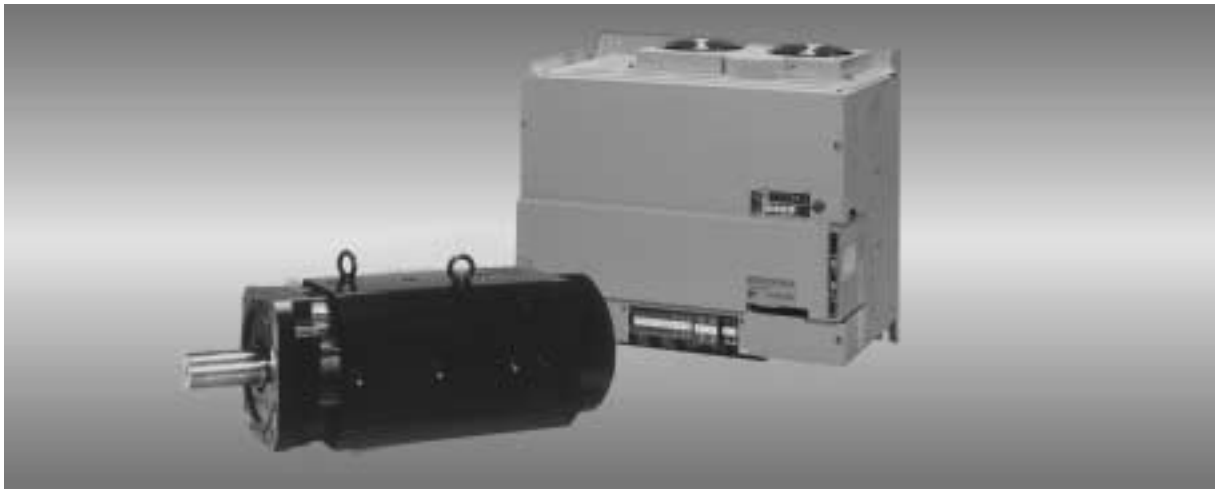
Σ-Ⅱ Series SGMBH/SGDH
USER'S MANUAL

AC Servodrive (400 V, 22 to 55 kW)

SGMBH Servomotor
SGDH SERVOPACK

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YASKAWA

MANUAL NO. SIE-S800-32.4

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About this Manual

■ This manual provides the following information for the Σ-II Series SGMBH/SGDH Servodrives.

- Procedures for installing and wiring the servomotor and SERVOPACK.
- Procedures for trial operation of the Servodrive.
- Procedures for using functions and adjusting the servodrives.
- Procedures for using the built-in Panel Operator and the Hand-held Digital Operator.
- Ratings and specifications for standard models.
- Procedures for maintenance and inspection.

■ Intended Audience

This manual is intended for the following users.

- Those designing Σ-II Series servodrive systems.
- Those installing or wiring Σ-II Series servodrives.
- Those performing trial operation or adjustments of Σ-II Series servodrives.
- Those maintaining or inspecting Σ-II Series servodrives.

■ Description of Technical Terms

In this manual, the following terms are defined as follows:

- Servomotor = Σ-II Series SGMBH servomotor.
- SERVOPACK = Σ-II Series SGDH SERVOPACK.
- Servodrive = A set including a servomotor and Servo Amplifier.
- Servo System = A servo control system that includes the combination of a servodrive with a host computer and peripheral devices.

■ Indication of Reverse Signals

In this manual, the names of reverse signals (ones that are valid when low) are written with a forward slash (/) before the signal name, as shown in the following example:

- $\overline{\text{S-ON}}$ = /S-ON
- $\overline{\text{P-CON}}$ = /P-CON

■ Visual Aids

The following aids are used to indicate certain types of information for easier reference.

IMPORTANT

Indicates important information that should be memorized, including precautions such as alarm displays to avoid damaging the devices.



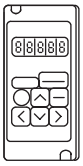
Indicates supplemental information.

◀ EXAMPLE ▶

Indicates application examples.



Indicates definitions of difficult terms or terms that have not been previously explained in this manual.



JUSP-OP02A-2

The text indicated by this icon explains the operating procedure using Hand-held type Digital Operator (Type: JUSP-OP02A-2).

Related Manuals

- Refer to the following manuals as required.
- Also, keep this manual in a safe place so that it can be referred to whenever necessary.

Manual Name	Manual Number	Contents
Σ Series/Σ-II Series Servopacks Personal Computer Monitoring Software Operation Manual	SIE-S800-35	Describes the applications and operation of software for the Σ Series/Σ-II Series servodrive monitoring devices for use on personal computers.
Σ-II Series SGM□H/SGDM Digital Operator Operation Manual	TOE-S800-34	Provides detailed information on the operation of the JUSP-OP02A-2 Digital Operator, which is an optional product.

Safety Information

The following conventions are used to indicate precautions in this manual.

Failure to heed precautions provided in this manual can result in serious or possibly even fatal injury or damage to the products or to related equipment and systems.

⚠ WARNING — Indicates precautions that, if not heeded, could possibly result in loss of life or serious injury.

⚠ CAUTION — Indicates precautions that, if not heeded, could result in relatively serious or minor injury, damage to the product, or faulty operation.

⃠ PROHIBITED — Indicates actions that must never be taken.

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Safety Precautions

The following precautions are for checking products upon delivery, installation, wiring, operation, maintenance and inspections.

■ Checking Products upon Delivery

⚠ CAUTION
• Always use the servomotor and SERVOPACK in one of the specified combinations. Not doing so may cause fire or malfunction.

■ Installation

⚠ CAUTION
• Never use the products in an environment subject to water, corrosive gases, inflammable gases, or combustibles. • Doing so may result in electric shock or fire.

■ Wiring

⚠ WARNING

- Connect the ground terminal ⏚ to electrical codes (ground resistance: 100 Ω or less).

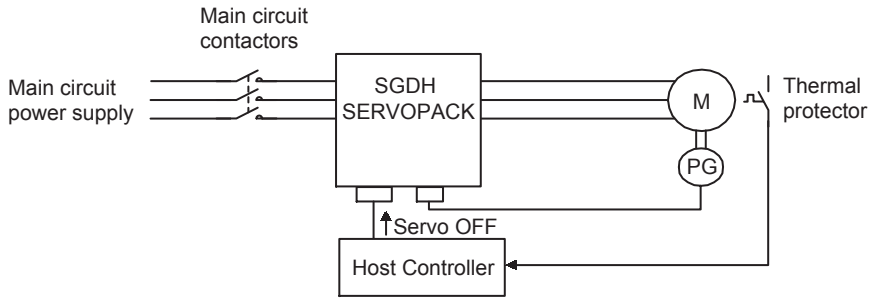
  Improper grounding may result in electric shock or fire.

- Use the thermal protector built into the servomotor according to either of the two following methods.

  SGMBH servomotors are cooled by a fan. If the fan is defective or power to the fan is disconnected, heat from the motor may result in burns or fire.

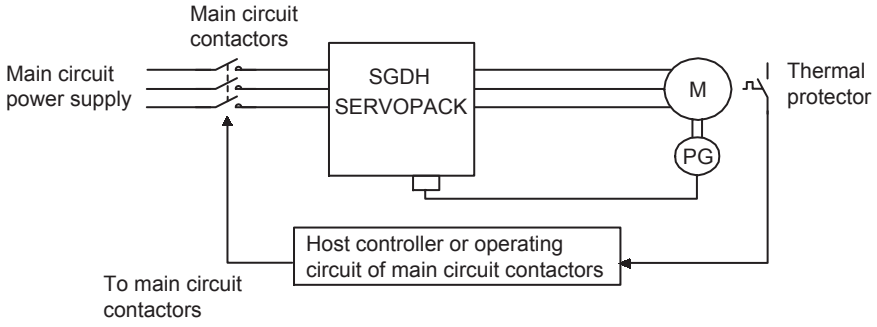
Method 1:

- Wire the output from the thermal protector to the host controller and turn OFF the servo when the thermal protector operates.



Method 2:

- Wire the thermal protector to the operating circuit of the main circuit contactors or the host controller and turn OFF the main circuit when the thermal protector operates.



⚠ CAUTION

- Do not connect a three-phase power supply to the SERVOPACK's U, V, or W output terminals.

  Doing so may result in injury or fire.

- Securely fasten the power supply terminal screws and motor output terminal screws.

  Not doing so may result in fire.

■ Operation

⚠ WARNING

- Never touch any rotating motor parts while the motor is running.

  Doing so may result in injury.

⚠ CAUTION

- Conduct trial operation on the servomotor alone with the motor shaft disconnected from machine to avoid any unexpected accidents.

  Not doing so may result in injury.
- Before starting operation with a machine connected, change the settings to match the parameters of the machine.

