAT	20.0	1.0	150.0	ERWZ	_V_

22.10 - FUNCTIONS/POWER LOSS

22.10.1	3400	Powerloss function		ENUM	Disable	0	1	ERWZ	FV_
				0	Disable				
				1	Enable				
22.10.2	3402	Powerloss accel time	s	FLOAT	10.0	0.01	100.0	ERW	FV_
22.10.3	3404	Powerloss decel time	s	FLOAT	2.0	0.01	100.0	ERW	FV_
22.10.4	3410	Powerloss Vdcref	V	FLOAT	CALCF	0.0	CALCF	ERWZS	FV_
22.10.5	3420	Powerloss P gain	A/V	FLOAT	CALCF	0.0	100.000	ERWS	FV_
22.10.6	3422	Powerloss I time	ms	FLOAT	CALCF	1.0	1000.0	ERWS	FV_
22.10.7	3438	Powerloss mode		ENUM	Ramp down	0	1	ERWZ	FV_
				0	Ramp down				
				1	Restart				
22.10.8	3440	Powerloss mains src		LINK	16 6000	0	16384	ERWZ	FV_
				L_DIGSEL2					

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.11 - FUNCTIONS/UV RIDE THROUGH										
22.11.1	3280	UV RT enable		ENUM		Disable	0	1	ERW	_V_
				0		Disable				
				1		Enable				
22.11.2	3282	UV RT on	V	FLOAT		CALCF	0.0	0.0	ERWS	_V_
22.11.3	3284	UV RT off	V	FLOAT		CALCF	0.0	0.0	ERWS	_V_
22.11.4	3290	UV RT feed fwd		FLOAT		CALCF	0	20	ERW	_V_
22.11.5	3292	UV RT timeout	s	FLOAT		0	0.0	120	ERWS	_V_
22.11.6	3294	UV RT Kp	Hz/V	FLOAT		CALCF	0.0	0.0	ERWS	_V_
22.11.7	3296	UV RT Ti	ms	FLOAT		CALCF	0.0	0.0	ERWS	_V_
22.11.8	3276	UV RT ext restor src		LINK	16	6000	0	16384	ERWZ	_V_
				L_DIGSEL2						
22.11.9	3286	UV RT restore		ENUM		Disable	0	1	ERW	_V_
				0		Disable				
				1		Enable				
22.11.10	3288	UV RT ext restor dly	ms	UINT16		80	0	65535	ERW	_V_
22.11.11	3312	UV RT state		ENUM	16	Not active	0	1	ER	_V_
				0		Not active				
				1		Active				

22.12 - FUNCTIONS/COMPARE

22.12.1	3650	Dig compare input 1	perc	FLOAT	32	0.0	-100.0	100.0	ERW	FVS
22.12.2	3652	Dig compare input 2	perc	FLOAT	32	0.0	-100.0	100.0	ERW	FVS
22.12.3	3660	Compare input 1 src		LINK	32	3650	0	16384	ERW	FVS
				L_CMP						
22.12.4	3662	Compare input 2 src		LINK	32	3652	0	16384	ERW	FVS
				L_CMP						
22.12.5	3670	Compare function		ENUM		None	0	8	ERW	FVS
				0		None				
				1		Inp1=Inp2				
				2		Inp1!=Inp2				
				3		Inp1<Inp2				
				4		Inp1>Inp2				
				5		Inp1 = Inp2				
				6		Inp1 != Inp2				
				7		Inp1 < Inp2				
				8		Inp1 > Inp2				
22.12.6	3672	Compare window	perc	FLOAT		0.0	0.0	100.0	ERW	FVS
22.12.7	3674	Compare delay	s	FLOAT		0.0	0.0	30.0	ERW	FVS
22.12.8	3676	Compare output		BIT	16	0	0	1	ER	FVS

22.13 - FUNCTIONS/PADS

22.13.1	3700	Pad 1		INT32	32	0	0	0	ERW	FVS
22.13.2	3702	Pad 2		INT32	32	0	0	0	ERW	FVS
22.13.3	3704	Pad 3		INT32	32	0	0	0	ERW	FVS
22.13.4	3706	Pad 4		INT32	32	0	0	0	ERW	FVS
22.13.5	3708	Pad 5		INT32	32	0	0	0	ERW	FVS
22.13.6	3710	Pad 6		INT32	32	0	0	0	ERW	FVS
22.13.7	3712	Pad 7		INT32	32	0	0	0	ERW	FVS
22.13.8	3714	Pad 8		INT32	32	0	0	0	ERW	FVS
22.13.9	3716	Pad 9		INT32	32	0	0	0	ERW	FVS
22.13.10	3718	Pad 10		INT32	32	0	0	0	ERW	FVS
22.13.11	3720	Pad 11		INT32	32	0	0	0	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
22.13.12	3722	Pad 12		INT32	32	0	0	0	ERW	FVS
22.13.13	3724	Pad 13		INT32	32	0	0	0	ERW	FVS
22.13.14	3726	Pad 14		INT32	32	0	0	0	ERW	FVS
22.13.15	3728	Pad 15		INT32	32	0	0	0	ERW	FVS
22.13.16	3730	Pad 16		INT32	32	0	0	0	ERW	FVS

22.14 - FUNCTIONS/VDC CONTROL

22.14.1	3450	Vdc control function		ENUM		Disable	0	1	ERWZ	FVS
				0		Disable				
				1		Enable				
22.14.2	3470	Vdc control P gain	A/V	FLOAT		CALCF	0.0	100.000	ERWS	FVS
22.14.3	3472	Vdc control I time	ms	FLOAT		CALCF	1.0	1000.0	ERWS	FVS

22.15 - FUNCTIONS/BRAKE CONTROL

22.15.1	3170	Brake control funct		ENUM		Disable	0	3	ERWZ	FVS
				0		Disable				
				1		Standard				
				2		Hoist mode 1				
				3		Hoist mode 2				
22.15.2	3172	Brake open delay	s	FLOAT		0.20	0.0	60.0	ERW	FVS
22.15.3	3174	Brake close delay	s	FLOAT		0.20	0.0	60.0	ERW	FVS
22.15.4	3176	Brake open spd thr	rpm	INT16		0	0	CALCI	ERW	FVS
22.15.5	3178	Brake close spd thr	rpm	INT16		0	0	CALCI	ERW	FVS
22.15.6	3194	Brake ramp freeze		ENUM		Disable	0	1	ERWZ	FVS
				0		Disable				
				1		Enable				
22.15.7	3182	Brake open thr sel		ENUM		Output curr	0	1	ERWZ	FVS
				0		Torque ref%				
				1		Output curr				
22.15.8	3184	Brake open thr	perc	FLOAT		10	-200.0	200.0	ERWZS	FVS
22.15.9	3186	Brake open thr src		LINK	16/32	3184	0	16384	ERWZ	FVS
				L_TCREF						
22.15.10	3188	Brake torque time	s	FLOAT		0.10	0.01	60.0	ERWZ	FVS
22.15.11	3190	Brake close wait	s	FLOAT		2	0.0	60.0	ERW	FVS

22.16 - FUNCTIONS/DIMENSION FACT

22.16.1	3900	Dim factor num		UINT16		1	1	65535	ERW	FVS
22.16.2	3902	Dim factor den		UINT16		1	1	65535	ERW	FVS
22.16.3	3904	Dim factor text		UINT32		7172210	0	0	ERW	FVS

22.17 - FUNCTIONS/CONTROL MODE

22.17.1	556	Control mode select		ENUM		Ramp	0	2	ERWZ	F_S
				0		Torque				
				1		Speed				
				2		Ramp				
22.17.2	6200	Ctrl mode src		LINK	16	556	0	16384	ERWZ	F_S
				L_CTRLMODE						
22.17.3	6202	Ctrl mode sel 0 src		LINK	16	6000	0	16384	ERWZ	F_S
				L_DIGSEL2						
22.17.4	6204	Ctrl mode sel 1 src		LINK	16	6000	0	16384	ERWZ	F_S
				L_DIGSEL2						
22.17.5	6206	Ctrl mode sel mon		UINT32		0	0	3	ER	F_S
22.17.6	6208	Ctrl mode mon		ENUM		Torque	0	0	ER	F_S

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				0	Torque				
				1	Speed				
				2	Ramp				

22.18 - FUNCTIONS/TEMP CONTROL

22.18.1	3500	Drv temp src		LINK	32	6000	0	16384	ERW	FVS
				L_TEMPCTRL						
22.18.2	3504	Drv temp thr	degC	INT32		45	1	100	ERW	FVS
22.18.3	3508	Drv temp hys	degC	INT32		2	0	CALCI	ERW	FVS
22.18.4	3502	Mot temp src		LINK	32	6000	0	16384	ERW	FVS
				L_TEMPCTRL						
22.18.5	3506	Mot temp thr	degC	INT32		45	1	100	ERW	FVS
22.18.6	3510	Mot temp hys	degC	INT32		2	0	CALCI	ERW	FVS

22.19 - FUNCTIONS/LC CONTROL

22.19.1	6020	Air humidity	perc	FLOAT		0.0	0.0	0.0	ER	FVS
22.19.2	6022	Air temperature	degC	FLOAT		0.0	0.0	0.0	ER	FVS
22.19.3	6032	Dew temperature	degC	INT16		0	0	0	ER	FVS
22.19.4	6034	Dew temp offset off	degC	INT16		8	3	50	ERW	FVS
22.19.5	6048	Dew temp offset on	degC	INT16		3	2	50	ERW	FVS
22.19.6	6036	Liquid temp setpoint	degC	INT16		0	0	0	ER	FVS
22.19.7	6038	Intake liquid temp	degC	INT16		0	0	0	ER	FVS
22.19.8	6040	Liquid temp src		LINK	32	6038	0	16384	ERW	FVS
				L_TEMPCTRL						
22.19.9	6042	Liquid temp mon	degC	INT16		0	0	0	ER	FVS

22.20 - FUNCTIONS/TIMERS

22.20.1	3550	Timer1 src		LINK	32	6000	0	16384	ERW	FVS
				L_DIGSEL1						
22.20.2	3552	Timer1 pos delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS
22.20.3	3554	Timer1 neg delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS
22.20.4	3556	Timer1 mon		INT32		0	0	0	ER	FVS
22.20.5	3560	Timer2 src		LINK	32	6000	0	16384	ERW	FVS
				L_DIGSEL1						
22.20.6	3562	Timer2 pos delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS
22.20.7	3564	Timer2 neg delay	s	FLOAT		0.10	0.0	30.0	ERW	FVS
22.20.8	3566	Timer2 mon		INT32		0	0	0	ER	FVS

22.21 - FUNCTIONS/TORQUE LIMADAPT

22.21.1	2330	Torque limit high	perc	FLOAT		100.0	0.0	CALCF	ERW	F_S
22.21.2	2332	Torque limit low	perc	FLOAT		70.0	0.0	CALCF	ERW	F_S
22.21.3	2334	Torque limit ramp	ms	UINT16		1000	0	60000	ERW	F_S
22.21.4	2336	Torque limit sel src		LINK	16/32	976	0	16384	ERW	F_S
22.21.5	2338	Torque limit adapt	perc	FLOAT		0.0	0.0	0.0	ER	F_S

23 - COMMUNICATION

23.1 - COMMUNICATION/RS485

23.1.1	3800	Drive address		UINT16		1	1	255	ERW	FVS
23.1.2	3802	Serial baudrate		ENUM		38400	0	2	ERW	FVS
				0		9600				
				1		19200				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				2	38400				
23.1.3	3810	Serial parameter		ENUM	N_8_1	0	3	ERW	FVS
				0	None,8,1				
				1	None,8,2				
				2	Even,8,1				
				3	Odd,8,1				
23.1.4	3804	Serial protocol		ENUM	Modbus	0	1	ERW	FVS
				0	Modbus				
				1	Jbus				
23.1.5	3806	Serial delay	ms	UINT16	0	0	1000	ERW	FVS
23.1.6	3808	Serial swap data		BIT	0	0	1	ERW	FVS

23.2 - COMMUNICATION/FIELDBUS CONFIG

23.2.1	4000	Fieldbus type		ENUM	Off	0	6	RW	FVS
				0	Off				
				1	CanOpen				
				2	DeviceNet				
				3	Profibus				
				10	DS402				
				30	Profidrive				
				40	Rte				
23.2.2	4004	Fieldbus baudrate		ENUM	500k	0	12	RW	FVS
				0	Auto				
				1	125k				
				2	250k				
				3	500k				
				4	1M				
				5	9600				
				6	19200				
				7	93750				
				8	187,5k				
				9	1,5M				
				10	3M				
				11	6M				
				12	12M				
23.2.3	4006	Fieldbus address		INT16	3	0	255	RW	FVS
23.2.4	4010	Fieldbus M->S enable		ENUM	Enable	0	1	ERWZ	FVS
				0	Disable				
				1	Enable				
23.2.5	4012	Fieldbus alarm mode		INT32	0	0	1	ERWZ	FVS
23.2.6	4014	Fieldbus state		ENUM	Stop	0	9	R	FVS
				0	Stop				
				1	PreOperational				
				2	Operational				
				3	Error				
				4	WaitPRM				
				5	WaitCFG				
				6	DataExchange				
				7	DPError				
				8	SafeOp				
				9	Init				
23.2.7	4398	RTE protocol		ENUM	None	0	0	ER	FVS
				0	None				
				1	Ethercat				
				2	EthernetIP				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				3	GdNet				
				4	Profinet				
				5	ModbusTCP				
				6	Powerlink				
				107	Profidrive				
23.2.8	5608	IP address		UINT32	0	0	4294967295	ER	FVS

23.3 - COMMUNICATION/FIELDBUS M->S

23.3.1	4020	Fieldbus M->S1 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.2	4022	Fieldbus M->S1 sys		ENUM	Not assigned	0	10	RW	FVS
			0	Not assigned					
			1	Count 16					
			2	Count 32					
			3	Fill 16					
			4	Fill 32					
			5	Mdplc 16					
			6	Mdplc 32					
			7	Eu					
			8	Eu float					
			9	Par 16					
			10	Par 32					
23.3.3	4024	Fieldbus M->S1 mon		INT32	16 0	0	0	ERW	FVS
23.3.4	4026	Fieldbus M->S1 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.5	4030	Fieldbus M->S2 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.6	4032	Fieldbus M->S2 sys		ENUM	Not assigned	0	10	RW	FVS
			0	Not assigned					
			1	Count 16					
			2	Count 32					
			3	Fill 16					
			4	Fill 32					
			5	Mdplc 16					
			6	Mdplc 32					
			7	Eu					
			8	Eu float					
			9	Par 16					
			10	Par 32					
23.3.7	4034	Fieldbus M->S2 mon		INT32	16 0	0	0	ERW	FVS
23.3.8	4036	Fieldbus M->S2 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.9	4040	Fieldbus M->S3 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.10	4042	Fieldbus M->S3 sys		ENUM	Not assigned	0	10	RW	FVS
			0	Not assigned					
			1	Count 16					
			2	Count 32					
			3	Fill 16					
			4	Fill 32					
			5	Mdplc 16					
			6	Mdplc 32					
			7	Eu					
			8	Eu float					
			9	Par 16					
			10	Par 32					
23.3.11	4044	Fieldbus M->S3 mon		INT32	16 0	0	0	ERW	FVS
23.3.12	4046	Fieldbus M->S3 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.13	4050	Fieldbus M->S4 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.14	4052	Fieldbus M->S4 sys		ENUM	Not assigned	0	10	RW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.15	4054	Fieldbus M->S4 mon		INT32	16 0	0	0	ERW	FVS
23.3.16	4056	Fieldbus M->S4 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.17	4060	Fieldbus M->S5 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.18	4062	Fieldbus M->S5 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.19	4064	Fieldbus M->S5 mon		INT32	16 0	0	0	ERW	FVS
23.3.20	4066	Fieldbus M->S5 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.21	4070	Fieldbus M->S6 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.22	4072	Fieldbus M->S6 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.23	4074	Fieldbus M->S6 mon		INT32	16 0	0	0	ERW	FVS
23.3.24	4076	Fieldbus M->S6 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.25	4080	Fieldbus M->S7 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.26	4082	Fieldbus M->S7 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				