  Starting operation without matching the proper settings may cause the machine to run out of control or malfunction.
- Before starting operation with a machine connected, make sure that an emergency stop can be applied at any time.

  Not doing so may result in injury.
- Do not touch the heat sinks during operation.

  Doing so may result in burns due to high temperatures.

■ Maintenance and Inspection

⚠ WARNING

- Never touch the inside of the SERVOPACKs.

  Doing so may result in electric shock.
- Do not remove the panel cover while the power is ON.

  Doing so may result in electric shock.
- Do not touch terminals for five minutes after the power is turned OFF.

  Residual voltage may cause electric shock.

⚠ CAUTION

- Do not disassemble the servomotor.

  Doing so may result in electric shock or injury.
- Do not attempt to change wiring while the power is ON.

  Doing so may result in electric shock or injury.

■ General Precautions

Note the following to ensure safe application.
• The drawings presented in this manual are sometimes shown without covers or protective guards. Always replace the cover or protective guard as specified first, and then operate the products in accordance with the manual. • The drawings presented in this manual are typical examples and may not match the product you received. • This manual is subject to change due to product improvement, specification modification, and manual improvement. When this manual is revised, the manual code is updated and the new manual is published as a next edition. • If the manual must be ordered due to loss or damage, inform your nearest Yaskawa representative or one of the offices listed on the back of this manual. • Yaskawa will not take responsibility for the results of unauthorized modifications of this product. Yaskawa shall not be liable for any damages or troubles resulting from unauthorized modification.

SGDH SERVOPACK Standards and Certification

SGDH SERVOPACKs conform to the following standards. However, because this product is a built-in type, reconfirmation is required after being installed in the final product.

- EN55011 group 1 class A
- EN50082-2

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Appendix A List of Parameters

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1

For First-time Users of AC Servos

This chapter is intended for first–time users of AC servos. It describes the basic configuration of a servo mechanism and basic technical terms relating to servos. Users who already have experience in using a servo should also take a look at this chapter to understand the features of Σ-II Series AC Servos.

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1.1 Basic Understanding of AC Servos

This section describes the basic configuration of a servo mechanism and technical terms relating to servos and also explains the features of Σ-II Series AC Servos.

1.1.1 Servo Mechanisms

You may be familiar with the following terms:

- Servo
- Servo mechanism[1]
- Servo control system

In fact, these terms are synonymous. They have the following meaning:

A control mechanism that monitors physical quantities such as specified positions.

In short, a servo mechanism is like a servant who does tasks faithfully and quickly according to his master's instructions. In fact, "servo" originally derives from the word "servant."

Servo system could be defined in more detail as a mechanism that:

- Moves at a specified speed and
- Locates an object in a specified position

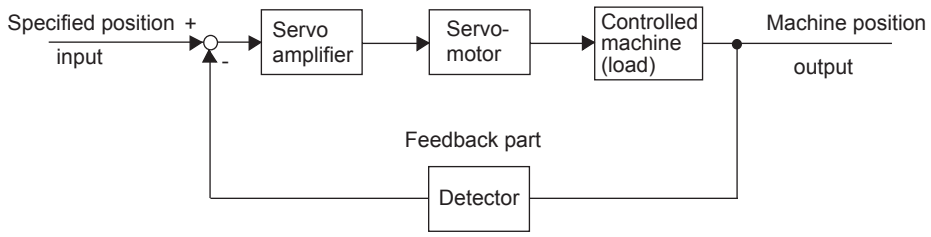


[1] Servo mechanism

According to Japanese Industrial Standard (JIS) terminology, a "servo mechanism" is defined as a mechanism that uses the position, direction, or orientation of an object as a process variable to control a system to follow any changes in a target value (set point). More simply, a servo mechanism is a control mechanism that monitors physical quantities such as specified positions. Feedback control is normally performed by a servo mechanism. (Source: JIS B0181)

To develop such a servo system, an automatic control system involving feedback control[1] must be designed. This automatic control system can be illustrated in the following block diagram:

Configuration of Servo System



This servo system is an automatic control system that detects the machine position (output data), feeds back the data to the input side, compares it with the specified position (input data), and moves the machine by the difference between the compared data.

In other words, the servo system is a system to control the output data to match the specified input data.

If, for example, the specified position changes, the servo system will reflect the changes.

In the above example, input data is defined as a position, but input data can be any physical quantities such as orientation (angle), water pressure, or voltage.

Position, speed, force (torque), electric current, and so on are typical controlled values for a servo system.

TERMS

[1] Feedback control

A control method in which process variables are returned to the input side to form a closed loop. It is also called closed-loop control. If a negative signal is returned to the input side, it is called negative feedback control. Normally, negative feedback control is used to stabilize the system. If feedback is not returned, the control method is called open-loop control.

1.1.2 Technical Terms

The main technical terms used in this manual are as follows:

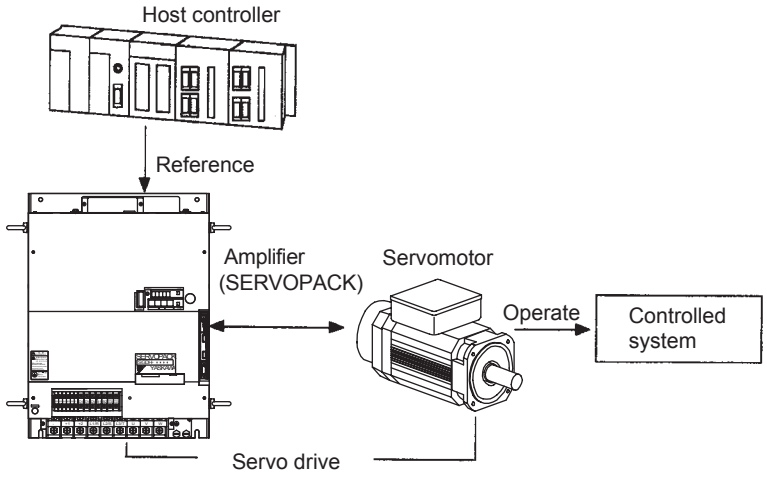
- Servo mechanism
- Servo

  Normally, servo is synonymous with servo mechanism. However, because “mechanism” is omitted, the meaning becomes somewhat ambiguous. Servo may refer to the entire servo mechanism but may also refer to an integral part of a servo mechanism such as a servomotor or a servo amplifier. This manual also follows this convention in the use of the term “servo.”

- Servo control system

  Servo control system is almost synonymous with servo mechanism but places the focus on system control. In this manual, the term “servo system” is also used as a synonym of servo control system.

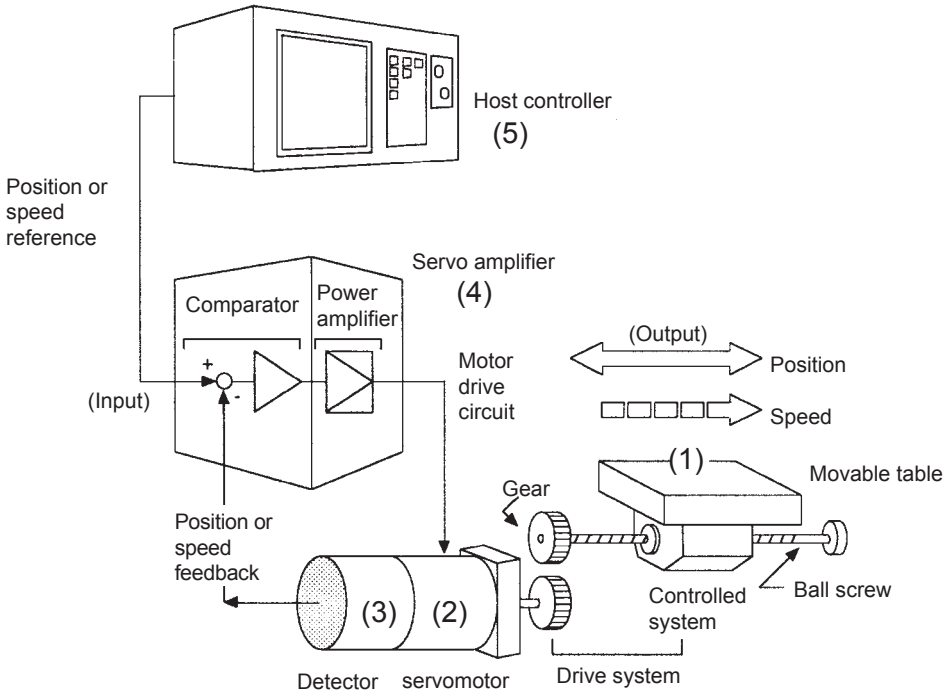
Related Terms	Meaning
Servomotor	General servomotors or Yaskawa SGMBH servomotors. In some cases, a position detector (encoder) is included in a servomotor.
SERVOPACK	Trademark of Yaskawa servo amplifier “SGDH SERVOPACK.”
Servo drive	A servomotor and amplifier pair. Also called “servo.”
Servo system	A closed control system consisting of a host controller, servo drive and controlled system to form a servo mechanism.