Menu	PAR	Description	UM	Type	FB BIT Def		Min	Max	Acc	Mod
				10	Par 32					
23.3.27	4084	Fieldbus M->S7 mon		INT32	16	0	0	0	ERW	FVS
23.3.28	4086	Fieldbus M->S7 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.29	4090	Fieldbus M->S8 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.30	4092	Fieldbus M->S8 sys		ENUM		Not assigned	0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					
				5	Mdplc 16					
				6	Mdplc 32					
				7	Eu					
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.3.31	4094	Fieldbus M->S8 mon		INT32	16	0	0	0	ERW	FVS
23.3.32	4096	Fieldbus M->S8 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.33	4100	Fieldbus M->S9 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.34	4102	Fieldbus M->S9 sys		ENUM		Not assigned	0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					
				5	Mdplc 16					
				6	Mdplc 32					
				7	Eu					
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.3.35	4104	Fieldbus M->S9 mon		INT32	16	0	0	0	ERW	FVS
23.3.36	4106	Fieldbus M->S9 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.37	4110	Fieldbus M->S10 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.38	4112	Fieldbus M->S10 sys		ENUM		Not assigned	0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					
				5	Mdplc 16					
				6	Mdplc 32					
				7	Eu					
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.3.39	4114	Fieldbus M->S10 mon		INT32	16	0	0	0	ERW	FVS
23.3.40	4116	Fieldbus M->S10 div		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.3.41	4120	Fieldbus M->S11 ipa		FBM2SIPA		0	0	20000	RW	FVS
23.3.42	4122	Fieldbus M->S11 sys		ENUM		Not assigned	0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.43	4124	Fieldbus M->S11 mon		INT32	16 0	0	0	ERW	FVS
23.3.44	4126	Fieldbus M->S11 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.45	4130	Fieldbus M->S12 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.46	4132	Fieldbus M->S12 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.47	4134	Fieldbus M->S12 mon		INT32	16 0	0	0	ERW	FVS
23.3.48	4136	Fieldbus M->S12 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.49	4140	Fieldbus M->S13 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.50	4142	Fieldbus M->S13 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.51	4144	Fieldbus M->S13 mon		INT32	16 0	0	0	ERW	FVS
23.3.52	4146	Fieldbus M->S13 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.53	4150	Fieldbus M->S14 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.54	4152	Fieldbus M->S14 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.55	4154	Fieldbus M->S14 mon		INT32	16 0	0	0	ERW	FVS
23.3.56	4156	Fieldbus M->S14 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.57	4160	Fieldbus M->S15 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.58	4162	Fieldbus M->S15 sys		ENUM	Not assigned	0	10	RW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.59	4164	Fieldbus M->S15 mon		INT32	16 0	0	0	ERW	FVS
23.3.60	4166	Fieldbus M->S15 div		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.3.61	4170	Fieldbus M->S16 ipa		FBM2SIPA	0	0	20000	RW	FVS
23.3.62	4172	Fieldbus M->S16 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.3.63	4174	Fieldbus M->S16 mon		INT32	16 0	0	0	ERW	FVS
23.3.64	4176	Fieldbus M->S16 div		FLOAT	1.0	1.0	1000.0	ERW	FVS

23.4 - COMMUNICATION/FIELDBUS S->M

23.4.1	4180	Fieldbus S->M1 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.2	4182	Fieldbus S->M1 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.3	4184	Dig Fieldbus S->M1		INT32	16 0	0	0	ERW	FVS
23.4.4	4186	Fieldbus S->M1 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.5	4190	Fieldbus S->M2 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.6	4192	Fieldbus S->M2 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.7	4194	Dig Fieldbus S->M2		INT32	16 0	0	0	ERW	FVS
23.4.8	4196	Fieldbus S->M2 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.9	4200	Fieldbus S->M3 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.10	4202	Fieldbus S->M3 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.11	4204	Dig Fieldbus S->M3		INT32	16 0	0	0	ERW	FVS
23.4.12	4206	Fieldbus S->M3 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.13	4210	Fieldbus S->M4 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.14	4212	Fieldbus S->M4 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.15	4214	Dig Fieldbus S->M4		INT32	16 0	0	0	ERW	FVS
23.4.16	4216	Fieldbus S->M4 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.17	4220	Fieldbus S->M5 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.18	4222	Fieldbus S->M5 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.19	4224	Dig Fieldbus S->M5		INT32	16 0	0	0	ERW	FVS
23.4.20	4226	Fieldbus S->M5 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.21	4230	Fieldbus S->M6 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.22	4232	Fieldbus S->M6 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.23	4234	Dig Fieldbus S->M6		INT32	16 0	0	0	ERW	FVS
23.4.24	4236	Fieldbus S->M6 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.25	4240	Fieldbus S->M7 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.26	4242	Fieldbus S->M7 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.27	4244	Dig Fieldbus S->M7		INT32	16 0	0	0	ERW	FVS
23.4.28	4246	Fieldbus S->M7 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.29	4250	Fieldbus S->M8 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.30	4252	Fieldbus S->M8 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.31	4254	Dig Fieldbus S->M8		INT32	16 0	0	0	ERW	FVS
23.4.32	4256	Fieldbus S->M8 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.33	4260	Fieldbus S->M9 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.34	4262	Fieldbus S->M9 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.35	4264	Dig Fieldbus S->M9		INT32	16 0	0	0	ERW	FVS
23.4.36	4266	Fieldbus S->M9 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
23.4.37	4270	Fieldbus S->M10 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.38	4272	Fieldbus S->M10 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.39	4274	Dig Fieldbus S->M10		INT32	16 0	0	0	ERW	FVS
23.4.40	4276	Fieldbus S->M10 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.41	4280	Fieldbus S->M11 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.42	4282	Fieldbus S->M11 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.43	4284	Dig Fieldbus S->M11		INT32	16 0	0	0	ERW	FVS
23.4.44	4286	Fieldbus S->M11 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.45	4290	Fieldbus S->M12 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.46	4292	Fieldbus S->M12 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				
				8	Eu float				
				9	Par 16				
				10	Par 32				
23.4.47	4294	Dig Fieldbus S->M12		INT32	16 0	0	0	ERW	FVS
23.4.48	4296	Fieldbus S->M12 mul		FLOAT	1.0	1.0	1000.0	ERW	FVS
23.4.49	4300	Fieldbus S->M13 ipa		FBS2MIPA	0	0	20000	RW	FVS
23.4.50	4302	Fieldbus S->M13 sys		ENUM	Not assigned	0	10	RW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
				3	Fill 16				
				4	Fill 32				
				5	Mdplc 16				
				6	Mdplc 32				
				7	Eu				

Menu	PAR	Description	UM	Type	FB BIT Def		Min	Max	Acc	Mod
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.4.51	4304	Dig Fieldbus S->M13		INT32	16	0	0	0	ERW	FVS
23.4.52	4306	Fieldbus S->M13 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.53	4310	Fieldbus S->M14 ipa		FBS2MIPA		0	0	20000	RW	FVS
23.4.54	4312	Fieldbus S->M14 sys		ENUM	Not assigned		0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					
				5	Mdplc 16					
				6	Mdplc 32					
				7	Eu					
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.4.55	4314	Dig Fieldbus S->M14		INT32	16	0	0	0	ERW	FVS
23.4.56	4316	Fieldbus S->M14 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.57	4320	Fieldbus S->M15 ipa		FBS2MIPA		0	0	20000	RW	FVS
23.4.58	4322	Fieldbus S->M15 sys		ENUM	Not assigned		0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					
				5	Mdplc 16					
				6	Mdplc 32					
				7	Eu					
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.4.59	4324	Dig Fieldbus S->M15		INT32	16	0	0	0	ERW	FVS
23.4.60	4326	Fieldbus S->M15 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS
23.4.61	4330	Fieldbus S->M16 ipa		FBS2MIPA		0	0	20000	RW	FVS
23.4.62	4332	Fieldbus S->M16 sys		ENUM	Not assigned		0	10	RW	FVS
				0	Not assigned					
				1	Count 16					
				2	Count 32					
				3	Fill 16					
				4	Fill 32					
				5	Mdplc 16					
				6	Mdplc 32					
				7	Eu					
				8	Eu float					
				9	Par 16					
				10	Par 32					
23.4.63	4334	Dig Fieldbus S->M16		INT32	16	0	0	0	ERW	FVS
23.4.64	4336	Fieldbus S->M16 mul		FLOAT		1.0	1.0	1000.0	ERW	FVS

23.5 - COMMUNICATION/WORD COMP

23.5.1	4400	Word bit0 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.2	4402	Word bit1 src		LINK	16	6000	0	16384	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
				L_DIGSEL1						
23.5.3	4404	Word bit2 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.4	4406	Word bit3 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.5	4408	Word bit4 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.6	4410	Word bit5 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.7	4412	Word bit6 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.8	4414	Word bit7 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.9	4416	Word bit8 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.10	4418	Word bit9 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.11	4420	Word bit10 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.12	4422	Word bit11 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.13	4424	Word bit12 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.14	4426	Word bit13 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.15	4428	Word bit14 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.16	4430	Word bit15 src		LINK	16	6000	0	16384	ERW	FVS
				L_DIGSEL1						
23.5.17	4432	Word comp mon		UINT32	16	0	0	0	ER	FVS

23.6 - COMMUNICATION/WORD DECOMP

23.6.1	4450	Dig word decomp		UINT32	16	0	0	0	ERW	FVS
23.6.2	4452	Word decomp src		LINK	16	4450	0	16384	ERW	FVS
				L_WDECOMP						
23.6.3	4454	Bit0 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.4	4456	Bit1 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.5	4458	Bit2 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.6	4460	Bit3 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.7	4462	Bit4 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.8	4464	Bit5 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.9	4466	Bit6 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.10	4468	Bit7 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.11	4470	Bit8 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.12	4472	Bit9 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.13	4474	Bit10 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.14	4476	Bit11 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.15	4478	Bit12 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.16	4480	Bit13 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.17	4482	Bit14 decomp mon		BIT	16	0	0	1	ER	FVS
23.6.18	4484	Bit15 decomp mon		BIT	16	0	0	1	ER	FVS

23.7 - COMMUNICATION/EXTERNAL IO

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
23.7.1	5480	External IO enable		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
23.7.2	5482	External IO info		UINT32	0	0	4294967295	ER	FVS
23.7.3	5484	External IO state		BIT	16 0	0	1	ER	FVS
23.7.4	5486	External IO failcode		UINT32	0	0	4294967295	ER	FVS

23.8 - COMMUNICATION/FAST LINK

23.8.1	5702	FL address		UINT16	0	0	16	ERWZ	FVS
23.8.2	5818	FL bidirectional		ENUM	Enable	0	1	ERWZ	FVS
				0	Disable				
				1	Enable				
23.8.3	5820	FL N of slave		UINT16	0	0	32767	ERWZ	FVS
23.8.4	5710	FL sync slave type		ENUM	Pwm&Ctrl	0	2	ERWZ	FVS
				0	Off				
				1	Pwm				
				2	Pwm&Ctrl				
23.8.5	5712	FL N Fwd slave chg		UINT16	0	0	4	ERWZ	FVS
23.8.6	5714	FL fault enable src		LINK	16 6002	0	16384	ERW	FVS
				L_DIGSEL1					
23.8.7	5730	FL Fwd 1 src		LINK	16/32 6000	0	16384	ERW	FVS
				L_FLWORD					
23.8.8	5732	FL Fwd 2 src		LINK	16/32 6000	0	16384	ERW	FVS
				L_FLWORD					
23.8.9	5734	FL Fwd 3 src		LINK	16/32 6000	0	16384	ERW	FVS
				L_FLWORD					
23.8.10	5736	FL Fwd 4 src		LINK	16/32 6000	0	16384	ERW	FVS
				L_FLWORD					
23.8.11	5830	FL Rev 1 src		LINK	16/32 6000	0	16384	ERW	FVS
				L_FLWORD					
23.8.12	5832	FL Rev 2 src		LINK	16/32 6000	0	16384	ERW	FVS
				L_FLWORD					
23.8.13	5750	FL Fwd 1 mon		INT32	32 0	0	0	ER	FVS
23.8.14	5752	FL Fwd 2 mon		INT32	32 0	0	0	ER	FVS
23.8.15	5754	FL Fwd 3 mon		INT32	32 0	0	0	ER	FVS
23.8.16	5756	FL Fwd 4 mon		INT32	32 0	0	0	ER	FVS
23.8.17	5758	FL Fwd 5 mon		INT32	32 0	0	0	ER	FVS
23.8.18	5760	FL Fwd 6 mon		INT32	32 0	0	0	ER	FVS
23.8.19	5762	FL Fwd 7 mon		INT32	32 0	0	0	ER	FVS
23.8.20	5764	FL Fwd 8 mon		INT32	32 0	0	0	ER	FVS
23.8.21	5850	FL Rev 1 mon		INT32	32 0	0	0	ER	FVS
23.8.22	5852	FL Rev 2 mon		INT32	32 0	0	0	ER	FVS
23.8.23	5854	FL Rev 3 mon		INT32	32 0	0	0	ER	FVS
23.8.24	5856	FL Rev 4 mon		INT32	32 0	0	0	ER	FVS
23.8.25	5822	FL Rev 1 slave sel		UINT16	0	0	31	ERWZ	FVS
23.8.26	5824	FL Rev 2 slave sel		UINT16	0	0	31	ERWZ	FVS
23.8.27	5826	FL Rev 3 slave sel		UINT16	0	0	31	ERWZ	FVS
23.8.28	5828	FL Rev 4 slave sel		UINT16	0	0	31	ERWZ	FVS
23.8.29	5720	Sync slave mon		BIT	16 0	0	1	ER	FVS
23.8.30	5722	FL fault code		UINT32	0	0	0	ER	FVS

24 - ALARM CONFIG

24.1	4500	Fault reset src		LINK	16 1120	0	16384	RW	FVS
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Menu	PAR	Description	UM	Type	FB BIT	Def	Min	Max	Acc	Mod
				L_DIGSEL2						
24.2	4502	ExtFlt src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
24.3	4504	ExtFlt activity		ENUM		Disable	0	4	RW	FVS
				0	Ignore					
				1	Warning					
				2	Disable					
				3	Stop					
				4	Fast stop					
24.4	4506	ExtFlt restart		ENUM		Disable	0	1	RW	FVS
				0	Disable					
				1	Enable					
24.5	4508	ExtFlt restart time	ms	UINT16		1000	120	30000	RW	FVS
24.6	4510	ExtFlt holdoff	ms	UINT16		0	0	10000	RW	FVS
24.7	4516	MotorOT pre activity		ENUM		Ignore	0	4	ERW	FVS
				0	Ignore					
				1	Warning					
				2	Disable					
				3	Stop					
				4	Fast stop					
24.8	4518	MotorOT pre thr	perc	UINT16		60	0	100	ERW	FVS
24.9	4520	MotorOT src		LINK	16	6000	0	16384	RW	FVS
				L_DIGSEL2						
24.10	4522	MotorOT activity		ENUM		Warning	0	4	RW	FVS
				0	Ignore					
				1	Warning					
				2	Disable					
				3	Stop					
				4	Fast stop					
24.11	4524	MotorOT restart		ENUM		Disable	0	1	RW	FVS
				0	Disable					
				1	Enable					
24.12	4526	MotorOT restart time	ms	UINT16		1000	120	30000	RW	FVS
24.13	4528	MotorOT holdoff	ms	UINT16		1000	0	30000	RW	FVS
24.14	4530	MotorOT probe		ENUM		SRC	0	13	ERW	FVS
				0	SRC					
				1	Sens An1X					
				2	Sens An2X					
				3	KTY84 AnX					
				4	PTC AnX					
				5	KTY84 An1					
				6	KTY84 An2					
				7	PTC An1					
				8	PTC An2					
				9	Klixon AnX					
				10	KTY84 An1X					
				11	KTY84 An2X					
				12	PTC An1X					
				13	PTC An2X					
24.15	4514	MotorOT KTY84 unit		ENUM		ohm	0	1	ERW	FVS
				0	ohm					
				1	°C					
24.16	4532	MotorOT thr	cnt	UINT16		0	0	32767	ERW	FVS
24.17	4536	MotorOT mon	cnt	INT16	16/32	0	0	32767	ER	FVS
24.18	4540	Overspeed threshold	rpm	INT32		CALCI	0	CALCI	RW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
24.19	4542	Overspeed activity		ENUM	Disable	0	4	RW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.20	4544	Overspeed holdoff	ms	UINT16	0	0	5000	RW	FVS
24.21	4550	SpdRefLoss threshold	rpm	INT16	100	0	CALCI	RW	FVS
24.22	4552	SpdRefLoss activity		ENUM	Ignore	0	4	RW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.23	4554	SpdRefLoss holdoff	ms	UINT16	1000	0	10000	RW	FVS
24.24	4558	SpdRefLoss minThr en		BIT	0	0	1	ERW	FVS
24.25	4560	SpdFbkLoss activity		ENUM	Disable	0	4	RW	FV_
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.26	4562	SpdFbkLoss holdoff	ms	UINT16	200	0	10000	RW	FV_
24.27	4564	SpdFbkLoss threshold	rpm	INT16	100	5	CALCI	RW	FV_
24.28	4570	Drive ovld activity		ENUM	Ignore	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.29	4572	Motor ovld activity		ENUM	Warning	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.30	4574	Bres ovld activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.31	4582	HTsens restart		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
24.32	4584	HTsens restart time	ms	UINT16	20000	120	60000	ERW	FVS
24.33	4600	InAir activity		ENUM	Stop	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.34	4602	InAir restart		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
24.35	4604	InAir restart time	ms	UINT16	1000	120	30000	ERW	FVS
24.36	4606	InAir holdoff	ms	UINT16	10000	1000	30000	ERW	FVS
24.37	4610	Desat restart		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
24.38	4612	Desat restart time	ms	UINT16	2000	1000	10000	ERW	FVS
24.39	4620	IOVerC restart		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
24.40	4622	IOVerC restart time	ms	UINT16	2000	1000	10000	ERW	FVS
24.41	4630	OverV restart		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
24.42	4632	OverV restart time	ms	UINT16	2000	1000	10000	ERW	FVS
24.43	4640	UnderV restart		ENUM	Enable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
24.44	4642	UnderV restart time	ms	UINT16	1000	120	10000	ERW	FVS
24.45	4650	UVRep attempts		UINT16	5	0	1000	ERW	FVS
24.46	4652	UVRep delay	s	UINT16	240	0	300	ERW	FVS
24.47	4660	PhLoss activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.48	4662	PhLoss restart		ENUM	Disable	0	1	ERW	FVS
				0	Disable				
				1	Enable				
24.49	4664	PhLoss restart time	ms	UINT16	1000	120	10000	ERW	FVS
24.50	4670	Optionbus activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.51	4672	Optbus fault en src		LINK	16 6002	0	16384	ERW	FVS
				L_DIGSEL1					
24.52	4680	GroundFault thr	perc	FLOAT	10.0	0.0	150.0	ERWS	FVS
24.53	4684	Brake fault activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.54	4690	ExtIO activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.55	4940	FL fault activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				2	Disable				
				3	Stop				
				4	Fast stop				
24.56	4654	Mot PhLoss activity		ENUM	Ignore	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.57	4656	Mot PhLoss holdoff	ms	UINT16	800	400	10000	ERW	FVS
24.58	4658	Mot PhLoss threshold	A	FLOAT	0.40	0	CALCF	ERW	FVS
24.59	4674	Mot PhLoss speed thr	rpm	INT16	30	10	32000	ERW	FVS
24.60	4678	Mot PhLoss code		UINT32	0	0	0	ER	FVS
24.61	4590	Condensat activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.62	4592	Condensat holdoff	s	UINT16	30	0	500	ERW	FVS
24.63	4576	Condensation delay	s	UINT16	5	0	50	ERW	FVS
24.64	4596	Overhumidity thr	perc	FLOAT	85.0	0.0	100	ERW	FVS
24.65	4578	Overhumidity delay	s	UINT16	5	0	50	ERW	FVS
24.66	4598	HumTSensErr code		UINT32	0	0	0	ER	FVS
24.67	4546	An inpLoss activity		ENUM	Warning	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
24.68	4548	An inpLoss holdoff	ms	UINT16	1000	0	30000	ERW	FVS
24.69	4568	An inpLoss code		UINT32	0	0	0	ER	FVS
24.70	4700	Alarm dig sel 1		ENUM	No alarm	0	63	ERW	FVS
24.71	4702	Alarm dig sel 2		ENUM	No alarm	0	63	ERW	FVS
24.72	4704	Alarm dig sel 3		ENUM	No alarm	0	63	ERW	FVS
24.73	4706	Alarm dig sel 4		ENUM	No alarm	0	63	ERW	FVS
				0	No alarm				
				1	Overvoltage				
				2	Undervoltage				
				3	Ground fault				
				4	Overcurrent				
				5	Desaturation				
				6	MultiUndervolt				
				7	MultiOvercurr				
				8	MultiDesat				
				9	Heatsink OT				
				10	HeatsinkS OTUT				
				11	Intakeair OT				
				12	Motor OT				
				13	Drive overload				
				14	Motor overload				
				15	Bres overload				
				16	Phaseloss				
				17	Opt Bus fault				
				18	Opt 1 IO fault				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
				19	Opt 2 IO fault				
				20	Opt Enc fault				
				21	External fault				
				22	Speed fbk loss				
				23	Overspeed				
				24	Speed ref loss				
				25	Emg stop alarm				
				26	Power down				
				27	ExtIO fault				
				28	FastLink fault				
				29	Brake fault				
				30	Motor pre OT				
				31	Mot phase loss				
				32	Condensation				
				33	Plc1 fault				
				34	Plc2 fault				
				35	Plc3 fault				
				36	Plc4 fault				
				37	Plc5 fault				
				38	Plc6 fault				
				39	Plc7 fault				
				40	Plc8 fault				
				41	Watchdog				
				42	Trap error				
				43	System error				
				44	User error				
				45	Param error				
				46	Load def par				
				47	Plc cfg error				
				48	Load def plc				
				49	Key failed				
				50	Encoder error				
				51	Opt cfg change				
				52	HumTempSensErr				
				53	Plc9 fault				
				54	Plc10 fault				
				55	Plc11 fault				
				56	Plc12 fault				
				57	Plc13 fault				
				58	Plc14 fault				
				59	Plc15 fault				
				60	Plc16 fault				
				61	UV Wng&Restart				
				62	An inpLoss				
				63	UV Ride Thr				
24.74	4720	Alm autoreset time	s	FLOAT	0.0	0.0	60.0	ERW	FVS
24.75	4722	Alm autoreset number		UINT16	20	0	100	ERW	FVS

25 - ALARM LOG

26 - APPLICATION

27 - SERVICE

27.1 - SERVICE/TEST GENERATOR

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
27.1.1	5000	Test gen dest		ENUM	Off	0	4	ERWZ	FVS
				0	Off				
				1	Ramp ref 1				
				2	Speed ref 1				
				3	Torque ref 1				
				4	Current ref				
27.1.2	5002	Test gen level high	perc	INT16	0	-200	200	ERW	FVS
27.1.3	5004	Test gen level low	perc	INT16	0	-200	200	ERW	FVS
27.1.4	5006	Test gen period	s	FLOAT	1.0	0.01	10.0	ERW	FVS
27.1.5	5008	Test gen out	perc	INT16	16/32 0	0	0	ER	FVS

27.2 - SERVICE/PARAM ADAPT

27.2.1	180	Adapt Rr P gain	perc	FLOAT	1.0	0.01	10.0	ERWS	F__
27.2.2	182	Adapt Rr I time	s	FLOAT	1.0	0.1	10.0	ERWS	F__
27.2.3	184	Adapt Rrlq threshold	A	FLOAT	CALCF	0.0	0.0	ERWZS	F__
27.2.4	170	Adapt Rs P gain	perc	FLOAT	2.0	0.01	10.0	ERWS	__S
27.2.5	172	Adapt Rs I time	s	FLOAT	0.5	0.1	10.0	ERWS	__S
27.2.6	174	Adapt Rslq threshold	A	FLOAT	CALCF	0.0	0.0	ERWZS	__S
27.2.7	2520	Motor coef alfa		FLOAT	0.00426	0.0	2.0	ERW	__S

27.3 - SERVICE/POSITION

27.3.1	2152	E1 Virtual pulses		UINT32	CALCI	0	0	ERW	FVS
27.3.2	2154	E1 Virtual position	cnt	UINT32	32 0	0	0	ER	FVS
27.3.3	2156	E1 Revolutions		INT32	32 0	0	0	ER	FVS
27.3.4	2168	E1 Abs pulses		UINT32	CALCI	0	0	ER	FVS
27.3.5	2164	E1 Abs position	cnt	UINT32	32 0	0	0	ER	FVS
27.3.6	2166	E1 Abs revolutions		UINT32	32 0	0	0	ER	FVS
27.3.7	5152	E2 Virtual pulses		UINT32	CALCI	0	0	ERW	FVS
27.3.8	5154	E2 Virtual position	cnt	UINT32	32 0	0	0	ER	FVS
27.3.9	5156	E2 Revolutions		INT32	32 0	0	0	ER	FVS
27.3.10	5168	E2 Abs pulses		UINT32	CALCI	0	0	ER	FVS
27.3.11	5164	E2 Abs position	cnt	UINT32	32 0	0	0	ER	FVS
27.3.12	5166	E2 Abs revolutions		UINT32	32 0	0	0	ER	FVS
27.3.13	5252	E3 Virtual pulses		UINT32	CALCI	0	0	ERW	FVS
27.3.14	5254	E3 Virtual position	cnt	UINT32	32 0	0	0	ER	FVS
27.3.15	5256	E3 Revolutions		INT32	32 0	0	0	ER	FVS
27.3.16	2126	Resolver OVR thr	V	FLOAT	4.820	0.000	4.820	ERWZ	FVS
27.3.17	2136	Resolver MIS maxThr	V	FLOAT	2.280	0.000	4.820	ERWZ	FVS
27.3.18	2138	Resolver MIS minThr	V	FLOAT	3.990	0.000	4.820	ERWZ	FVS
27.3.19	2140	Resolver LOT thr	deg	FLOAT	4	0	9	ERWZ	FVS
27.3.20	2142	Resolver LOT hys	deg	FLOAT	0.5	0	9	ERWZ	FVS
27.3.21	2144	Resolver get reg		UINT16	0	0	0	ERWZ	FVS
27.3.22	2146	Resolver reg mon		UINT16	0	0	0	ERZ	FVS
27.3.23	2086	Resolver resolution		ENUM	16	2	3	ERWZ	FVS
				2	14 bit				
				3	16 bit				
27.3.24	5312	Encoder fbk mon		ENUM	E1 Abs	0	0	ER	FVS
				0	E1 Abs				
				1	E1 Inc				
				2	E2 Abs				
				3	E2 Inc				
				4	E1 None				
				5	E2 None				

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
27.4 - SERVICE/FIELDBUS SERV									
27.4.1	4016	Fieldbus float order		BIT	0	0	1	ERW	FVS
27.4.2	4018	Profibus byte order		BIT	0	0	1	ERW	FVS
27.4.3	5604	InputSize		UINT16	0	0	65535	ER	FVS
27.4.4	5606	OutputSize		UINT16	0	0	65535	ER	FVS
27.4.5	5614	PN diagnostic		UINT32	0	0	4294967295	ERW	FVS
27.4.6	5616	MDPlc direct map		INT32	0	0	1	ERWZ	FVS

27.5 - SERVICE/EXT IO SERV

27.5.1	5488	External IO period		UINT16	8	8	64	ERW	FVS
27.5.2	5490	External IO address		INT16	1	1	255	ERW	FVS
27.5.3	5492	External IO baudrate		ENUM	500k	0	12	ERW	FVS
				0	Auto				
				1	125k				
				2	250k				
				3	500k				
				4	1M				
				5	9600				
				6	19200				
				7	93750				
				8	187,5k				
				9	1,5M				
				10	3M				
				11	6M				
				12	12M				
27.5.4	5494	External IO lifetime		UINT16	3	1	100	ERW	FVS
27.5.5	5496	External IO err cnt		UINT16	0	0	65535	ERW	FVS
27.5.6	4980	ExtIO holdoff	ms	UINT16	1	1	10000	ERW	FVS
27.5.7	4982	External IO pdo time		UINT16	4	1	10000	ERW	FVS
27.5.8	4984	External IO HB time	ms	UINT16	100	8	10000	ERW	FVS

27.6 - SERVICE/FAST LINK SERV

27.6.1	4946	FL fault holdoff	us	UINT16	250	125	10000	ERW	FVS
27.6.2	5790	FLRxTimeoutHoldOff		UINT16	4	0	4000	ERW	FVS
27.6.3	5792	FLRxTimeoutCnt		UINT16	0	0	0	ER	FVS
27.6.4	5794	FLSyncSlaveEHoldOff		UINT16	4	0	4000	ERW	FVS
27.6.5	5796	FLSyncSlaveErrCnt		UINT16	0	0	0	ER	FVS