Servo system

1.2 Configuration of Servo System

The following diagram illustrates a servo system in detail:



(1) Controlled system: Mechanical system for which the position or speed is to be controlled. This includes a drive system that transmits torque from a servomotor.

(2) Servomotor: A main actuator that moves a controlled system. Two types are available: AC servomotor and DC servomotor.

(3) Detector: A position or speed detector. Normally, an encoder mounted on a motor is used as a position detector.

(4) Servo amplifier: An amplifier that processes an error signal to correct the difference between a reference and feedback data and operates the servomotor accordingly. A servo amplifier consists of a comparator, which processes error signals, and a power amplifier, which operates the servomotor.

(5) Host controller: A device that controls a servo amplifier by specifying a position or speed as a set point.

Servo components (1) to (5) are outlined below:

1. Controlled System

   In the previous figure, the controlled system is a movable table for which the position or speed is controlled. The movable table is driven by a ball screw and is connected to the servomotor via gears. So, the drive system consists of:

• Gears + Ball Screw

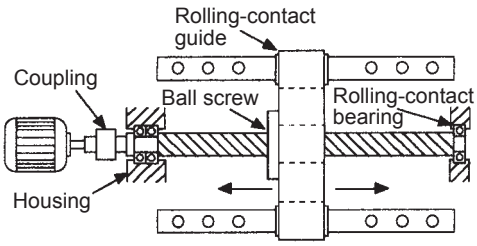
  This drive system is most commonly used because the power transmission ratio (gear ratio) can be freely set to ensure high positioning accuracy. However, play in the gears must be minimized.

  The following drive system[1] is also possible when the controlled system is a movable table:

• Coupling + Ball Screw

  When the power transmission ratio is 1 : 1, a coupling is useful because it has no play.

  This drive system is widely used for machining tools.

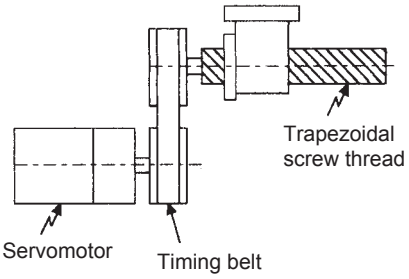


• Timing Belt + Trapezoidal Screw Thread

  A timing belt is a coupling device that allows the power transmission ratio to be set freely and that has no play.

  A trapezoidal screw thread does not provide excellent positioning accuracy, so can be treated as a minor coupling device.

  To develop an excellent servo system, it is important to select a rigid drive system that has no play.



  Configure the controlled system by using an appropriate drive system for the control purpose.

TERMS

[1] Drive system

Also called a drive mechanism. A drive system connects an actuator (such as a servomotor) to a controlled system and serves a mechanical control component that transmits torque to the controlled system, orientates the controlled system, and converts motion from rotation to linear motion and vice versa.

2. Servomotor

• DC Servomotor and AC Servomotor

Servomotors are divided into two types: DC servomotors and AC servomotors.

DC servomotors are driven by direct current (DC). They have a long history. Up until the 1980s, the term "servomotor" used to imply a DC servomotor.

From 1984, AC servomotors were emerging as a result of rapid progress in microprocessor technology. Driven by alternating current (AC), AC servomotors are now widely used because of the following advantages:

- Easy maintenance: No brush
- High speed: No limitation in rectification rate

Note however that servomotors and SERVOPACKs use some parts that are subject to mechanical wear or aging. For preventive maintenance, inspect and replace parts at regular intervals. For details, refer to *Chapter 8 Inspection, Maintenance, and Troubleshooting*.

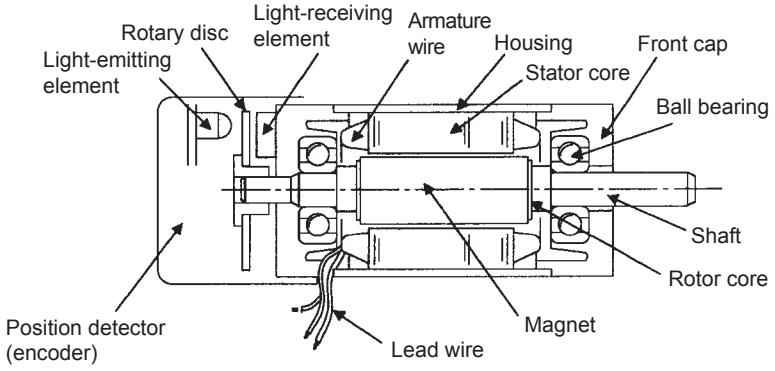
• AC Servomotor

AC servomotors are divided into two types: Synchronous type and induction type. The synchronous type is more commonly used.

For a synchronous type servomotor, motor speed is controlled by changing the frequency of alternating current.

A synchronous type servomotor provides strong holding torque when stopped, so this type is ideal when precise positioning is required. Use this type for a servo mechanism for position control.

The following figure illustrates the structure of a synchronous type servomotor:



Yaskawa SGMBH servomotors are of the synchronous type.

• Performance of Servomotor

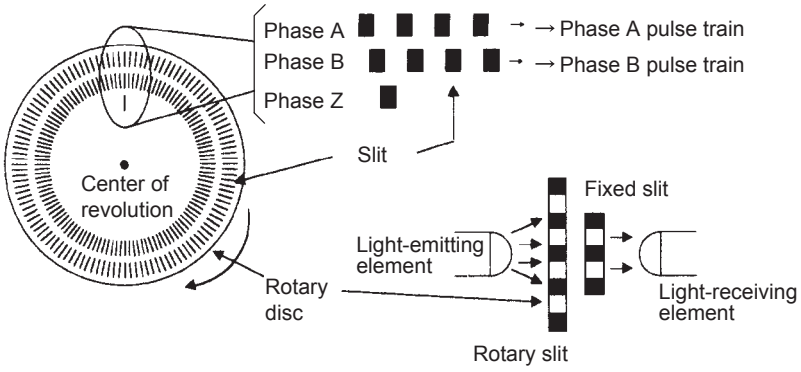
A servomotor must have "instantaneous power" so that it can start as soon as a start reference is received. The term "power rating (kW/s)" is used to represent instantaneous power. It refers to the electric power (kW) that a servomotor generates per second. The greater the power rating, the more powerful the servomotor.

3. Detector

A servo system requires a position or speed detector. It uses an encoder mounted on a servomotor for this purpose. Encoders are divided into the following two types:

• Incremental Encoder

An incremental encoder is a pulse generator, which generates a certain number of pulses per revolution (e.g., 2,000 pulses per revolution). If this encoder is connected to the mechanical system and one pulse is defined as a certain length (e.g., 0.001 mm), it can be used as a position detector. However, this encoder does not detect an absolute position and merely outputs a pulse train. Hence zero point return operation must be performed before positioning. The following figure illustrates the operation principle of a pulse generator:



• Absolute Encoder

An absolute encoder is designed to detect an absolute angle of rotation as well as to perform the general functions of an incremental encoder. With an absolute encoder, therefore, it is possible to create a system that does not require zero point return operation at the beginning of each operation.

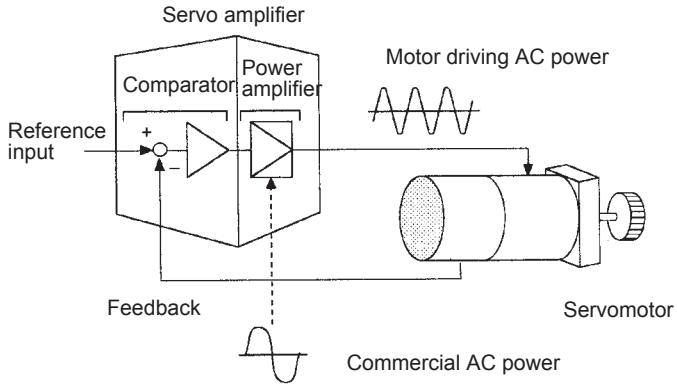
• Difference between an Absolute and Incremental Encoder

An absolute encoder will keep track of the motor shaft position even if system power is lost and some motion occurs during that period of time. The incremental encoder is incapable of the above.

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4. Servo Amplifier

A servo amplifier is required to operate an AC servomotor. The following figure illustrates the configuration of a servo amplifier:



A servo amplifier consists of the following two sections:

- Comparator

A comparator consists of a comparison function and a control function. The comparison function compares reference input (position or speed) with a feedback signal and generates a differential signal.