27.7 - SERVICE/SERIAL NUMBERS

27.7.1	520	Product S/N		UINT32	0	0	0	R	FVS
27.7.2	522	Regulation S/N		UINT32	0	0	0	R	FVS
27.7.3	524	Power S/N		UINT32	0	0	0	R	FVS
27.7.4	536	Slot1 card S/N		UINT32	0	0	0	R	FVS
27.7.5	538	Slot2 card S/N		UINT32	0	0	0	R	FVS
27.7.6	540	Slot3 card S/N		UINT32	0	0	0	R	FVS

27.8 - SERVICE/SENSORLESS VF

27.8.1	3356	Magn curr speed zero	perc	UINT32	150	50	200	ERW	<u>S</u>
27.8.2	3384	Vf catch min time	ms	UINT16	600	1	20000	ERW	<u>V</u>
27.8.3	2456	AC brake max time	ms	FLOAT	20000	1	60000.0	ERWS	<u>V</u>
27.8.4	2458	AC brake max curr	perc	UINT16	150	101	200	ERWS	<u>V</u>

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
27.8.5	2496	Steady curr filter		FLOAT	10.0	0.0	1000.0	ERWZ	_V_

27.9 - SERVICE/CURRENTS

27.9.1	80	Phase current U	A	FLOAT	0.0	0.0	0.0	ER	FVS
27.9.2	82	Phase current V	A	FLOAT	0.0	0.0	0.0	ER	FVS
27.9.3	84	Phase current W	A	FLOAT	0.0	0.0	0.0	ER	FVS
27.9.4	90	Phase current RMS U	A	FLOAT	0.0	0.0	0.0	ER	FVS
27.9.5	92	Phase current RMS V	A	FLOAT	0.0	0.0	0.0	ER	FVS
27.9.6	94	Phase current RMS W	A	FLOAT	0.0	0.0	0.0	ER	FVS
27.9.7	78	Phase current filter	ms	UINT16	0	0	20	ERW	FVS

27.10 - SERVICE/MOTOR PHLOSS

27.10.1	4676	Mot PhLoss magn time	ms	UINT16	5000	1000	20000	ERW	FVS
27.10.2	4688	Mot PhLoss wait	ms	UINT16	1000	0	10000	ERW	FVS
27.10.3	4694	Mot PhLoss SRL delay	ms	UINT16	200	0	1000	ERW	FVS

27.11 - SERVICE/LC SERV

27.11.1	200	Thermal_resistance1	degC/W	FLOAT	0.02	0	1	ERWS	FVS
27.11.2	202	Thermal_resistance2	degC/W	FLOAT	0	0	1	ERWS	FVS
27.11.3	206	Powerloss factor1		FLOAT	0.005	0	1	ERWS	FVS
27.11.4	210	Liquid temp filter	ms	UINT16	1000	0	10000	ERW	FVS
27.11.5	212	Powerloss factor2		FLOAT	0	0	1	ERWS	FVS
27.11.6	4594	HumTSensErr activity		ENUM	Disable	0	4	ERW	FVS
				0	Ignore				
				1	Warning				
				2	Disable				
				3	Stop				
				4	Fast stop				
27.11.7	4580	HumTSensErr holdoff	s	UINT16	3	1	50	ERW	FVS
27.11.8	6052	LC sens err enable		UINT16	2	0	0	ERWS	FVS

27.12 - SERVICE/MAGNETIZATION

27.12.1	2500	DSP enabler code		UINT32	38991	0	4294967295	ERW	FVS
27.12.2	2502	SoftScope N page		UINT16	0	0	65535	ERW	FVS

27.13 - SERVICE/OBSOLETE PARAMS

27.13.1	2400	Voltage flux boost	perc	FLOAT	0.0	0.0	15.0	ERWS	_V_
27.13.2	2402	Voltage boost gain	V/A	FLOAT	0.0	0.0	0.0	ERWS	_V_
27.13.3	2470	Damping gain	perc	UINT16	0	0	100	ERW	_V_
27.13.4	2472	Damping threshold 1	Hz	INT16	20	5	100	ERW	_V_
27.13.5	2474	Damping threshold 2	Hz	INT16	30	5	100	ERW	_V_
27.13.6	2508	Motor temp K		FLOAT	0	0.0	0	ERW	FVS

27.14 - SERVICE/FILTERS

27.14.1	30	Display spd filter	ms	UINT16	200	10	1000	ERW	FVS
27.14.2	32	Display trq filter	ms	UINT16	200	10	1000	ERW	FVS
27.14.3	34	Display cosphi filt	ms	UINT16	600	0	1000	ERW	FVS

27.15 - SERVICE/TEST VAR

27.15.1	5060	Var 1 addr		UINT32	3759169536	0	0	ERW	FVS
27.15.2	5062	Var 2 addr		UINT32	3759169536	0	0	ERW	FVS

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
27.15.3	5070	Var 1 type		ENUM	Not assigned	0	2	ERW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
27.15.4	5072	Var 2 type		ENUM	Not assigned	0	2	ERW	FVS
				0	Not assigned				
				1	Count 16				
				2	Count 32				
27.15.5	5080	Var 1 mon		INT32	0	0	0	ER	FVS
27.15.6	5082	Var 2 mon		INT32	0	0	0	ER	FVS

27.16 - SERVICE/OBSERVER

27.16.1	2570	Flux obsv gain		FLOAT	1.0	0.0	5.0	ERWS	F_S
27.16.2	2572	Flux obsv enable		BIT	0	0	1	ERWS	F_S
27.16.3	2574	Flux obsv filter tau	ms	FLOAT	4.0	0.01	10.0	ERWS	F_S
27.16.4	2576	Flux obsv speed thrd	perc	FLOAT	15.0	0.0	400.0	ERWS	F_S

27.17 - SERVICE/SD CARD

27.17.1	598	Load from SD card		BIT	0	0	1	ERWZ	FVS
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28 - RECIPE CONFIG

28.1	6300	Recipe config 1		UINT16	0	0	0	RW	FVS
28.2	6302	Recipe config 2		UINT16	0	0	0	RW	FVS
28.3	6304	Recipe config 3		UINT16	0	0	0	RW	FVS
28.4	6306	Recipe config 4		UINT16	0	0	0	RW	FVS
28.5	6308	Recipe config 5		UINT16	0	0	0	RW	FVS
28.6	6310	Recipe config 6		UINT16	0	0	0	RW	FVS
28.7	6312	Recipe config 7		UINT16	0	0	0	RW	FVS
28.8	6314	Recipe config 8		UINT16	0	0	0	RW	FVS
28.9	6316	Recipe config 9		UINT16	0	0	0	RW	FVS
28.10	6318	Recipe config 10		UINT16	0	0	0	RW	FVS
28.11	6320	Recipe config 11		UINT16	0	0	0	RW	FVS
28.12	6322	Recipe config 12		UINT16	0	0	0	RW	FVS
28.13	6324	Recipe config 13		UINT16	0	0	0	RW	FVS
28.14	6326	Recipe config 14		UINT16	0	0	0	RW	FVS
28.15	6328	Recipe config 15		UINT16	0	0	0	RW	FVS
28.16	6330	Recipe config 16		UINT16	0	0	0	RW	FVS
28.17	6332	Recipe config 17		UINT16	0	0	0	RW	FVS
28.18	6334	Recipe config 18		UINT16	0	0	0	RW	FVS
28.19	6336	Recipe config 19		UINT16	0	0	0	RW	FVS
28.20	6338	Recipe config 20		UINT16	0	0	0	RW	FVS

29 - RECIPE

Menu	PAR	Description	UM	Type	FB BIT Def	Min	Max	Acc	Mod
PARAMETERS NOT PRESENT ON MENU									
-	220	Theta ref mon		INT32	0.0	0.0	0.0	ER	
-	224	Flux ref mon		INT32	0.0	0.0	0.0	ER	
-	262	Motor speed nofilter	FF	INT16	16 0	0	0	ER	
-	362	Drive overload trip		BIT	16 0	0	1	ER	
-	366	Drive overload 80%		BIT	16 0	0	1	ER	
-	626	Ramp ref out mon	FF	INT16	16 0	0	0	ER	
-	760	Ramp out mon	FF	INT16	16 0	0	0	ER	
-	764	Ramp acc state		BIT	16 0	0	1	ER	
-	766	Ramp dec state		BIT	16 0	0	1	ER	
-	934	Ref is 0		BIT	16 0	0	1	ER	
-	936	Ref is 0 delay		BIT	16 0	0	1	ER	
-	938	Ref is 0 Vf limit		BIT	16 0	0	1	ER	
-	944	Speed is 0		BIT	16 0	0	1	ER	
-	946	Speed is 0 delay		BIT	16 0	0	1	ER	
-	956	Speed thr 1_2 mon		BIT	16 0	0	1	ER	
-	966	Set speed		BIT	16 0	0	1	ER	
-	976	Speed thr 3 mon		BIT	16 0	0	1	ER	
-	986	Current thr mon		BIT	16 0	0	1	ER	
-	1030	Local/remote mon		BIT	16 0	0	1	ER	
-	1060	Sequencer status		UINT16	16 0	0	0	ER	
-	1062	Drive OK		BIT	16 0	0	1	ER	
-	1064	Drive ready		BIT	16 0	0	1	ER	
-	1072	UV Wng&Restart		BIT	16 0	0	1	ER	
-	1110	Digital input E mon		BIT	16 0	0	1	ER	
-	1112	Digital input 1 mon		BIT	16 0	0	1	ER	
-	1114	Digital input 2 mon		BIT	16 0	0	1	ER	
-	1116	Digital input 3 mon		BIT	16 0	0	1	ER	
-	1118	Digital input 4 mon		BIT	16 0	0	1	ER	
-	1120	Digital input 5 mon		BIT	16 0	0	1	ER	
-	1210	Digital input 1X mon		BIT	16 0	0	1	ER	
-	1212	Digital input 2X mon		BIT	16 0	0	1	ER	
-	1214	Digital input 3X mon		BIT	16 0	0	1	ER	
-	1216	Digital input 4X mon		BIT	16 0	0	1	ER	
-	1218	Digital input 5X mon		BIT	16 0	0	1	ER	
-	1220	Digital input 6X mon		BIT	16 0	0	1	ER	
-	1222	Digital input 7X mon		BIT	16 0	0	1	ER	
-	1224	Digital input 8X mon		BIT	16 0	0	1	ER	
-	1530	Analog inp1		BIT	16 0	0	1	ER	
-	1540	An inp 1 err mon		BIT	16 0	0	0	ER	
-	1542	Analog inp1>thr		BIT	16 0	0	1	ER	
-	1580	Analog inp2		BIT	16 0	0	1	ER	
-	1590	An inp 2 err mon		BIT	16 0	0	0	ER	
-	1592	Analog inp2>thr		BIT	16 0	0	1	ER	
-	1640	An inp 1X err mon		BIT	16 0	0	0	ER	
-	1690	An inp 2X err mon		BIT	16 0	0	0	ER	
-	2388	Torque ref nofilter	perc	FLOAT	16 0.0	0.0	0.0	ER	
-	2396	Torque nofilter	perc	FLOAT	16 0.0	0.0	0.0	ER	
-	3006	Speed ratio out mon	rpm	INT16	16 0	0	0	ER	
-	3180	Brake control mon		BIT	16 0	0	1	ER	
-	3192	Brake open thr mon	perc	FLOAT	0	0.0	0	ERS	
-	3214	Motor overload trip		BIT	16 0	0	1	ER	

Menu	PAR	Description	UM	Type	FB	BIT	Def	Min	Max	Acc	Mod
-	3262	Bres overload trip		BIT	16	0		0	1	ER	
-	3374	Vf catch out		INT32	16	0		0	0	ER	
-	3442	Powerloss rampdown		BIT	16	0		0	1	ER	
-	3446	Powerloss nexratio		INT32	32	0		0	0	ER	
-	3448	Powerloss nextactive		BIT	16	0		0	1	ER	
-	3480	Vdc ctrl ramp freeze		BIT	16	0		0	1	ER	
-	3512	Drv thr overtemp mon		UINT32		0		0	0	ER	
-	3514	Mot thr overtemp mon		UINT32		0		0	0	ER	
-	4372	DS402 status word		UINT16	16	0		0	65535	ER	
-	4394	PFdrv status word 1		UINT16	16	0		0	65535	ER	
-	4396	PFdrv status word 2		UINT16	16	0		0	65535	ER	
-	4538	KTY84/PTC current	mA	UINT32		2		1	10	ERWS	
-	4708	Alm dig out mon 1		BIT	16	0		0	1	ER	
-	4710	Alm dig out mon 2		BIT	16	0		0	1	ER	
-	4712	Alm dig out mon 3		BIT	16	0		0	1	ER	
-	4714	Alm dig out mon 4		BIT	16	0		0	1	ER	
-	4770	First alarm		UINT32	16	0		0	0	ERW	
-	4780	Alarm PLC		UINT16		0		0	0	ER	
-	4840	Alarm lo state		UINT32	32	0		0	0	ER	
-	4842	Alarm hi state		UINT32	32	0		0	0	ER	
-	5510	Digital input 9X mon		BIT	16	0		0	1	ER	
-	5512	Digital input10X mon		BIT	16	0		0	1	ER	
-	5514	Digital input11X mon		BIT	16	0		0	1	ER	
-	5516	Digital input12X mon		BIT	16	0		0	1	ER	
-	5518	Digital input13X mon		BIT	16	0		0	1	ER	
-	5520	Digital input14X mon		BIT	16	0		0	1	ER	
-	5522	Digital input15X mon		BIT	16	0		0	1	ER	
-	5524	Digital input16X mon		BIT	16	0		0	1	ER	
-	5800	FL Fwd 1 inv mon		INT32	32	0		0	0	ER	
-	5802	FL Fwd 2 inv mon		INT32	32	0		0	0	ER	
-	5804	FL Fwd 3 inv mon		INT32	32	0		0	0	ER	
-	5806	FL Fwd 4 inv mon		INT32	32	0		0	0	ER	
-	5808	FL Fwd 5 inv mon		INT32	32	0		0	0	ER	
-	5810	FL Fwd 6 inv mon		INT32	32	0		0	0	ER	
-	5812	FL Fwd 7 inv mon		INT32	32	0		0	0	ER	
-	5814	FL Fwd 8 inv mon		INT32	32	0		0	0	ER	
-	6000	Null		UINT32	32	0		0	0	ER	
-	6002	One		UINT32	32	1		1	1	ER	
-	6004	Speed limit state		BIT	16	0		0	1	ER	
-	6006	Current limit state		BIT	16	0		0	1	ER	
-	6044	Condensation state		UINT32		0		0	0	ER	
-	6046	Overhumidity state		UINT32		0		0	0	ER	

G – SELECTION LISTS

PAR	Description	Menu	PAR	Description	Menu	PAR	Description	Menu
L_ANOUT			3704	Pad 3	22.12.3	894	Mpot output mon	8.13
6000	Null	(*)	3706	Pad 4	22.12.4	920	Jog output mon	9.6
626	Ramp ref out mon	(*)	3708	Pad 5	22.12.5	1500	Analog input 1 mon	14.1
628	Ramp setpoint	1.7	3710	Pad 6	22.12.6	1550	Analog input 2 mon	14.17
760	Ramp out mon	(*)	3712	Pad 7	22.12.7	1600	Analog input 1X mon	14.33
664	Speed setpoint	1.8	3714	Pad 8	22.12.8	1650	Analog input 2X mon	14.45
260	Motor speed	1.9	3716	Pad 9	22.12.9	368	Drive overload accum	1.24
262	Motor speed nofilter	(*)	3718	Pad 10	22.12.10	3212	Motor overload accum	1.23
2150	Encoder 1 speed	17.2.13	3720	Pad 11	22.12.11	3260	Bres overload accum	1.25
5150	Encoder 2 speed	17.3.13	3722	Pad 12	22.12.12	4024	Fieldbus M->S1 mon	23.3.3
250	Output current	1.1	3724	Pad 13	22.12.13	4034	Fieldbus M->S2 mon	23.3.7
252	Output voltage	1.2	3726	Pad 14	22.12.14	4044	Fieldbus M->S3 mon	23.3.11
254	Output frequency	1.3	3728	Pad 15	22.12.15	4054	Fieldbus M->S4 mon	23.3.15
256	Output power	1.4	3730	Pad 16	22.12.16	4064	Fieldbus M->S5 mon	23.3.19
280	Torque current ref	1.19	5008	Test gen out	27.1.5	4074	Fieldbus M->S6 mon	23.3.23
282	Magnet current ref	1.20	5750	FL Fwd 1 mon	23.8.13	4084	Fieldbus M->S7 mon	23.3.27
284	Torque current	1.21	5752	FL Fwd 2 mon	23.8.14	4094	Fieldbus M->S8 mon	23.3.31
286	Magnet current	1.22	5754	FL Fwd 3 mon	23.8.15	4104	Fieldbus M->S9 mon	23.3.35
2360	Torque lim Pos Inuse	20.9	5756	FL Fwd 4 mon	23.8.16	4114	Fieldbus M->S10 mon	23.3.39
2362	Torque lim Neg Inuse	20.10	5758	FL Fwd 5 mon	23.8.17	4124	Fieldbus M->S11 mon	23.3.43
2386	Torque ref %	20.18	5760	FL Fwd 6 mon	23.8.18	4134	Fieldbus M->S12 mon	23.3.47
2388	Torque ref nofilter	(*)	5762	FL Fwd 7 mon	23.8.19	4144	Fieldbus M->S13 mon	23.3.51
2394	Torque %	20.20	5764	FL Fwd 8 mon	23.8.20	4154	Fieldbus M->S14 mon	23.3.55
2396	Torque nofilter	(*)	5800	FL Fwd 1 inv mon	(*)	4164	Fieldbus M->S15 mon	23.3.59
270	DC link voltage	1.10	5802	FL Fwd 2 inv mon	(*)	4174	Fieldbus M->S16 mon	23.3.63
3006	Speed ratio out mon	(*)	5804	FL Fwd 3 inv mon	(*)	3700	Pad 1	22.13.1
3070	Droop out mon	22.2.5	5806	FL Fwd 4 inv mon	(*)	3702	Pad 2	22.13.2
852	Multi ref out mon	7.24	5808	FL Fwd 5 inv mon	(*)	3704	Pad 3	22.13.3
870	Mpot setpoint	8.1	5810	FL Fwd 6 inv mon	(*)	3706	Pad 4	22.13.4
894	Mpot output mon	8.13	5812	FL Fwd 7 inv mon	(*)	3708	Pad 5	22.13.5
920	Jog output mon	9.6	5814	FL Fwd 8 inv mon	(*)	3710	Pad 6	22.13.6
3104	Inertia comp mon	22.3.3	4538	KTY84/PTC current	(*)	3712	Pad 7	22.13.7
1500	Analog input 1 mon	14.1	2346	Torque current ref 1	20.15	3714	Pad 8	22.13.8
1550	Analog input 2 mon	14.17	2342	Working load	1.18	3716	Pad 9	22.13.9
1600	Analog input 1X mon	14.33	L_CMP			3718	Pad 10	22.13.10
1650	Analog input 2X mon	14.45	XXXX (1)			3720	Pad 11	22.13.11
368	Drive overload accum	1.24	626	Ramp ref out mon	(*)	3722	Pad 12	22.13.12
3212	Motor overload accum	1.23	628	Ramp setpoint	1.7	3724	Pad 13	22.13.13
3260	Bres overload accum	1.25	760	Ramp out mon	(*)	3726	Pad 14	22.13.14
2232	Spd reg P gain Inuse	18.11	664	Speed setpoint	1.8	3728	Pad 15	22.13.15
2234	Spd reg I gain Inuse	18.12	260	Motor speed	1.9	3730	Pad 16	22.13.16
2246	Speed reg P factor	18.16	262	Motor speed nofilter	(*)	5750	FL Fwd 1 mon	23.8.13
2248	Speed reg I factor	18.17	2150	Encoder 1 speed	17.2.13	5752	FL Fwd 2 mon	23.8.14
3446	Powerloss nexratio	(*)	5150	Encoder 2 speed	17.3.13	5754	FL Fwd 3 mon	23.8.15
4024	Fieldbus M->S1 mon	23.3.3	250	Output current	1.1	5756	FL Fwd 4 mon	23.8.16
4034	Fieldbus M->S2 mon	23.3.7	252	Output voltage	1.2	5758	FL Fwd 5 mon	23.8.17
4044	Fieldbus M->S3 mon	23.3.11	254	Output frequency	1.3	5760	FL Fwd 6 mon	23.8.18
4054	Fieldbus M->S4 mon	23.3.15	256	Output power	1.4	5762	FL Fwd 7 mon	23.8.19
4064	Fieldbus M->S5 mon	23.3.19	280	Torque current ref	1.19	5764	FL Fwd 8 mon	23.8.20
4074	Fieldbus M->S6 mon	23.3.23	282	Magnet current ref	1.20	5800	FL Fwd 1 inv mon	(*)
4084	Fieldbus M->S7 mon	23.3.27	284	Torque current	1.21	5802	FL Fwd 2 inv mon	(*)
4094	Fieldbus M->S8 mon	23.3.31	286	Magnet current	1.22	5804	FL Fwd 3 inv mon	(*)
4104	Fieldbus M->S9 mon	23.3.35	2386	Torque ref %	20.18	5806	FL Fwd 4 inv mon	(*)
4114	Fieldbus M->S10 mon	23.3.39	2388	Torque ref nofilter	(*)	5808	FL Fwd 5 inv mon	(*)
4124	Fieldbus M->S11 mon	23.3.43	2394	Torque %	20.20	5810	FL Fwd 6 inv mon	(*)
4134	Fieldbus M->S12 mon	23.3.47	2396	Torque nofilter	(*)	5812	FL Fwd 7 inv mon	(*)
4144	Fieldbus M->S13 mon	23.3.51	270	DC link voltage	1.10	5814	FL Fwd 8 inv mon	(*)
4154	Fieldbus M->S14 mon	23.3.55	3006	Speed ratio out mon	(*)	2346	Torque current ref 1	20.15
4164	Fieldbus M->S15 mon	23.3.59	3070	Droop out mon	22.2.5	(1) the XXXX parameter changes according to the src parameter used:		
4174	Fieldbus M->S16 mon	23.3.63	852	Multi ref out mon	7.24	960 Set speed ref src		
3700	Pad 1	22.12.1	870	Mpot setpoint	8.1			
3702	Pad 2	22.12.2						

PAR	Description	Menu	PAR	Description	Menu	PAR	Description	Menu
(1) = 968	Dig set speed ref	10.11	1210	Digital input 1X mon	(*)	4484	Bit15 decomp mon	23.6.18
3660	Compare input 1 src		1212	Digital input 2X mon	(*)	3700	Pad 1	22.13.1
(1) = 3650	Dig compare input 1	22.12.1	1214	Digital input 3X mon	(*)	3702	Pad 2	22.13.2
3662	Compare input 2 src		1216	Digital input 4X mon	(*)	3704	Pad 3	22.13.3
(1) = 3652	Dig compare input 2	22.12.2	1218	Digital input 5X mon	(*)	3706	Pad 4	22.13.4
			1220	Digital input 6X mon	(*)	3708	Pad 5	22.13.5
			1222	Digital input 7X mon	(*)	3710	Pad 6	22.13.6
			1224	Digital input 8X mon	(*)	3712	Pad 7	22.13.7
			5510	Digital input 9X mon	(*)	3714	Pad 8	22.13.8
			5512	Digital input10X mon	(*)	3716	Pad 9	22.13.9
			5514	Digital input11X mon	(*)	3718	Pad 10	22.13.10
			5516	Digital input12X mon	(*)	3720	Pad 11	22.13.11
			5518	Digital input13X mon	(*)	3722	Pad 12	22.13.12
			5520	Digital input14X mon	(*)	3724	Pad 13	22.13.13
			5522	Digital input15X mon	(*)	3726	Pad 14	22.13.14
			5524	Digital input16X mon	(*)	3728	Pad 15	22.13.15
			1062	Drive OK	(*)	3730	Pad 16	22.13.16
			1064	Drive ready	(*)	6004	Speed limit state	(*)
			934	Ref is 0	(*)	6006	Current limit state	(*)
			936	Ref is 0 delay	(*)	764	Ramp acc state	(*)
			944	Speed is 0	(*)	766	Ramp dec state	(*)
			946	Speed is 0 delay	(*)	1030	Local/remote mon	(*)
			956	Speed thr 1_2 mon	(*)	4780	Alarm PLC	(*)
			966	Set speed	(*)	3676	Compare output	22.12.8
			976	Speed thr 3 mon	(*)	3442	Powerloss rampdown	(*)
			986	Current thr mon	(*)	3448	Powerloss nextactive	(*)
			1066	Enable state mon	1.26	3180	Brake control mon	(*)
			1068	Start state mon	1.27	3304	Par set select mon	22.8.3
			1070	FastStop state mon	1.28	5720	Sync slave mon	23.8.29
			1024	Enable cmd mon	11.13	3512	Drv thr overtemp mon	(*)
			1026	Start cmd mon	11.14	3514	Mot thr overtemp mon	(*)
			1028	FastStop cmd mon	11.15	6044	Condensation state	(*)
			1054	Safe start mon	11.16	6046	Overhumidity state	(*)
			1034	Drv interlock mon	11.25	938	Ref is 0 Vf limit	(*)
			4708	Alm dig out mon 1	(*)	1072	UV Wng&Restart	(*)
			4710	Alm dig out mon 2	(*)	3556	Timer1 mon	22.20.4
			4712	Alm dig out mon 3	(*)	3566	Timer2 mon	22.20.8
			4714	Alm dig out mon 4	(*)	1540	An inp 1 err mon	(*)
			1530	Analog inp1<thr	(*)	1590	An inp 2 err mon	(*)
			1542	Analog inp1>thr	(*)	1640	An inp 1X err mon	(*)
			1580	Analog inp2<thr	(*)	1690	An inp 2X err mon	(*)
			1592	Analog inp2>thr	(*)	5350	Encoder 1 state	17.2.15
			362	Drive overload trip	(*)	5360	Encoder 2 state	17.3.15
			3214	Motor overload trip	(*)	5370	Encoder 3 state	17.4.6
			3262	Bres overload trip	(*)	3312	UV RT state	22.11.11
			366	Drive overload 80%	(*)			
			1048	FR start mon	11.21			
			1050	FR reverse mon	11.22			
			4454	Bit0 decomp mon	23.6.3			
			4456	Bit1 decomp mon	23.6.4			
			4458	Bit2 decomp mon	23.6.5			
			4460	Bit3 decomp mon	23.6.6			
			4462	Bit4 decomp mon	23.6.7			
			4464	Bit5 decomp mon	23.6.8			
			4466	Bit6 decomp mon	23.6.9			
			4468	Bit7 decomp mon	23.6.10			
			4470	Bit8 decomp mon	23.6.11			
			4472	Bit9 decomp mon	23.6.12			
			4474	Bit10 decomp mon	23.6.13			
			4476	Bit11 decomp mon	23.6.14			
			4478	Bit12 decomp mon	23.6.15			
			4480	Bit13 decomp mon	23.6.16			
			4482	Bit14 decomp mon	23.6.17			

L_CTRLMODE

XXXX (2)

6206	Ctrl mode sel mon	22.16.5
4024	Fieldbus M->S1 mon	23.3.3
4034	Fieldbus M->S2 mon	23.3.7
4044	Fieldbus M->S3 mon	23.3.11
4054	Fieldbus M->S4 mon	23.3.15
4064	Fieldbus M->S5 mon	23.3.19
4074	Fieldbus M->S6 mon	23.3.23
4084	Fieldbus M->S7 mon	23.3.27
4094	Fieldbus M->S8 mon	23.3.31
4104	Fieldbus M->S9 mon	23.3.35
4114	Fieldbus M->S10 mon	23.3.39
4124	Fieldbus M->S11 mon	23.3.43
4134	Fieldbus M->S12 mon	23.3.47
4144	Fieldbus M->S13 mon	23.3.51
4154	Fieldbus M->S14 mon	23.3.55
4164	Fieldbus M->S15 mon	23.3.59
4174	Fieldbus M->S16 mon	23.3.63
3700	Pad 1	22.13.1
3702	Pad 2	22.13.2
3704	Pad 3	22.13.3
3706	Pad 4	22.13.4
3708	Pad 5	22.13.5
3710	Pad 6	22.13.6
3712	Pad 7	22.13.7
3714	Pad 8	22.13.8
3716	Pad 9	22.13.9
3718	Pad 10	22.13.10
3720	Pad 11	22.13.11
3722	Pad 12	22.13.12
3724	Pad 13	22.13.13
3726	Pad 14	22.13.14
3728	Pad 15	22.13.15
3730	Pad 16	22.13.16

(2) the XXXX parameter changes according to the src parameter used:

6200 Ctrl mode src
(2) = 556 Control mode select 22.16.1

L_DIGSEL1

6000	Null	(*)
6002	One	(*)
1110	Digital input E mon	(*)
1112	Digital input 1 mon	(*)
1114	Digital input 2 mon	(*)
1116	Digital input 3 mon	(*)
1118	Digital input 4 mon	(*)
1120	Digital input 5 mon	(*)

L_DIGSEL2

6000	Null	(*)
6002	One	(*)
1110	Digital input E mon	(*)
1112	Digital input 1 mon	(*)
1114	Digital input 2 mon	(*)
1116	Digital input 3 mon	(*)
1118	Digital input 4 mon	(*)
1120	Digital input 5 mon	(*)
1210	Digital input 1X mon	(*)
1212	Digital input 2X mon	(*)
1214	Digital input 3X mon	(*)
1216	Digital input 4X mon	(*)
1218	Digital input 5X mon	(*)
1220	Digital input 6X mon	(*)
1222	Digital input 7X mon	(*)