The control function amplifies and transforms the differential signal. In other words, it performs proportional (P) control or proportional/integral (PI) control[1]. (It is not important if you do not understand these control terms completely at this point.)

- Power Amplifier

A power amplifier runs the servomotor at a speed or torque proportional to the output of the comparator. In other words, from the commercial power supply of 50/60 Hz, it generates alternating current with a frequency proportional to the reference speed and runs the servomotor with this current.

5. Host Controller

A host controller controls a servo amplifier by specifying a position or speed as a set point.

For speed reference, a position control loop may be formed in the host controller when a position feedback signal is received. Yaskawa machine controller MP920 is a typical host controller.

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[1] Proportional/integral (PI) control

PI control provides more accurate position or speed control than proportional control, which is more commonly used.

1.3 Features of Σ-II Series Servos

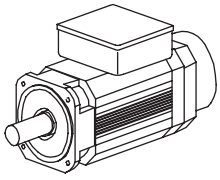
A Σ-II Series Servo consists of an SGMBH servomotor and an SGDH SERVOPACK.

1.3.1 Outline

This section outlines SGMBH servomotor types and the control types of SGDH SERVOPACKs.

■ SGMBH Servomotor Type

Σ-II Series SGMBH servomotors are synchronous type servomotors and have the following features:

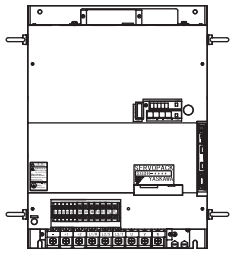


SGMBH Servomotor

Rated Motor Speed Maximum Motor Speed	Voltage	Maximum Torque	Rated Output
1500 min^{-1} 2000 min^{-1}	400 V	200 %	22 to 55 kW (10 models)

■ Control Types of SGDH SERVOPACK

SGDH SERVOPACKs allow the control of speed, position and torque.



SGDH SERVOPACK

Speed Control (Analog Reference)

Accepts an analog voltage speed reference.

Position Control (Pulse Reference)

Accepts a pulse train position reference.

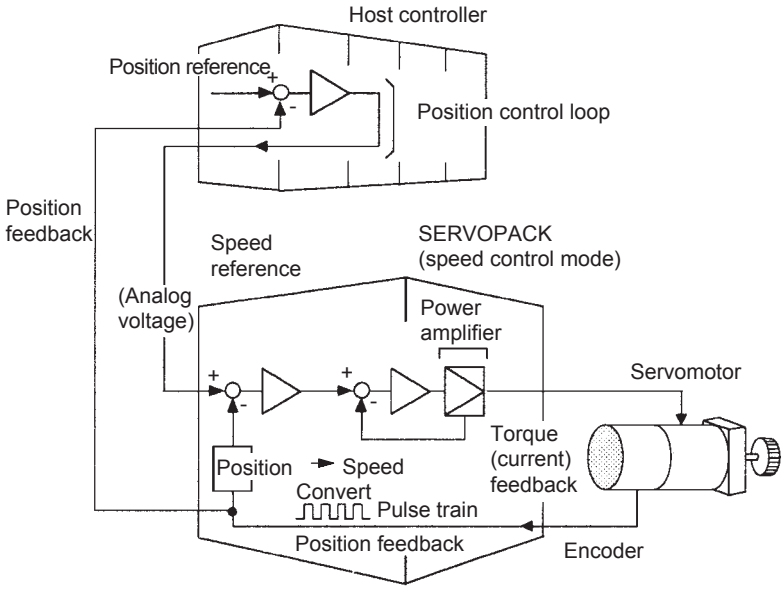
Torque Control (Analog Reference)

Accepts an analog voltage torque reference.

1.3.2 Using the SGDH SERVOPACK

■ Using the SERVOPACK for Speed Control

The most common use of a SERVOPACK for speed control is shown below:



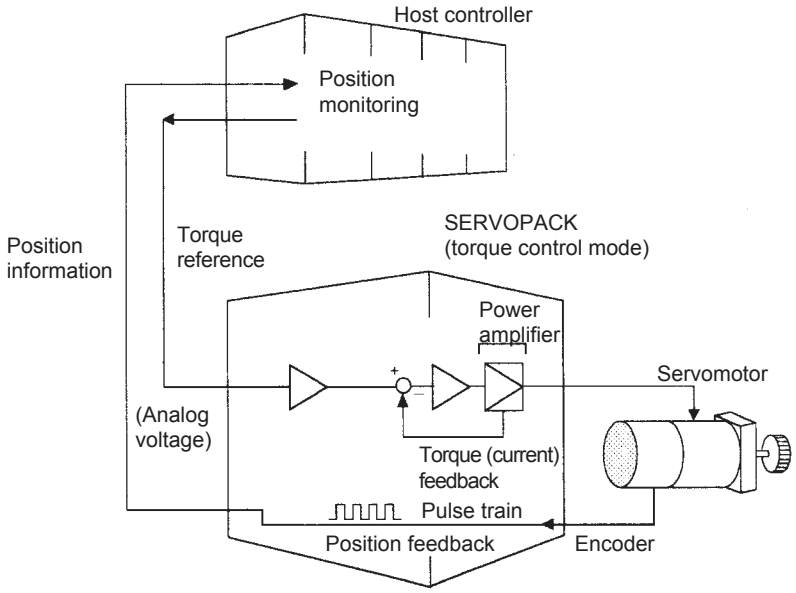
As shown in the above figure, a position control loop is formed in the host controller. The host controller compares a position reference with a position feedback signal and sends the processed result to the SERVOPACK as a speed reference.

In this way the host controller can be freed from performing the servo mechanism control. The SERVOPACK undertakes the speed control loop and subsequent control processing.

The Yaskawa machine controller MP920 is used as a typical host controller.

■ Using the SERVOPACK for Torque Control

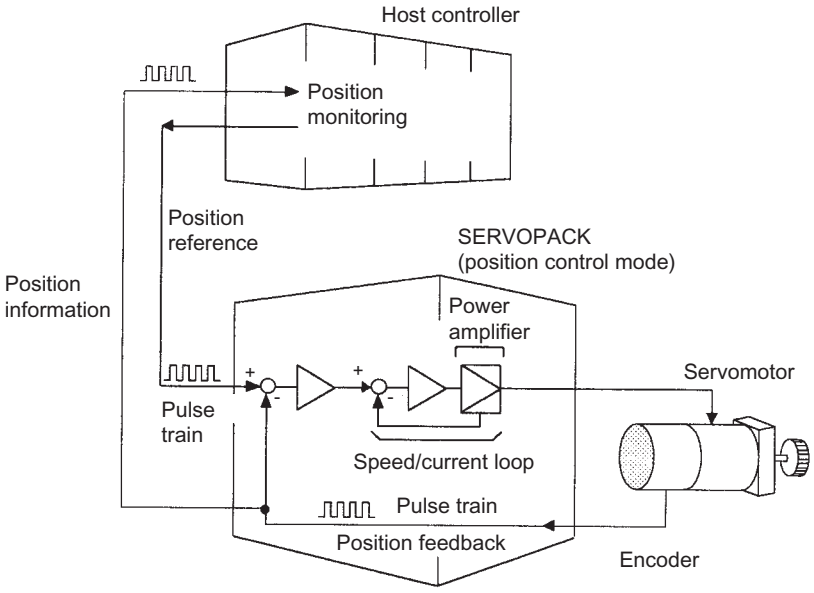
The SERVOPACK can be used for torque control as shown below.



The host controller outputs a torque reference to control the SERVOPACK. It also receives a pulse train (position information) from the SERVOPACK and uses it to monitor the position.

■ Using the SERVOPACK for Position Control

The SERVOPACK can be used for position control as shown below.



The host controller can send a position reference (pulse train) to the SERVOPACK to perform positioning or interpolation. This type of SERVOPACK contains a position control loop.

Parameters can be used to select either of the following pulse trains:

- Sign + pulse train
- Two-phase pulse train with 90° phase difference
- Forward and reverse pulse trains

The host controller receives a pulse train (position information) from the SERVOPACK and uses it to monitor the position.

■ Parameter Setting

A Digital Operator can be used to set parameters for a SERVOPACK as follows:

- Setting parameters to enable or disable each function
- Setting parameters required for functions to be used

Set parameters according to the servo system to be set up.

2

Basic Operation

This chapter describes the first things to do when Σ-II Series products are delivered. It also explains the most fundamental ways of connecting and operating Σ-II Series products. Both first-time and experienced servo users **must read** this chapter.

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2.2 Installation ---------- 2-5

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2.1 Precautions

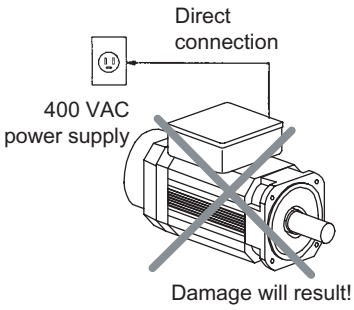
This section provides notes on using Σ-II Series products.