PAR	Description	Menu	PAR	Description	Menu	PAR	Description	Menu
1224	Digital input 8X mon	(*)	1120	Digital input 5 mon	(*)	4482	Bit14 decomp mon	23.6.17
5510	Digital input 9X mon	(*)	1210	Digital input 1X mon	(*)	4484	Bit15 decomp mon	23.6.18
5512	Digital input10X mon	(*)	1212	Digital input 2X mon	(*)	3700	Pad 1	22.13.1
5514	Digital input11X mon	(*)	1214	Digital input 3X mon	(*)	3702	Pad 2	22.13.2
5516	Digital input12X mon	(*)	1216	Digital input 4X mon	(*)	3704	Pad 3	22.13.3
5518	Digital input13X mon	(*)	1218	Digital input 5X mon	(*)	3706	Pad 4	22.13.4
5520	Digital input14X mon	(*)	1220	Digital input 6X mon	(*)	3708	Pad 5	22.13.5
5522	Digital input15X mon	(*)	1222	Digital input 7X mon	(*)	3710	Pad 6	22.13.6
5524	Digital input16X mon	(*)	1224	Digital input 8X mon	(*)	3712	Pad 7	22.13.7
4454	Bit0 decomp mon	23.6.3	5510	Digital input 9X mon	(*)	3714	Pad 8	22.13.8
4456	Bit1 decomp mon	23.6.4	5512	Digital input10X mon	(*)	3716	Pad 9	22.13.9
4458	Bit2 decomp mon	23.6.5	5514	Digital input11X mon	(*)	3718	Pad 10	22.13.10
4460	Bit3 decomp mon	23.6.6	5516	Digital input12X mon	(*)	3720	Pad 11	22.13.11
4462	Bit4 decomp mon	23.6.7	5518	Digital input13X mon	(*)	3722	Pad 12	22.13.12
4464	Bit5 decomp mon	23.6.8	5520	Digital input14X mon	(*)	3724	Pad 13	22.13.13
4466	Bit6 decomp mon	23.6.9	5522	Digital input15X mon	(*)	3726	Pad 14	22.13.14
4468	Bit7 decomp mon	23.6.10	5524	Digital input16X mon	(*)	3728	Pad 15	22.13.15
4470	Bit8 decomp mon	23.6.11	1062	Drive OK	(*)	3730	Pad 16	22.13.16
4472	Bit9 decomp mon	23.6.12	1064	Drive ready	(*)	6004	Speed limit state	(*)
4474	Bit10 decomp mon	23.6.13	934	Ref is 0	(*)	6006	Current limit state	(*)
4476	Bit11 decomp mon	23.6.14	936	Ref is 0 delay	(*)	764	Ramp acc state	(*)
4478	Bit12 decomp mon	23.6.15	944	Speed is 0	(*)	766	Ramp dec state	(*)
4480	Bit13 decomp mon	23.6.16	946	Speed is 0 delay	(*)	4780	Alarm PLC	(*)
4482	Bit14 decomp mon	23.6.17	956	Speed thr 1_2 mon	(*)	3676	Compare output	22.12.8
4484	Bit15 decomp mon	23.6.18	966	Set speed	(*)	5720	Sync slave mon	23.8.29
3700	Pad 1	22.13.1	976	Speed thr 3 mon	(*)	3556	Timer1 mon	22.20.4
3702	Pad 2	22.13.2	986	Current thr mon	(*)	3566	Timer2 mon	22.20.8
3704	Pad 3	22.13.3	1066	Enable state mon	1.26			
3706	Pad 4	22.13.4	1068	Start state mon	1.27			
3708	Pad 5	22.13.5	1070	FastStop state mon	1.28			
3710	Pad 6	22.13.6	1024	Enable cmd mon	11.13			
3712	Pad 7	22.13.7	1026	Start cmd mon	11.14			
3714	Pad 8	22.13.8	1028	FastStop cmd mon	11.15			
3716	Pad 9	22.13.9	1054	Safe start mon	11.16			
3718	Pad 10	22.13.10	1034	Drv interlock mon	11.25			
3720	Pad 11	22.13.11	4708	Alm dig out mon 1	(*)			
3722	Pad 12	22.13.12	4710	Alm dig out mon 2	(*)			
3724	Pad 13	22.13.13	4712	Alm dig out mon 3	(*)			
3726	Pad 14	22.13.14	4714	Alm dig out mon 4	(*)			
3728	Pad 15	22.13.15	1530	Analog inp1<thr	(*)			
3730	Pad 16	22.13.16	1542	Analog inp1>thr	(*)			
1530	Analog inp1<thr	(*)	1580	Analog inp2<thr	(*)			
1542	Analog inp1>thr	(*)	1592	Analog inp2>thr	(*)			
1580	Analog inp2<thr	(*)	362	Drive overload trip	(*)			
1592	Analog inp2>thr	(*)	3214	Motor overload trip	(*)			
1048	FR start mon	11.21	3262	Bres overload trip	(*)			
1050	FR reverse mon	11.22	366	Drive overload 80%	(*)			
3676	Compare output	22.12.8	1048	FR start mon	11.21			
3480	Vdc ctrl ramp freeze	(*)	1050	FR reverse mon	11.22			
3556	Timer1 mon	22.20.4	4454	Bit0 decomp mon	23.6.3			
3566	Timer2 mon	22.20.8	4456	Bit1 decomp mon	23.6.4			
3312	UV RT state	22.11.11	4458	Bit2 decomp mon	23.6.5			
			4460	Bit3 decomp mon	23.6.6			
			4462	Bit4 decomp mon	23.6.7			
			4464	Bit5 decomp mon	23.6.8			
			4466	Bit6 decomp mon	23.6.9			
			4468	Bit7 decomp mon	23.6.10			
			4470	Bit8 decomp mon	23.6.11			
			4472	Bit9 decomp mon	23.6.12			
			4474	Bit10 decomp mon	23.6.13			
			4476	Bit11 decomp mon	23.6.14			
			4478	Bit12 decomp mon	23.6.15			
			4480	Bit13 decomp mon	23.6.16			

L_FBS2M

XXXX (3)

6000 Null (*)

6002 One (*)

1110 Digital input E mon (*)

1112 Digital input 1 mon (*)

1114 Digital input 2 mon (*)

1116 Digital input 3 mon (*)

1118 Digital input 4 mon (*)

(3) the XXXX parameter changes according to the src parameter used:

1014 Local/remote src

(3) = 1012 Dig local/remote 11.7

L_FBS2M

XXXX (4)

66000 Null (*)

6002 One (*)

626 Ramp ref out mon (*)

628 Ramp setpoint 1.7

760 Ramp out mon (*)

664 Speed setpoint 1.8

260 Motor speed 1.9

262 Motor speed nofilter (*)

2150 Encoder 1 speed 17.2.13

5150 Encoder 2 speed 17.3.13

250 Output current 1.1

252 Output voltage 1.2

254 Output frequency 1.3

280 Torque current ref 1.19

282 Magnet current ref 1.20

284 Torque current 1.21

286 Magnet current 1.22

2360 Torque lim Pos Inuse 20.9

2362 Torque lim Neg Inuse 20.10

2386 Torque ref % 20.18

2388 Torque ref nofilter (*)

2394 Torque % 20.20

2396 Torque nofilter (*)

270 DC link voltage 1.10

2162 Encoder 1 position 17.2.14

2154 E1 Virtual position 27.3.2

295

PAR	Description	Menu	PAR	Description	Menu	PAR	Description	Menu
3730	Pad 16	22.13.16	3716	Pad 9	22.13.9	3716	Pad 9	22.13.9
4770	First alarm	(*)	3718	Pad 10	22.13.10	3718	Pad 10	22.13.10
4840	Alarm lo state	(*)	3720	Pad 11	22.13.11	3720	Pad 11	22.13.11
4842	Alarm hi state	(*)	3722	Pad 12	22.13.12	3722	Pad 12	22.13.12
1100	Digital input mon	1.29	3724	Pad 13	22.13.13	3724	Pad 13	22.13.13
1200	Digital input X mon	1.31	3726	Pad 14	22.13.14	3726	Pad 14	22.13.14
5008	Test gen out	27.1.5	3728	Pad 15	22.13.15	3728	Pad 15	22.13.15
5750	FL Fwd 1 mon	23.8.13	3730	Pad 16	22.13.16	3730	Pad 16	22.13.16
5752	FL Fwd 2 mon	23.8.14	5008	Test gen out	27.1.5	5008	Test gen out	27.1.5
5754	FL Fwd 3 mon	23.8.15	5750	FL Fwd 1 mon	23.8.13	5750	FL Fwd 1 mon	23.8.13
5756	FL Fwd 4 mon	23.8.16	5752	FL Fwd 2 mon	23.8.14	5752	FL Fwd 2 mon	23.8.14
5758	FL Fwd 5 mon	23.8.17	5754	FL Fwd 3 mon	23.8.15	5754	FL Fwd 3 mon	23.8.15
5760	FL Fwd 6 mon	23.8.18	5756	FL Fwd 4 mon	23.8.16	5756	FL Fwd 4 mon	23.8.16
5762	FL Fwd 7 mon	23.8.19	5758	FL Fwd 5 mon	23.8.17	5758	FL Fwd 5 mon	23.8.17
5764	FL Fwd 8 mon	23.8.20	5760	FL Fwd 6 mon	23.8.18	5760	FL Fwd 6 mon	23.8.18
5800	FL Fwd 1 inv mon	(*)	5762	FL Fwd 7 mon	23.8.19	5762	FL Fwd 7 mon	23.8.19
5802	FL Fwd 2 inv mon	(*)	5764	FL Fwd 8 mon	23.8.20	5764	FL Fwd 8 mon	23.8.20
5804	FL Fwd 3 inv mon	(*)	5800	FL Fwd 1 inv mon	(*)	5800	FL Fwd 1 inv mon	(*)
5806	FL Fwd 4 inv mon	(*)	5802	FL Fwd 2 inv mon	(*)	5802	FL Fwd 2 inv mon	(*)
5808	FL Fwd 5 inv mon	(*)	5804	FL Fwd 3 inv mon	(*)	5804	FL Fwd 3 inv mon	(*)
5810	FL Fwd 6 inv mon	(*)	5806	FL Fwd 4 inv mon	(*)	5806	FL Fwd 4 inv mon	(*)
5812	FL Fwd 7 inv mon	(*)	5808	FL Fwd 5 inv mon	(*)	5808	FL Fwd 5 inv mon	(*)
5814	FL Fwd 8 inv mon	(*)	5810	FL Fwd 6 inv mon	(*)	5810	FL Fwd 6 inv mon	(*)
5850	FL Rev 1 mon	23.8.21	5812	FL Fwd 7 inv mon	(*)	5812	FL Fwd 7 inv mon	(*)
5852	FL Rev 2 mon	23.8.22	5814	FL Fwd 8 inv mon	(*)	5814	FL Fwd 8 inv mon	(*)
5854	FL Rev 3 mon	23.8.23						
5856	FL Rev 4 mon	23.8.24						
220	Theta ref mon	(*)						
224	Flux ref mon	(*)						

L_LIM

6000	Null	(*)
1500	Analog input 1 mon	14.1
1550	Analog input 2 mon	14.17
2380	Dig torque ref 1	20.12
1600	Analog input 1X mon	14.33
1650	Analog input 2X mon	14.45
4024	Fieldbus M->S1 mon	23.3.3
4034	Fieldbus M->S2 mon	23.3.7
4044	Fieldbus M->S3 mon	23.3.11
4054	Fieldbus M->S4 mon	23.3.15
4064	Fieldbus M->S5 mon	23.3.19
4074	Fieldbus M->S6 mon	23.3.23
4084	Fieldbus M->S7 mon	23.3.27
4094	Fieldbus M->S8 mon	23.3.31
4104	Fieldbus M->S9 mon	23.3.35
4114	Fieldbus M->S10 mon	23.3.39
4124	Fieldbus M->S11 mon	23.3.43
4134	Fieldbus M->S12 mon	23.3.47
4144	Fieldbus M->S13 mon	23.3.51
4154	Fieldbus M->S14 mon	23.3.55
4164	Fieldbus M->S15 mon	23.3.59
4174	Fieldbus M->S16 mon	23.3.63
3700	Pad 1	22.13.1
3702	Pad 2	22.13.2
3704	Pad 3	22.13.3
3706	Pad 4	22.13.4
3708	Pad 5	22.13.5
3710	Pad 6	22.13.6
3712	Pad 7	22.13.7
3714	Pad 8	22.13.8

L_MLTREF

XXXXX (5)		
1500	Analog input 1 mon	14.1
1550	Analog input 2 mon	14.17
852	Multi ref out mon	7.24
894	Mpot output mon	8.13
2150	Encoder 1 speed	17.2.13
5150	Encoder 2 speed	17.3.13
1600	Analog input 1X mon	14.33
1650	Analog input 2X mon	14.45
3070	Droop out mon	22.2.5
4024	Fieldbus M->S1 mon	23.3.3
4034	Fieldbus M->S2 mon	23.3.7
4044	Fieldbus M->S3 mon	23.3.11
4054	Fieldbus M->S4 mon	23.3.15
4064	Fieldbus M->S5 mon	23.3.19
4074	Fieldbus M->S6 mon	23.3.23
4084	Fieldbus M->S7 mon	23.3.27
4094	Fieldbus M->S8 mon	23.3.31
4104	Fieldbus M->S9 mon	23.3.35
4114	Fieldbus M->S10 mon	23.3.39
4124	Fieldbus M->S11 mon	23.3.43
4134	Fieldbus M->S12 mon	23.3.47
4144	Fieldbus M->S13 mon	23.3.51
4154	Fieldbus M->S14 mon	23.3.55
4164	Fieldbus M->S15 mon	23.3.59
4174	Fieldbus M->S16 mon	23.3.63
3700	Pad 1	22.13.1
3702	Pad 2	22.13.2
3704	Pad 3	22.13.3
3706	Pad 4	22.13.4
3708	Pad 5	22.13.5
3710	Pad 6	22.13.6
3712	Pad 7	22.13.7
3714	Pad 8	22.13.8

L_NLIM

6000	Null	(*)
1500	Analog input 1 mon	14.1
1550	Analog input 2 mon	14.17
2380	Dig torque ref 1	20.12

(4) the XXXX parameter changes according to the src parameter used:

222	Theta ref src	
(5) = 220	Theta ref mon	(*)
226	Flux ref src	
(5) = 224	Flux ref mon	(*)
610	Ramp ref 1 src	
(5) = 600	Dig ramp ref 1	5.1
612	Ramp ref 2 src	
(5) = 602	Dig ramp ref 2	5.2
614	Ramp ref 3 src	
(5) = 604	Dig ramp ref 3	5.3
650	Speed ref 1 src	
(5) = 640	Dig speed ref 1	5.15
652	Speed ref 2 src	
(5) = 642	Dig speed ref 2	5.16
832	Multi ref 0 src	
(5) = 800	Multi reference 0	7.1
834	Multi ref 1 src	
(5) = 802	Multi reference 1	7.2

L_PLIM		
6000	Null	(*)
1500	Analog input 1 mon	14.1
1550	Analog input 2 mon	14.17
2380	Dig torque ref 1	20.12
2372	Torque limit pos	20.6
2338	Torque limit adapt	22.21.5
1600	Analog input 1X mon	14.33

1500	Analog input 1 mon	14.1
1550	Analog input 2 mon	14.17
626	Ramp ref out mon	(*)
664	Speed setpoint	1.8
262	Motor speed nofilter	(*)
2150	Encoder 1 speed	17.2.13
5150	Encoder 2 speed	17.3.13
1600	Analog input 1X mon	14.33
1650	Analog input 2X mon	14.45

6000	Null	(*)
1110	Digital input E mon	(*)
1112	Digital input 1 mon	(*)
1114	Digital input 2 mon	(*)
1116	Digital input 3 mon	(*)
1118	Digital input 4 mon	(*)
1120	Digital input 5 mon	(*)

PAR	Description	Menu	PAR	Description	Menu	PAR	Description	Menu
6000	Null	(*)				4154	Fieldbus M->S14 mon	23.3.55
L_TCREF			3186	Brake open thr src	22.15.8	4164	Fieldbus M->S15 mon	23.3.59
XXXX (6)			(6) = 3184 Brake open thr			4174	Fieldbus M->S16 mon	23.3.63
1500	Analog input 1 mon	14.1	L_TEMPCTRL			3700	Pad 1	22.11.1
1550	Analog input 2 mon	14.17	6000	Null	(*)	3702	Pad 2	22.11.2
1600	Analog input 1X mon	14.33	272	Heatsink temperature	1.11	3704	Pad 3	22.11.3
1650	Analog input 2X mon	14.45	6038	Intake liquid temp	22.19.7	3706	Pad 4	22.11.4
4024	Fieldbus M->S1 mon	23.3.3	292	Sensor inp X mon	1.13	3708	Pad 5	22.11.5
4034	Fieldbus M->S2 mon	23.3.7	1544	An inp 1 temp mon	1.14	3710	Pad 6	22.11.6
4044	Fieldbus M->S3 mon	23.3.11	1594	An inp 2 temp mon	1.15	3712	Pad 7	22.11.7
4054	Fieldbus M->S4 mon	23.3.15	1610	An inp 1X temp mon	1.16	3714	Pad 8	22.11.8
4064	Fieldbus M->S5 mon	23.3.19	1660	An inp 2X temp mon	1.17	3716	Pad 9	22.11.9
4074	Fieldbus M->S6 mon	23.3.23	290	Motor temperature	1.12	3718	Pad 10	22.11.10
4084	Fieldbus M->S7 mon	23.3.27	3700	Pad 1	22.13.1	3720	Pad 11	22.11.11
4094	Fieldbus M->S8 mon	23.3.31	3702	Pad 2	22.13.2	3722	Pad 12	22.11.12
4104	Fieldbus M->S9 mon	23.3.35	3704	Pad 3	22.13.3	3724	Pad 13	22.11.13
4114	Fieldbus M->S10 mon	23.3.39	3706	Pad 4	22.13.4	3726	Pad 14	22.11.14
4124	Fieldbus M->S11 mon	23.3.43	3708	Pad 5	22.13.5	3728	Pad 15	22.11.15
4134	Fieldbus M->S12 mon	23.3.47	3710	Pad 6	22.13.6	3730	Pad 16	22.11.16
4144	Fieldbus M->S13 mon	23.3.51	3712	Pad 7	22.13.7	6000	Null	(*)
4154	Fieldbus M->S14 mon	23.3.55	3714	Pad 8	22.13.8	5008	Test gen out	27.1.5
4164	Fieldbus M->S15 mon	23.3.59	3716	Pad 9	22.13.9	5750	FL Fwd 1 mon	23.8.13
4174	Fieldbus M->S16 mon	23.3.63	3718	Pad 10	22.13.10	5752	FL Fwd 2 mon	23.8.14
3700	Pad 1	22.13.1	3720	Pad 11	22.13.11	5754	FL Fwd 3 mon	23.8.15
3702	Pad 2	22.13.2	3722	Pad 12	22.13.12	5756	FL Fwd 4 mon	23.8.16
3704	Pad 3	22.13.3	3724	Pad 13	22.13.13	5758	FL Fwd 5 mon	23.8.17
3706	Pad 4	22.13.4	3726	Pad 14	22.13.14	5760	FL Fwd 6 mon	23.8.18
3708	Pad 5	22.13.5	3728	Pad 15	22.13.15	5762	FL Fwd 7 mon	23.8.19
3710	Pad 6	22.13.6	3730	Pad 16	22.13.16	5764	FL Fwd 8 mon	23.8.20
3712	Pad 7	22.13.7	L_THETASEL			5800	FL Fwd 1 inv mon	(*)
3714	Pad 8	22.13.8	5750	FL Fwd 1 mon	23.8.13	5802	FL Fwd 2 inv mon	(*)
3716	Pad 9	22.13.9	5752	FL Fwd 2 mon	23.8.14	5804	FL Fwd 3 inv mon	(*)
3718	Pad 10	22.13.10	5754	FL Fwd 3 mon	23.8.15	5806	FL Fwd 4 inv mon	(*)
3720	Pad 11	22.13.11	5756	FL Fwd 4 mon	23.8.16	5808	FL Fwd 5 inv mon	(*)
3722	Pad 12	22.13.12	L_VREF			5810	FL Fwd 6 inv mon	(*)
3724	Pad 13	22.13.13	XXXX (6)			5812	FL Fwd 7 inv mon	(*)
3726	Pad 14	22.13.14	3104	Inertia comp mon	22.3.3	5814	FL Fwd 8 inv mon	(*)
3728	Pad 15	22.13.15	3374	Vf catch out	(*)	3192	Brake open thr mon	(*)
3730	Pad 16	22.13.16	1500	Analog input 1 mon	14.1	(7) the XXXX parameter changes according to the src parameter used:		
6000	Null	(*)	1550	Analog input 2 mon	14.17	2382 Torque ref 1 src		
5008	Test gen out	27.1.5	1600	Analog input 1X mon	14.33	(7) = 2380 Dig torque ref 1	20.12	
5750	FL Fwd 1 mon	23.8.13	1650	Analog input 2X mon	14.44	2492 Vf scale src		
5752	FL Fwd 2 mon	23.8.14	4024	Fieldbus M->S1 mon	23.3.3	(7) = 2490 Dig Vf scale	21.19	
5754	FL Fwd 3 mon	23.8.15	4034	Fieldbus M->S2 mon	23.3.7	3002 Speed ratio src		
5756	FL Fwd 4 mon	23.8.16	4044	Fieldbus M->S3 mon	23.3.11	(7) = 3000 Dig speed ratio	22.1.1	
5758	FL Fwd 5 mon	23.8.17	4054	Fieldbus M->S4 mon	23.3.15	L_WDECOMP		
5760	FL Fwd 6 mon	23.8.18	4064	Fieldbus M->S5 mon	23.3.19	XXXX (8)		
5762	FL Fwd 7 mon	23.8.19	4074	Fieldbus M->S6 mon	23.3.23	3104	Inertia comp mon	22.3.3
5764	FL Fwd 8 mon	23.8.20	4084	Fieldbus M->S7 mon	23.3.27	3374	Vf catch out	(*)
5800	FL Fwd 1 inv mon	(*)	4094	Fieldbus M->S8 mon	23.3.31	1500	Analog input 1 mon	14.1
5802	FL Fwd 2 inv mon	(*)	4104	Fieldbus M->S9 mon	23.3.35	1550	Analog input 2 mon	14.17
5804	FL Fwd 3 inv mon	(*)	4114	Fieldbus M->S10 mon	23.3.39	1600	Analog input 1X mon	14.33
5806	FL Fwd 4 inv mon	(*)	4124	Fieldbus M->S11 mon	23.3.43	1650	Analog input 2X mon	14.45
5808	FL Fwd 5 inv mon	(*)	4134	Fieldbus M->S12 mon	23.3.47	4024	Fieldbus M->S1 mon	23.3.3
5810	FL Fwd 6 inv mon	(*)	4144	Fieldbus M->S13 mon	23.3.51	4034	Fieldbus M->S2 mon	23.3.7
5812	FL Fwd 7 inv mon	(*)						
5814	FL Fwd 8 inv mon	(*)						
(6) the XXXX parameter changes according to the src parameter used:								

PAR	Description	Menu	PAR	Description	Menu	PAR	Description	Menu
4044	Fieldbus M->S3 mon	23.3.11						
4054	Fieldbus M->S4 mon	23.3.15						
4064	Fieldbus M->S5 mon	23.3.19						
4074	Fieldbus M->S6 mon	23.3.23						
4084	Fieldbus M->S7 mon	23.3.27						
4094	Fieldbus M->S8 mon	23.3.31						
4104	Fieldbus M->S9 mon	23.3.35						
4114	Fieldbus M->S10 mon	23.3.39						
4124	Fieldbus M->S11 mon	23.3.43						
4134	Fieldbus M->S12 mon	23.3.47						
4144	Fieldbus M->S13 mon	23.3.51						
4154	Fieldbus M->S14 mon	23.3.55						
4164	Fieldbus M->S15 mon	23.3.59						
4174	Fieldbus M->S16 mon	23.3.63						
3700	Pad 1	22.13.1						
3702	Pad 2	22.13.2						
3704	Pad 3	22.13.3						
3706	Pad 4	22.13.4						
3708	Pad 5	22.13.5						
3710	Pad 6	22.13.6						
3712	Pad 7	22.13.7						
3714	Pad 8	22.13.8						
3716	Pad 9	22.13.9						
3718	Pad 10	22.13.10						
3720	Pad 11	22.13.11						
3722	Pad 12	22.13.12						
3724	Pad 13	22.13.13						
3726	Pad 14	22.13.14						
3728	Pad 15	22.13.15						
3730	Pad 16	22.13.16						
6000	Null	(*)						
5008	Test gen out	27.1.5						
5750	FL Fwd 1 mon	23.8.13						
5752	FL Fwd 2 mon	23.8.14						
5754	FL Fwd 3 mon	23.8.15						
5756	FL Fwd 4 mon	23.8.16						
5758	FL Fwd 5 mon	23.8.17						
5760	FL Fwd 6 mon	23.8.18						
5762	FL Fwd 7 mon	23.8.19						
5764	FL Fwd 8 mon	23.8.20						
5800	FL Fwd 1 inv mon	(*)						
5802	FL Fwd 2 inv mon	(*)						
5804	FL Fwd 3 inv mon	(*)						
5806	FL Fwd 4 inv mon	(*)						
5808	FL Fwd 5 inv mon	(*)						
5810	FL Fwd 6 inv mon	(*)						
5812	FL Fwd 7 inv mon	(*)						
5814	FL Fwd 8 inv mon	(*)						
3192	Brake open thr mon	(*)						

(8) the XXXX parameter changes according to the src parameter used:

4452 Word decomp src

(8) = 4450 Dig word decomp 23.6.1

(*) Parameter not shown on the keypad.
For information see the "PARAMETERS INCLUDED IN SELECTION LISTS BUT NOT SHOWN ON THE KEYPAD" section.

APPENDIX 1.

APP. 1.1 - Use of analog and digital I/Os from the MDPLC programming environment

- The following table shows the internal and variable system parameters for External digital input exp.

DIGITAL INPUT EXP

Name	Type	Description	Unit		R/W
sysEDIBitWord	DWORD	Exp Digital input word Scheme: "Digital Inputs"	Null	1200	R
sysEDIBitWordBit0	BOOL	Exp Digital input 0 (0..1) Scheme: "Digital Inputs"	Null	1210	R
sysEDIBitWordBit1	BOOL	Exp Digital input 1 (0..1) Scheme: "Digital Inputs"	Null	1212	R
sysEDIBitWordBit2	BOOL	Exp Digital input 2 (0..1) Scheme: "Digital Inputs"	Null	1214	R
sysEDIBitWordBit3	BOOL	Exp Digital input 3 (0..1) Scheme: "Digital Inputs"	Null	1216	R
sysEDIBitWordBit4	BOOL	Exp Digital input 4 (0..1) Scheme: "Digital Inputs"	Null	1218	R
sysEDIBitWordBit5	BOOL	Exp Digital input 5 (0..1) Scheme: "Digital Inputs"	Null	1220	R
sysEDIBitWordBit6	BOOL	Exp Digital input 6 (0..1) Scheme: "Digital Inputs"	Null	1222	R
sysEDIBitWordBit7	BOOL	Exp Digital input 7 (0..1) Scheme: "Digital Inputs"	Null	1224	R
SysEDIBitWordBit8	BOOL	Exp Digital input 8 (0..1) Scheme: "Digital Inputs"	Null	5510	R
SysEDIBitWordBit9	BOOL	Exp Digital input 9 (0..1) Scheme: "Digital Inputs"	Null	5512	R
SysEDIBitWordBit10	BOOL	Exp Digital input 10 (0..1) Scheme: "Digital Inputs"	Null	5514	R
SysEDIBitWordBit11	BOOL	Exp Digital input 11 (0..1) Scheme: "Digital Inputs"	Null	5516	R
SysEDIBitWordBit12	BOOL	Exp Digital input 12 (0..1) Scheme: "Digital Inputs"	Null	5518	R
SysEDIBitWordBit13	BOOL	Exp Digital input 13 (0..1) Scheme: "Digital Inputs"	Null	5520	R
SysEDIBitWordBit14	BOOL	Exp Digital input 14 (0..1) Scheme: "Digital Inputs"	Null	5522	R
SysEDIBitWordBit15	BOOL	Exp Digital input 15 (0..1) Scheme: "Digital Inputs"	Null	5524	R
sysExtIODigIn0	DWORD	External expansion digital input 0 This parameter displays the state of external inputs from 0 to 31	Null	5400	R
sysExtIODigIn1	DWORD	External expansion digital input 1 This parameter displays the state of external inputs from 32 to 63	Null	5402	R

- The following table shows the internal and variable system parameters for External analog input exp.

Analog input modules can have a resolution of 12 to 16 bits and scaling may vary from manufacturer to manufacturer.

E.g.:

12-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3	Variant 4
-10V..+10V	-2048..+2047	-32768..+32767	-16384..+16383	
0V..+10V	0..+4095	0..+2047	0..+32767	0..+65535
4..20mA	0..+32767	+6553..+32767	+3276..+16383	

16-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3
-10V..+10V	-32768..+32767		
0V..+10V	0..+65535	0..+32767	
4..20mA			

- There is no single Unit suitable for all models of analog input module.
Check the scaling provided by the model being used and use the system variables accordingly.

ANALOG INPUT EXP

Name	Type	Description	Unit		R/W
sysEAI0	DINT	Exp Analog input 0 Scheme: "Analog Inputs Expansion Card"	$4000H * 2^{16} = 10V$	1600	R
sysEAI1	DINT	Exp Analog input 1 Scheme: "Analog Inputs Expansion Card"	$4000H * 2^{16} = 10V$	1650	R
sysExtIOAnIn0	INT	External expansion analog input 0.	Defined by module builder	5410	R
sysExtIOAnIn1	INT	External expansion analog input 1	Defined by module builder	5412	R
sysExtIOAnIn2	INT	External expansion analog input 2	Defined by module builder	5414	R
sysExtIOAnIn3	INT	External expansion analog input 3	Defined by module builder	5416	R
sysExtIOAnIn4	INT	External expansion analog input 4	Defined by module builder	5418	R
sysExtIOAnIn5	INT	External expansion analog input 5	Defined by module builder	5420	R
sysExtIOAnIn6	INT	External expansion analog input 6	Defined by module builder	5422	R
sysExtIOAnIn7	INT	External expansion analog input 7	Defined by module builder	5424	R

- The following table shows the internal and variable system parameters for External digital output exp.