■ Use a 400-VAC power supply.

Use a 400-VAC power supply.

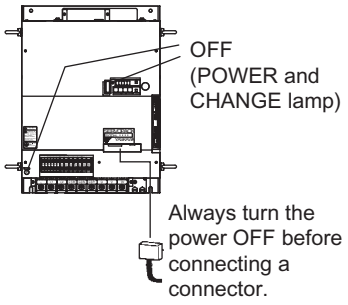
■ Do not connect the servomotor directly to a commercial power line.

Direct connection to the power frequency supply will damage the servomotor. The servomotor cannot be operated without an SGDH SERVOPACK.



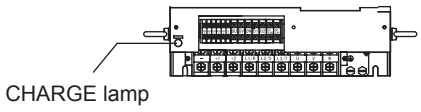
■ Do not change wiring when power is ON.

Always turn the power OFF before connecting or disconnecting a connector. (Except for Digital Operator (Model: JUSP-OP02A-2))



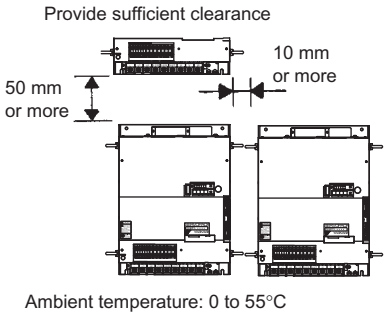
■ Before inspecting, always wait 5 minutes after turning power OFF.

Even after the power is turned OFF, residual electric charge still remains in the capacitor inside the SERVOPACK. To prevent an electric shock, always wait for the CHARGE lamp to go OFF before starting inspection (if necessary).



■ Always follow the specified installation method.

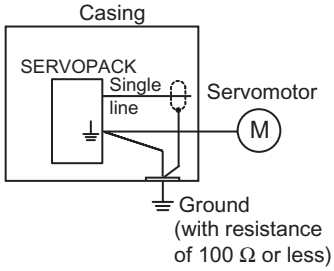
When installing SERVOPACKs side by side as shown in the figure on the right, allow at least 10 mm (0.39 in) between and at least 50 mm (1.97 in) above and below each SERVOPACK. The SERVOPACK generates heat. Install the SERVOPACK so that it can radiate heat freely. Note also that the SERVOPACK must be in an environment free from condensation, vibration and shock.



■ Perform noise reduction and grounding properly.

If the signal line is noisy, vibration or malfunction will result.

- Separate high-voltage cables from low-voltage cables.
- Use cables as short as possible.
- Perform the grounding with the ground resistance of 100 Ω or less for the servomotor and SERVOPACK.
- Never use a line filter for the power supply in the motor circuit.



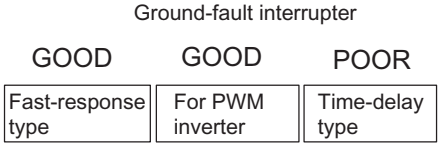
■ Conduct a voltage resistance test under the following conditions.

- Voltage: 1500 Vrms AC, one minute
- Current limit: 100 mA
- Frequency: 50/60 Hz
- Voltage application points: Between 480 V, 460 V, 440 V, 400 V, 380 V, 0 V terminals, L1/R, L2/S, L3/T terminals, and frame ground (connect terminals securely).

Contact your Yaskawa representative before applying voltage to points not specified above, e.g., when performing standards certification tests.

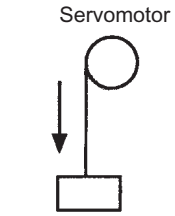
■ Use a fast-response type ground-fault interrupter.

For a ground-fault interrupter, always use a fast-response type or one designed for PWM inverters. Do not use a time-delay type.



■ Do not perform continuous operation under overhanging load.

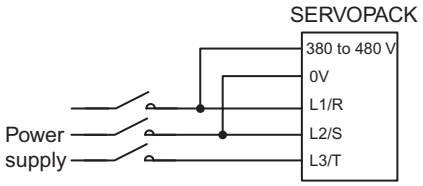
Continuous operation cannot be performed by rotating the motor from the load and applying regenerative braking. Regenerative braking by the SERVOPACK can be applied only for a short period, such as the motor deceleration time.



Do not apply regenerative braking continuously.

■ The servomotor cannot be operated by turning the power ON and OFF.

Frequently turning the power ON and OFF causes the internal circuit elements to deteriorate. Always start or stop the servomotor by using reference pulses.



Do not start or stop by tuning power ON and OFF.

2.2 Installation

This section describes how to check Σ-II Series products on delivery and how to install them.

2.2.1 Checking on Delivery

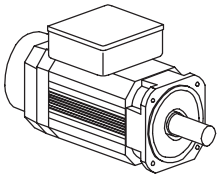
Check the following items when Σ-II Series products are delivered.

Check Items	Comments
Are the delivered products the ones that were ordered?	Check the model numbers marked on the nameplates of the servomotor and SERVOPACK. (See the following.)
Does the servomotor shaft rotate smoothly?	The servomotor shaft is normal if it can be turned smoothly by hand. Servomotors with brakes, however, cannot be turned manually.
Is there any damage?	Check the overall appearance, and check for damage or scratches that may have occurred during shipping.
Are there any loose screws?	Check screws for looseness using a screwdriver.

If any of the above items are faulty or incorrect, contact your Yaskawa sales representative or the dealer from whom you purchased the products.

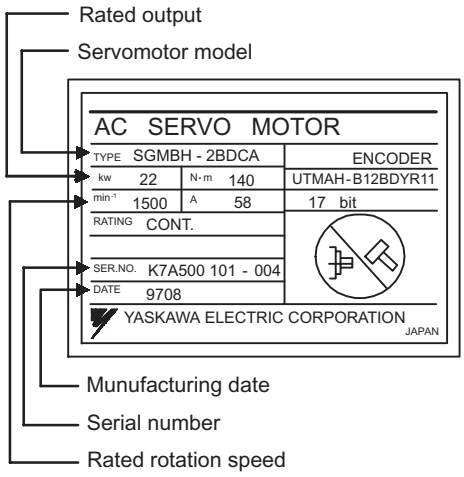
■ Servomotors

External Appearance and Nameplate Examples



SGMBH
servomotor

(Example)



Model Numbers

SGMBH - 2B D C A □ □

Σ-II Series
Servomotor

Servomotor Capacity
2B: 22 kW 4E: 45 kW
3Z: 30 kW 5E: 55 kW
3G: 37 kW

Supply Voltage
D: 400 V

Encoder Specifications
2: 17-bit absolute encoder
3: 20-bit absolute encoder (optional)
C: 17-bit incremental encoder

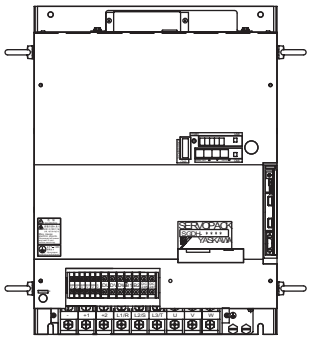
Design Revision Order
A: Maximum torque 200%

Options
1: With V-type oil seal
B: With V-type oil seal, 90-VDC holding brake
C: With V-type oil seal, 24-VDC holding brake
S: With S-type oil seal
D: With S-type oil seal, 90-VDC holding brake
E: With S-type oil seal, 24-VDC holding brake

Shaft End Specifications
2: Flange mounted, straight without key
6: Flange mounted, straight with key and tap
K: With foot, straight without key
L: With foot, straight with key and tap

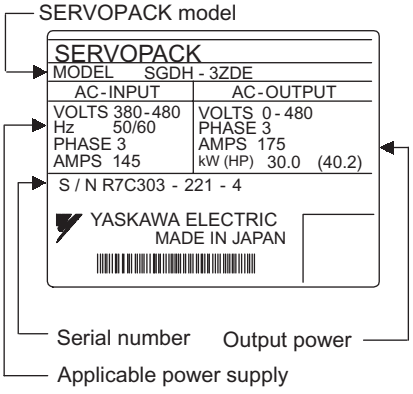
■ SERVOPACKs

External Appearance and Nameplate



Σ-II Series SGDH
SERVOPACK

(Example)



Model Numbers

SGDH - 2B D E

Σ-II Series
SGDH SERVOPACK

Rated Output (motor capacity)
2B: 22 kW 4E: 45 kW
3Z: 30 kW 5E: 55 kW
3G: 37 kW

Supply Voltage
D: 400 V

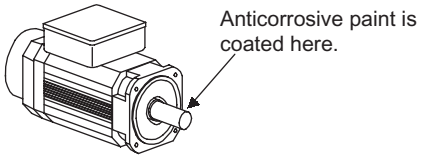
Model
E: For speed/torque control and position control

2.2.2 Installing the Servomotor

SGMBH servomotors can be installed either horizontally or vertically. The service life of the servomotor will be shortened or unexpected problems will occur if the servomotor is installed incorrectly or in an inappropriate location. Always observe the following installation instructions.