DIGITAL OUTPUT EXP

Name	Type	Description	Unit		R/W
sysED0BitWord	DWORD	Read only exp digital output word Scheme: "Digital Outputs"	Null	1400	R
sysExtIODigOut0	DWORD	External expansion digital output 0 <i>This parameter displays the state of the external outputs from 0 to 31. The state of digital outputs 0...7 from the MDPLC is not actually available, as it is overwritten by the drive according to the setting of the analog output.</i>	Null	5454	RW
sysExtIODigOut1	DWORD	External expansion digital output 1 <i>This parameter displays the state of the external outputs from 32 to 63.</i>	Null	5456	RW

- The following table shows the internal and variable system parameters for External analog output exp. Analog output modules can have a resolution of 12 to 16 bits and scaling may vary from manufacturer to manufacturer.

E.g.:

12-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3	Variant 4
-10V..+10V	-2048..+2047	-32768..+32767	-16384..+16383	
0V..+10V	0..+4095	0..+2047	0..+16383	0..+32767
4..20mA	0..+32767	+6553..+32767	+3276..+16383	

16-bit module

Signal connected Module configuration	Variant 1	Variant 2	Variant 3
-10V..+10V	-32768..+32767		
0V..+10V	0..+65535	0..+32767	
4..20mA			

- There is no single unit that is suitable for all models of analog output module. Check the scaling provided by the model being used and use the system variables accordingly.

ANALOG OUTPUT EXP

Name	Type	Description	Unit		R/W
sysEA00Value	DINT	Exp Analog Output 0 Value Scheme: "Analog Outputs"	$4000H * 2^{16} = 10V$	1866	R
sysEA01Value	DINT	Exp Analog Output 1 Value Scheme: "Analog Outputs"	$4000H * 2^{16} = 10V$	1868	R
sysExtIOAnaOut0	INT	External expansion analog output 0. <i>This variable is not actually available from the MDPLC. The value written by the MDPLC is overwritten by the drive according to the setting of the analog output.</i>	Defined by module builder	5460	RW
sysExtIOAnaOut1	INT	External expansion analog output 1 <i>This variable is not actually available from the MDPLC. The value written by the MDPLC is overwritten by the drive according to the setting of the analog output.</i>	Defined by module builder	5462	RW
sysExtIOAnaOut2	INT	External expansion analog output 2	Defined by module builder	5464	RW
sysExtIOAnaOut3	INT	External expansion analog output 3	Defined by module builder	5466	RW
sysExtIOAnaOut4	INT	External expansion analog output 4	Defined by module builder	5468	RW
sysExtIOAnaOut5	INT	External expansion analog output 5	Defined by module builder	5470	RW
sysExtIOAnaOut6	INT	External expansion analog output 6	Defined by module builder	5472	RW
sysExtIOAnaOut7	INT	External expansion analog output 7	Defined by module builder	5474	RW

- The state of the communication with the external module can be read directly by the application using the following variable:

DIGITAL OUTPUT EXP

Name	Type	Description	Unit		R/W
sysExtIOstate	BOOL	External expansion state	Null	5484	R

The value is identical to that of parameter 5484 **ExtIO State**, however, the variable is updated immediately in the task.

TRUE when the communication with the module is active. This indicates that the state is Operational and all slave TPDO data have been received correctly at least once.

If not all TPDO data are received in a communication cycle the variable moves to FALSE and alarm “**Opt ExtIO**” [27] is generated.

APP. 1.2 - CANopen protocol support

The drive controls an external I/O module via CANopen, with some master functions, limited to the possibility of managing a single device.

The single slave that is connected must be equipped with CANopen DS301 according to "DS401 Device profile for generic I/O modules Version 3.0.0 3 June 2008" and must be set separately from the drive to operate with a baudrate of 500 kbps, with address 1.

The drive has access to the following objects in the Object Directory of the slave:

. Index	Sub.	Name
0x1000	0	Device type
0x100c	0	Guard time (as an alternative to 0x1016 and 0x1017)
0x100d	0	Lifetime factor
0x1016	0	Consumer HB Object
	1	Cons.HB n+T
0x1017	0	Producer HB time
0x1018	0	Identity Object
	1	Vendor Id
	2	Product Code
0x1400/1/2/3	0	RPDOs Communication Parameters
	1	COB-ID
	2	Transmission type = 1
0x1600/1/2/3	0	RPDOs Mapping
	1-n	Object mapped
0x1800/1/2/3	0	RPDOs Communication Parameters
	1	COB-ID
	2	Transmission type = 1
	3	Inhibit time
0x1A00/1/2/3	0	TPDOs Mapping
	1-n	Object mapped

The slave must preferably support the Heartbeat protocol, or at least NodeGuarding.

If objects 1016 and 1017 are writeable, HeartBeat is used and the 100C and 100D objects are reset, otherwise they are set to 200 and 3, respectively, and the NodeGuarding protocol is active.

The drive interprets the Emergency command as a possible error and so generates an alarm, which is managed in all 3 phases.

The slave must support the NMT protocol for transition to Pre-Operational and Operational.

APP. 1.3 - SDO Configuration Table

The objects requested via SDO in the Config phase are listed in the table below. An error or lack of response generates an alarm with the subcode shown.

SubCode	Index	SubIndex	Notes
1	0x1000	0	Device Type . Must be 401
2	0x1018	0	
3	0x1018	1	Vendor ID
4	0x1018	2	Product Code
5	0x1400	1	RPD01
6	0x1401	1	RPD02
7	0x1402	1	RPD03
8	0x1403	1	RPD04
9	0x1800	1	TPD01
10	0x1801	1	TPD02
11	0x1802	1	TPD03
12	0x1803	1	TPD04
13	0x1600	0..8 Mapping	RPD01 mapping info
14	0x1601	0..8 Mapping	RPD02 mapping info
15	0x1602	0..8 Mapping	RPD03 mapping info
16	0x1603	0..8 Mapping	RPD04 mapping info
17	0x1A00	0..8 Mapping	TPD01mapping info
18	0x1A01	0..8 Mapping	TPD01mapping info
19	0x1A02	0..8 Mapping	TPD01mapping info
20	0x1A03	0..8 Mapping	TPD01mapping info

These objects are written via SDO in the Config phase

SubCode	Index	SubIndex	Notes
21	0x1016	1	HeartBeat consumer rate and Id
22	0x1017	0	HeartBeat producer rate
23	0x100C	0	GuardTime (100 ms or 0 if HeartBeat is supported)
24	0x100D	0	LifeTime period (3 or 0 if HeartBeat is supported)
25	0x1400	1	RPD01 default
26	0x1401	1	RPD02 default
27	0x1402	1	RPD03 default
28	0x1403	1	RPD04default
29	0x1800	1	TPD01 default
30	0x1801	1	TPD03 default
31	0x1802	1	TPD03 default
32	0x1803	1	TPD04 default
33	0x1400	2	RPD01 transmission type
34	0x1400	1	RPD01 enable
35	0x1401	2	RPD03 transmission type
36	0x1401	1	RPD02 enable
37	0x1402	2	RPD03 transmission type
38	0x1402	1	RPD03 enable
39	0x1403	2	RPD03 transmission type
40	0x1403	1	RPD04 enable
41	0x1800	2	TPD01 transmission type
42	0x1800	3	TPD01 inhibit time
43	0x1800	1	TPD01 enable
44	0x1801	2	TPD02 transmission type
45	0x1801	3	TPD02 inhibit time
46	0x1801	1	TPD02 enable
47	0x1802	2	TPD03 transmission type
48	0x1802	3	TPD03 inhibit time
49	0x1802	1	TPD03 enable
50	0x1803	2	TPD04 transmission type
51	0x1803	3	TPD04 inhibit time

SubCode	Index	SubIndex	Notes
52	0x1803	1	TPD04 enable

During the control phase, the system sends a HeartBeat message to the slave every 100 ms and checks the Op state via HeartBeat producer message sent by the device, which must arrive within the time set in object 1017. If an error occurs it returns to Init .

If HeartBeat is not available and NodeGuarding is active instead, the timeout values set in objects 100C and 100D are used.

Among the objects requested during the configuration phase are those which contain the mapping, the meaning of the data in the PDOs. The objects the slave may have mapped in the PDOs are a subset of those defined by the DS401 profile. In particular, the list indicates objects recognised by the drive:

- 6000h Read Input 8 bit
- 6100h ReadInput 16 bit
- 6120h ReadInput 32 bit
- 6200h Write Output 8 bit
- 6300h WriteOutput 16 bit
- 6320h WriteOutput 32 bit
- 6400h ReadAnalog 8 bit
- 6401h ReadAnalog 16 bit
- 6411h WriteAnalog 16 bit

The configuration does not fail if other objects are detected, however the object in the PDO is not managed when received and is written as 0 for transmission.

The objects are associated with the analog and digital input and output parameters in the order they are detected.

For example, if the slave is configured as follows

1600	
1	6200h
2	6200h
1601	
1	6300h
2	6300h

The data sent via RPDO will be associated in this order

Byte 0	Byte1	Byte2	Byte3	Digital out 0Ext mon
↓	↓			
Byte 0	Byte1	Byte2	Byte3	PD01
6200h	6200h	--	--	

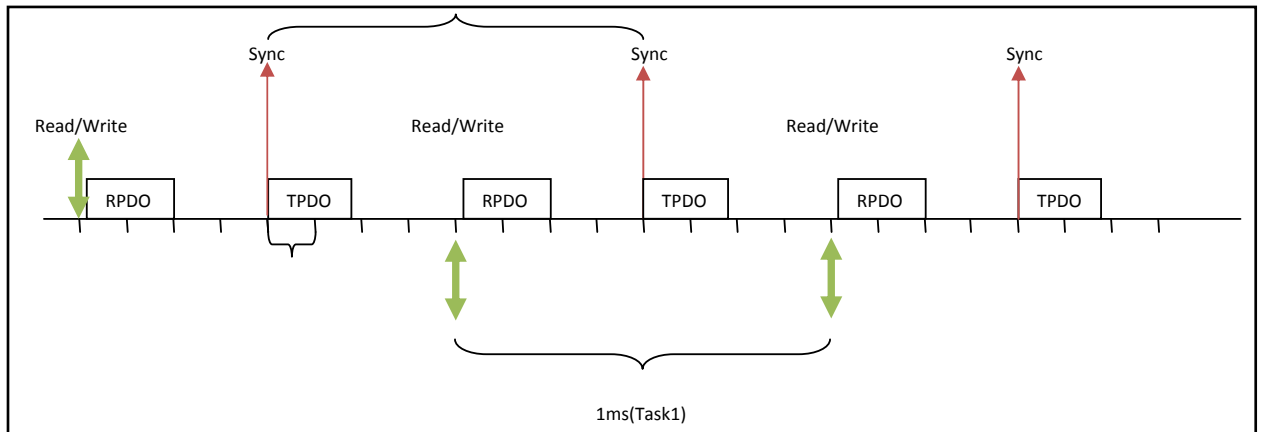
Byte 0	Byte1	Digital out 0Ext mon		
↓	↓			
Byte 0	Byte1	Byte 0	Byte1	Digital out 1Ext mon
↓	↓	↓	↓	
Byte 0	Byte1	Byte2	Byte3	PD01
6200h	6200h	--	--	

Following the transition to Op, the drive software reads and writes the PDOs (RPDO) and moves the data to the I/O control blocks and periodically sends the Sync message.

Since there are only 2 devices in the network and data exchange is predefined, synchronous PDOs are always used to have repeatability in communication.

Data are exchanged in communication cycles, the duration of which is predefined with parameter 5488 "External IO period" (available in the service menu and via the .sco configuration file). The default communication cycle value is 8 ms.

Each communication cycle the block accesses the CAN peripheral device to check the PDOs sent by the slave (TPDOs) and copy these, and then writes the RPDOs to be sent.



Each communication cycle sends a Sync message, to which the slave must immediately reply with its PDOs. If the slave does not send the PDOs this is interpreted as a loss of communication owing to the generation of an “ExtIO fault” alarm and switching of parameter 5484 “External IO state” from Off to On. The loss of communication is detected after a maximum time equal to twice the communication cycle from the last time value data were received.

APP. 1.4 - System variables for MDPLC

System variables in the MDPLC environment for FastLink.

FASTLINK

Name	Type	Description	Unit	PAR	R/W
sysFL_Fw1_mon	DWORD	FastLink Forward 1 monitor Scheme: "Control_FastLink_04"	Null	5750	R
sysFL_Fw2_mon	DWORD	FastLink Forward 2 monitor Scheme: "Control_FastLink_04"	Null	5752	R
sysFL_Fw3_mon	DWORD	FastLink Forward 3 monitor Scheme: "Control_FastLink_04"	Null	5754	R
sysFL_Fw4_mon	DWORD	FastLink Forward 4 monitor Scheme: "Control_FastLink_04"	Null	5756	R
sysFL_Fw5_mon	DWORD	FastLink Forward 5 monitor Scheme: "Control_FastLink_04"	Null	5758	R
sysFL_Fw6_mon	DWORD	FastLink Forward 6 monitor Scheme: "Control_FastLink_04"	Null	5760	R
sysFL_Fw7_mon	DWORD	FastLink Forward 7 monitor Scheme: "Control_FastLink_04"	Null	5762	R
sysFL_Fw8_mon	DWORD	FastLink Forward 8 monitor Scheme: "Control_FastLink_04"	Null	5764	R
sysFL_Fw1_inv_mon	DWORD	FastLink Forward 1 monitor inverted Scheme: "Control_FastLink_04"	Null	5800	R
sysFL_Fw2_inv_mon	DWORD	FastLink Forward 2 monitor inverted Scheme: "Control_FastLink_04"	Null	5802	R
sysFL_Fw3_inv_mon	DWORD	FastLink Forward 3 monitor inverted Scheme: "Control_FastLink_04"	Null	5804	R
sysFL_Fw4_inv_mon	DWORD	FastLink Forward 4 monitor inverted Scheme: "Control_FastLink_04"	Null	5806	R
sysFL_Fw5_inv_mon	DWORD	FastLink Forward 5 monitor inverted Scheme: "Control_FastLink_04"	Null	5808	R
sysFL_Fw6_inv_mon	DWORD	FastLink Forward 6 monitor inverted Scheme: "Control_FastLink_04"	Null	5810	R
sysFL_Fw7_inv_mon	DWORD	FastLink Forward 7 monitor inverted Scheme: "Control_FastLink_04"	Null	5812	R
sysFL_Fw8_inv_mon	DWORD	FastLink Forward 8 monitor inverted Scheme: "Control_FastLink_04"	Null	5814	R
sysFL_Fw5		FastLink Forward 5 Scheme: "Control_FastLink_04"	Null	5578	RW
sysFL_Fw6		FastLink Forward 6 Scheme: "Control_FastLink_04"	Null	5580	RW
sysFL_Fw7		FastLink Forward 7 Scheme: "Control_FastLink_04"	Null	5582	RW
sysFL_Fw8		FastLink Forward 8 Scheme: "Control_FastLink_04"	Null	5584	RW

SYSTEM

Name	Type	Description	Unit		R/W
sysSyncSlaveStatus	DWORD	Stato della sincronizzazione dei Pwm Scheme: "Control_FastLink_04"	Null	5720	R

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