■ Prior to Installation

The end of the motor shaft is coated with anticorrosive paint. Thoroughly remove the paint using a cloth moistened with thinner prior to installation.



IMPORTANT

Avoid getting thinner on other parts of the servomotor when cleaning the shaft.

■ Storage Temperature

Store the servomotor within the following temperature range if it is stored with the power cable disconnected.
Between -20 to 60 °C.

■ Installation Site

SGMBH servomotors are designed for indoor use. Install the servomotor in environments that satisfy the following conditions.

- Free of corrosive or explosive gases.
- Well-ventilated and free of dust and moisture.
- Ambient temperature of 0 to 40 °C.
- Relative humidity of 20% to 80% (non-condensing)
- Facilitates inspection and cleaning.
- Altitude : 1000 m max.

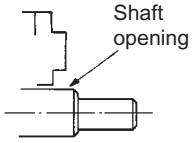
Install a protective cover over the servomotor if it is used in a location that is subject to water or oil mist. Also use a servomotor with an oil seal to seal the through shaft[1] section.

Install the electrical connector with the cable facing downward or in a horizontal position.

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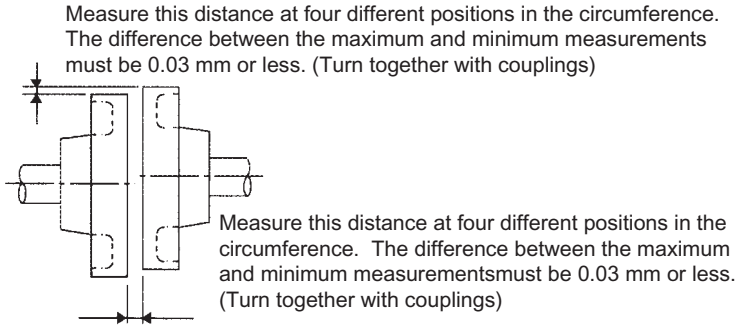
[1] Through Sections of the shaft

This refers to the gap where the shaft protrudes from the end of the motor.



■ Alignment

Align the shaft of the servomotor with that of the equipment to be controlled, then connect the shafts with flexible couplings. Install the servomotor so that alignment accuracy falls within the following range.



IMPORTANT

1. Vibration that will damage the bearings will occur if the shafts are not properly aligned.
2. Do not allow direct impact to be applied to the shafts when installing the coupling. Otherwise the encoder mounted on the opposite end of the shaft may be damaged.
3. Before mounting the pinion gear directly to the motor output shaft, consult your Yaskawa sales representative.

■ Wiring the Servomotor Power Lines

Connect the servomotor power lines (U, V, and W) to the servomotor terminal block (M10) in the servomotor terminal box. Connect the ground wire to the ground screw in the terminal box.

■ Wiring the Servomotor Thermostat

The servomotor has a built-in thermostat. Wire the thermostat leads (l, lb) to the terminal block (M4) in the servomotor's terminal box.

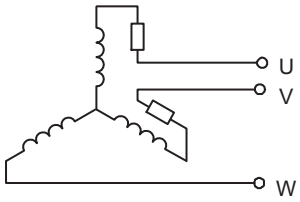
■ Wiring the Servomotor Fan

Wire the servomotor fan leads U(A), V(B), and W(C) so that the direction of air flows according to the following diagram. If the air flows in the opposite direction, change the wiring of any of the two phases U, V, and W.



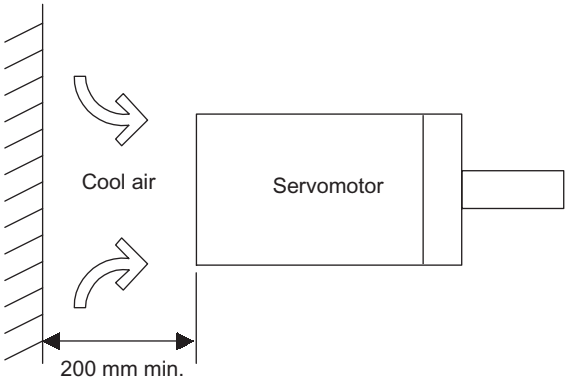
■ Protecting the Servomotor Fan

The servomotor fan has a built-in thermal protector, as shown in the following diagram, that operates at 140°C ±5 %. To protect the servomotor fan from overcurrent, use with a 2-A no-fuse breaker.



■ Installing the Servomotor Fan

To maximize the cooling capacity of the servomotor fan, install the fan at least 200 mm (7.87 in) from the inlet side of the servomotor as shown in the following diagram.



■ Servomotor Connector Specifications

- Encoder Connector at Servomotor

  The connector specifications for the encoder on the servomotor are as follows:

Encoder Connectors			
Plug		Cable Clamp	Receptacle *1
L-shaped	Straight		
JA08A-20-29S-JA-EB *2, *3 or MS3108B20-29S	JA06A-20-29S-J1-EB *2, *3 or MS3106B20-29S	JL04-2022CKE (**) *2, *3 or MS3057-12A ** indicates the cable diameter.	97F-3102E20-29P *3

To be prepared by the customer

* 1. Connector at servomotor is already provided.
* 2. Manufactured by Japan Aviation Electronics Industry, Ltd.
* 3. Waterproof.

• Fan Connector on Servomotor

The connector specifications for the fan on the servomotor are as follows:

Fan Connectors			
Plug		Cable Clamp	Receptacle *1
L-shaped	Straight		
CE05-8A18-10SD-B-BAS *2, *3 or MS3108B18-10S	CE05-6A18-10SD-B-BSS *2, *3 or MS3106B18-10S	CE3057-10A-* (D265) *2, *3 or MS3057-10A ** indicates the cable diameter.	CE05-2A18-10PD-B *3

To be prepared by the customer

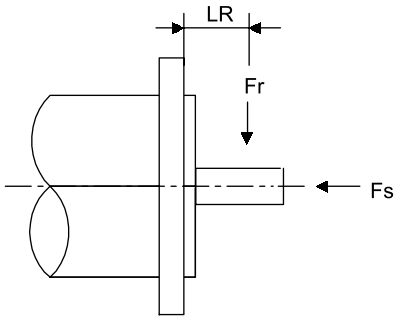
* 1. Connector at servomotor is already provided.
* 2. Manufactured by Daiichi Denshi Kogyo Co., Ltd.
* 3. Waterproof.

2.2.3 Allowable Radial and Thrust Loads

Design the mechanical system so radial and thrust loads[1] applied to the servomotor shaft end during operation falls within the ranges shown in the following table.

Servomotor Model SGMBH-	Allowable Radial Load Fr [N]	Allowable Thrust Load Fs [N]	LR [mm]
2BD□□	5880	2156	100
3ZD□□	6272	2156	100
3GD□□	7448	2156	100
4ED□□	7840	2156	100
5ED□□	8428	2156	110

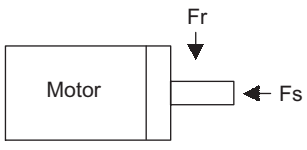
Note: Allowable radial and thrust loads shown above are the maximum values that could be applied to the shaft end from motor torque or other loads.



TERMS

[1] Radial and thrust loads

Thrust load (Fs): Load applied parallel to the centerline of the shaft.
Radial load (Fr): Load applied perpendicular to the centerline of the shaft.



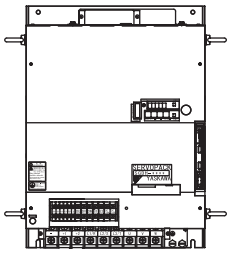
2.2.4 Installing the SERVOPACK

The SGDH SERVOPACK is a base-mounting servo controller. Incorrect installation will cause problems. Always observe the installation instructions below.

■ Storage Temperature

Store the servomotor within the following temperature range if it is stored with the power cable disconnected.

Between -20 to +85 °C.



SGDH SERVOPACK

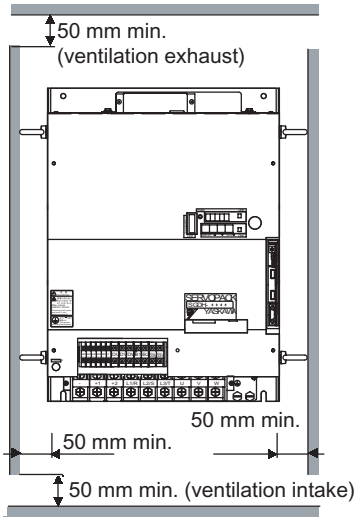
■ Installation Site

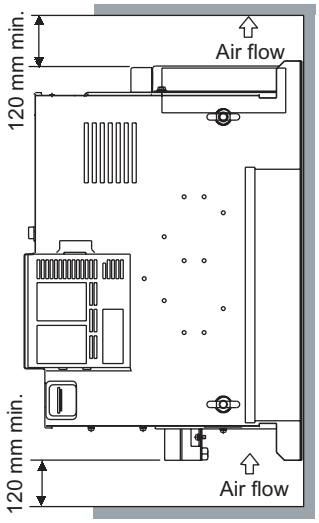
Take the following precautions at the installation site.

Situation	Notes on Installation
Installation in a Control Panel	Design the control panel size, unit layout, and cooling method so the temperature around the SERVOPACK does not exceed 55°C.
Installation Near a Heating Unit	Minimize heat radiated from the heating unit as well as any temperature rise caused by natural convection so the temperature around the SERVOPACK does not exceed 55°C.
Installation Near a Source of Vibration	Install a vibration isolator beneath the SERVOPACK to avoid subjecting it to vibration.
Installation at a Site Exposed to Corrosive Gas	Take appropriate action to avoid corrosive gas. Corrosive gas does not have an immediate effect on the SERVOPACK, but will eventually cause electronic components and contactor-related devices to malfunction.
Other Situations	Do not install the SERVOPACK in hot and humid locations or locations subject to excessive dust or iron powder in the air.

■ Orientation

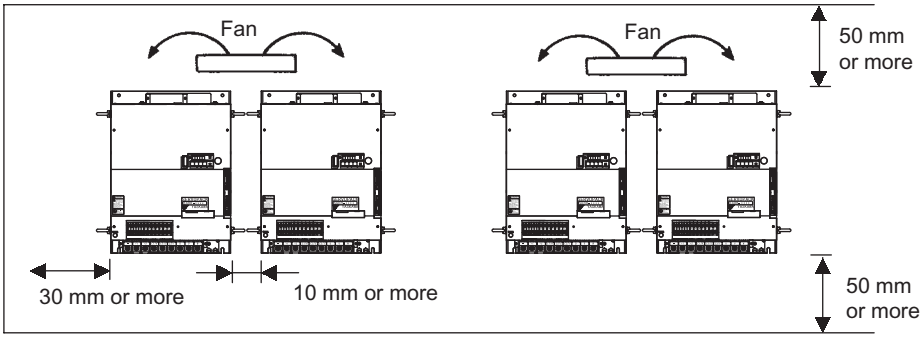
Install the SERVOPACK perpendicular to the wall as shown in the figure.





■ Installation

Follow the procedure below to install multiple SERVOPACKs side by side in a control panel.



SERVOPACK Orientation

Install the SERVOPACK perpendicular to the wall so the front panel containing connectors faces outward.

Cooling

As shown in the figure above, allow sufficient space around each SERVOPACK for cooling by cooling fans or natural convection.

Side-by-side Installation

When installing SERVOPACKs side by side as shown above, allow at least 10mm (0.39 in) between and at least 50mm (1.97 in) above and below each SERVOPACK. Install cooling fans above the SERVOPACKs to avoid excessive temperature rise and to maintain even temperature inside the control panel.

Environmental Conditions in the Control Panel

- Ambient Temperature: 0 to 55 °C
- Humidity: 90% RH or less
- Vibration: 4.9 m/s^2
- Condensation and Freezing: None
- Ambient Temperature for Long-term Reliability: 45°C max.

2.2.5 Power Loss

Power loss of SERVOPACK is given below:

SERVOPACK Model SGDH-	Output Current (Effective Value) [A]	Main Circuit Power Loss [W]	Control Circuit Power Loss [W]	Total Power Loss [W]
2BDE	60	650	120	770
3ZDE	88	970		1090
3GDE	105	1140		1260
4EDE	135	1440		1560
5EDE	160	1720		1840

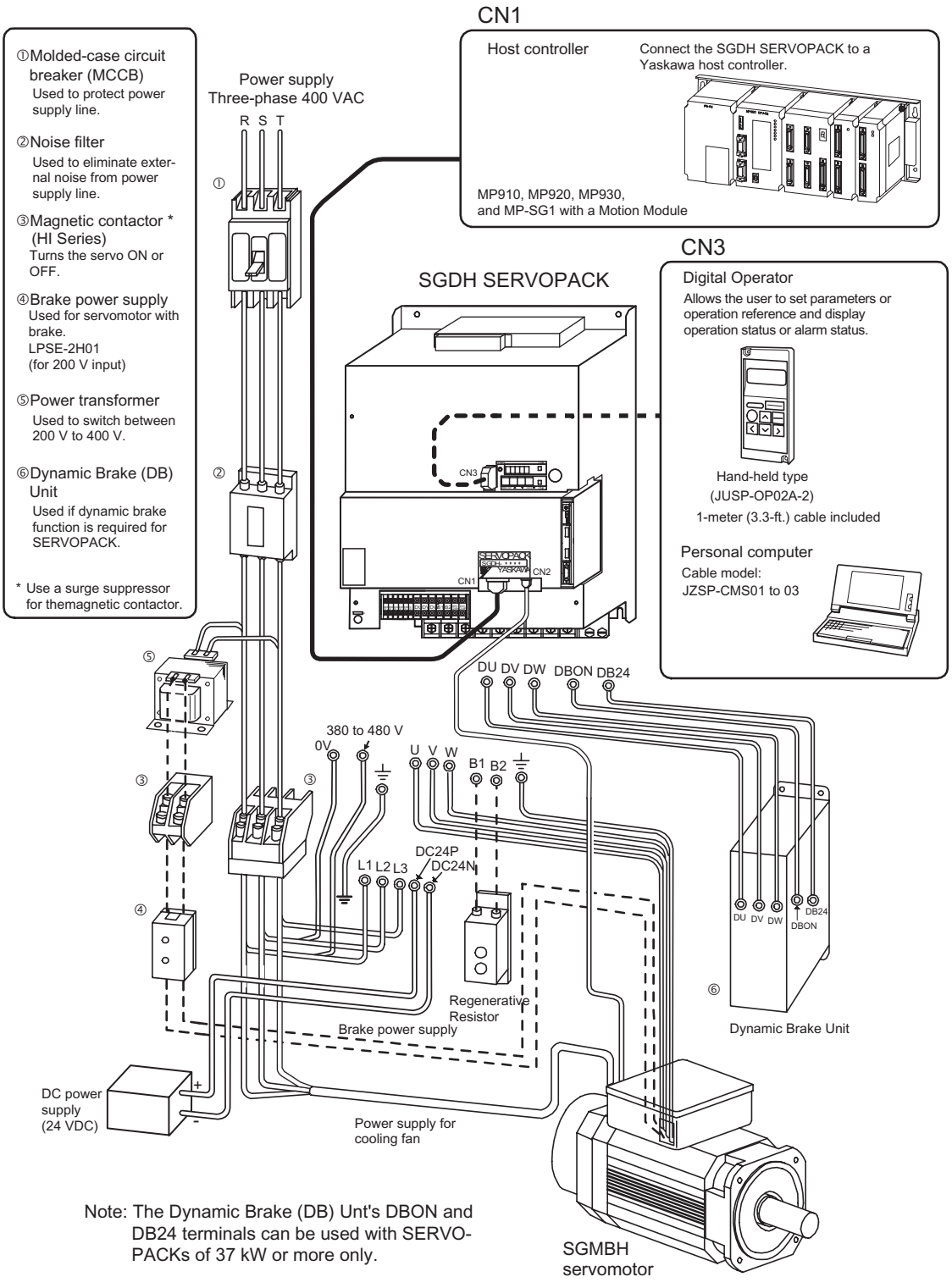
2.3 Connection and Wiring

This section describes how to connect Σ-II Series products to peripheral devices and explains a typical example of wiring the main circuit. It also describes an example of connecting to main host controllers.

2.3.1 Connecting to Peripheral Devices

This section shows a standard example of connecting Σ-II Series products to peripheral devices and briefly explains how to connect to each peripheral device.

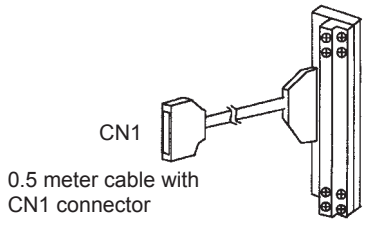
■ 400 V Series



Note: The Dynamic Brake (DB) Unt's DBON and DB24 terminals can be used with SERVOPACKs of 37 kW or more only.

■ Connector terminal block converter unit (Model: JUSP-TA50P)

The terminal block allows connection to a host controller.

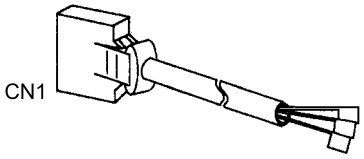


■ Cable with CN1 connector and one end without connector

1m (3.3ft): JZSP-CKI01-1

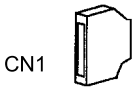
2m (6.6ft): JZSP-CKI01-2

3m (9.8ft): JZSP-CKI01-3



■ CN1 connector kit

Model: JZSP-CKI9



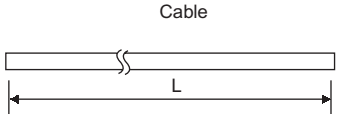
■ Cable for PG

This cable is used to connect the encoder of servomotor to the SERVOPACK.

The following cables are available according to encoder types.

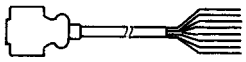
- Cable only (without connector at either end)

Cable Type	Cable Model	Length	Remarks
Standard Encoder Cable	JZSP-CMP09-05	5 m (196.85 in)	The maximum allowable cable length is 20 m.
	JZSP-CMP09-10	10 m (393.70 in)	
	JZSP-CMP09-15	15 m (590.55 in)	
	JZSP-CMP09-20	20 m (787.40 in)	
50-m Specifications Encoder Cable	JZSP-CMP19-30	30 m (1181.10 in)	The maximum allowable cable length is 50 m.
	JZSP-CMP19-40	40 m (1574.80 in)	
	JZSP-CMP19-50	50 m (1968.50 in)	



• Cable with a single connector (without connector on encoder end)

Cable Model	Length
JZSP-CMP03-03	3 m (118.11 in)
JZSP-CMP03-05	5 m (196.85 in)
JZSP-CMP03-10	10 m (393.70 in)
JZSP-CMP03-15	15 m (590.55 in)
JZSP-CMP03-20	20 m (787.40 in)



• Cable with connectors on both ends (straight plug on encoder end)

Applicable Servomotors		Cable Model	Length
SGMBH Servomotors	With Straight Plug	JZSP-CMP01-03	3 m (118.11 in)
		JZSP-CMP01-05	5 m (196.85 in)
		JZSP-CMP01-10	10 m (393.70 in)
		JZSP-CMP01-15	15 m (590.55 in)
		JZSP-CMP01-20	20 m (787.40 in)
	With L-Shape Plug	JZSP-CMP02-03	3 m (118.11 in)
		JZSP-CMP02-05	5 m (196.85 in)
		JZSP-CMP02-10	10 m (393.70 in)
		JZSP-CMP02-15	15 m (590.55 in)
		JZSP-CMP02-20	20 m (787.40 in)

■ Connector for PG

Connector on SERVOPACK End Only	55102-0600 (Manufactured by Molex Japan Co., Ltd.)	Connector kit: JZSP-CMP9-1
Connector on Servomotor End Only	54280-0600 (Manufactured by Molex Japan Co., Ltd.)	-

2.3.2 Main Circuit Wiring and Power ON Sequence

This section shows typical examples of main circuit wiring for Σ-II Series servo products, functions of main circuit terminals, and the power ON sequence.

■ 400-V Power Supply

- SERVOPACK Main Circuit Terminal Names and Descriptions

The following table shows the name and description of each main circuit terminal.

Table 2.1 SERVOPACK Main Circuit Terminals

Terminal Symbol	Functions	Description
L1/R, L2/S, L3/T	Main power input terminals	Three-phase 380 to 480 VAC $^{+10}_{-15}$ %, 50/60 Hz
U, V, W	Servomotor connection terminal	Used to connect to the servomotor.
DC24P, DC24N	Control power input terminal	24 VDC±15 %
⏚ (Two)	Ground terminal	Connected to ground. (For power ground and motor ground)
+1, +2	DC reactor connection terminal	Used to protect against harmonics (factory setting: short-circuited)
B1, B2	Regenerative Resistor Unit connection terminal	Used to connect the regenerative resistor.
480 V, 460 V, 440 V, 400 V, 380 V, 0 V	Input terminals for control actuator	Single-phase 380 to 480 V, 50/60 Hz Power supply input terminals for the fan and the contactor.
–	Main circuit minus terminal	Normally, external connection is not required.
DU, DV, DW	Dynamic Brake Unit connection terminal	Used to connect the Dynamic Brake Unit.
DBON, DB24	Dynamic Brake Unit connection terminal	Used to connect the Dynamic Brake Unit to the DBON and DB24 terminals (when using 37-kW and 55-kW SERVOPACKs only).

• Servomotor Terminal Names and Descriptions

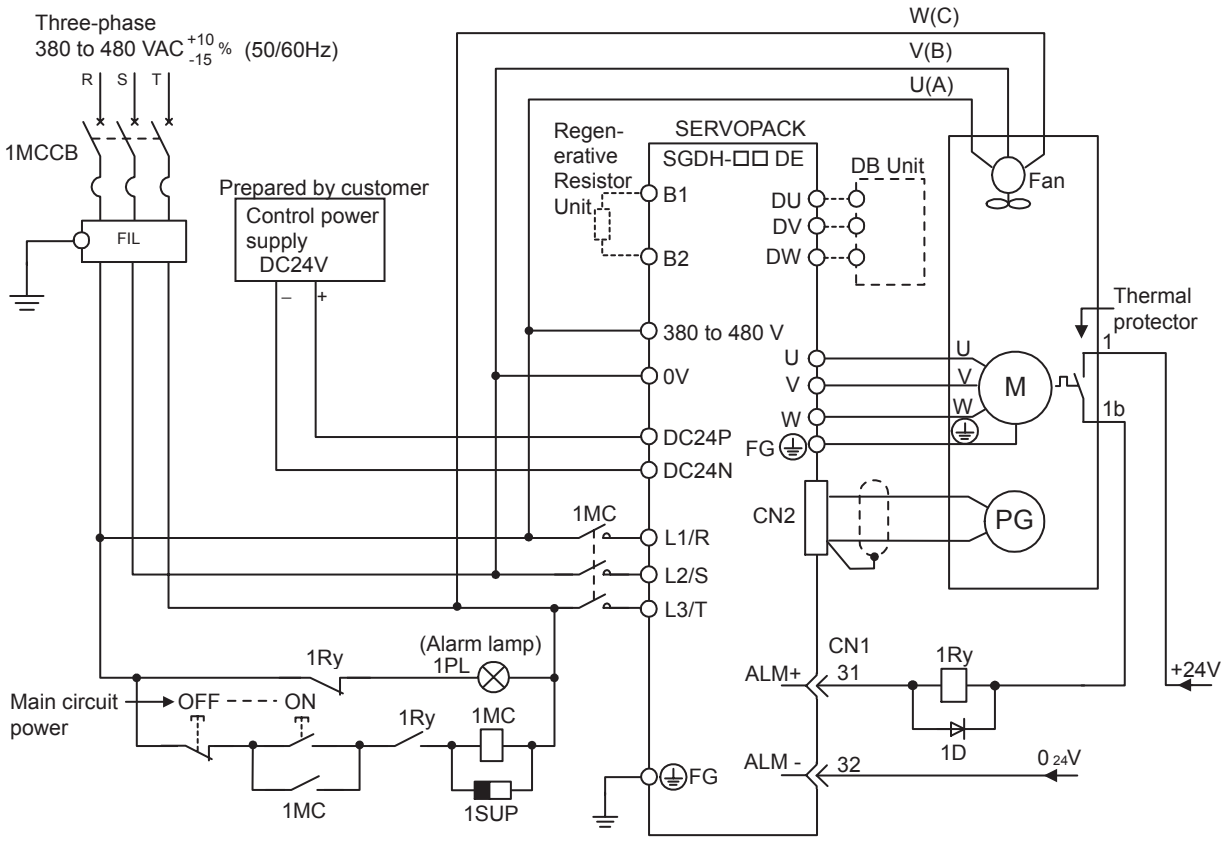
The following table shows the name and description of each motor terminal.

Table 2.2 Servomotor Terminals

Terminal Symbol	Functions	Description
U, V, W	SERVOPACK connection terminals	Used to connect to the U, V, and W terminals of the SERVOPACK
U (A), V (B), W (C)	Fan terminals	Used to connect the fan power supply. Three-phase 380 to 480 VAC $^{+10}_{-15}$ % , 50/60 Hz
A, B	Brake power supply connection terminals	Used to connect the brake power supply (only when using servomotors with brakes).
1, 1b	Thermal protector terminals	Used to detect overheating of the servomotor and open the thermal protector circuit. Use a sequence that turns OFF the SERVOPACK's main circuit power or the servomotor when the thermal protector circuit opens.

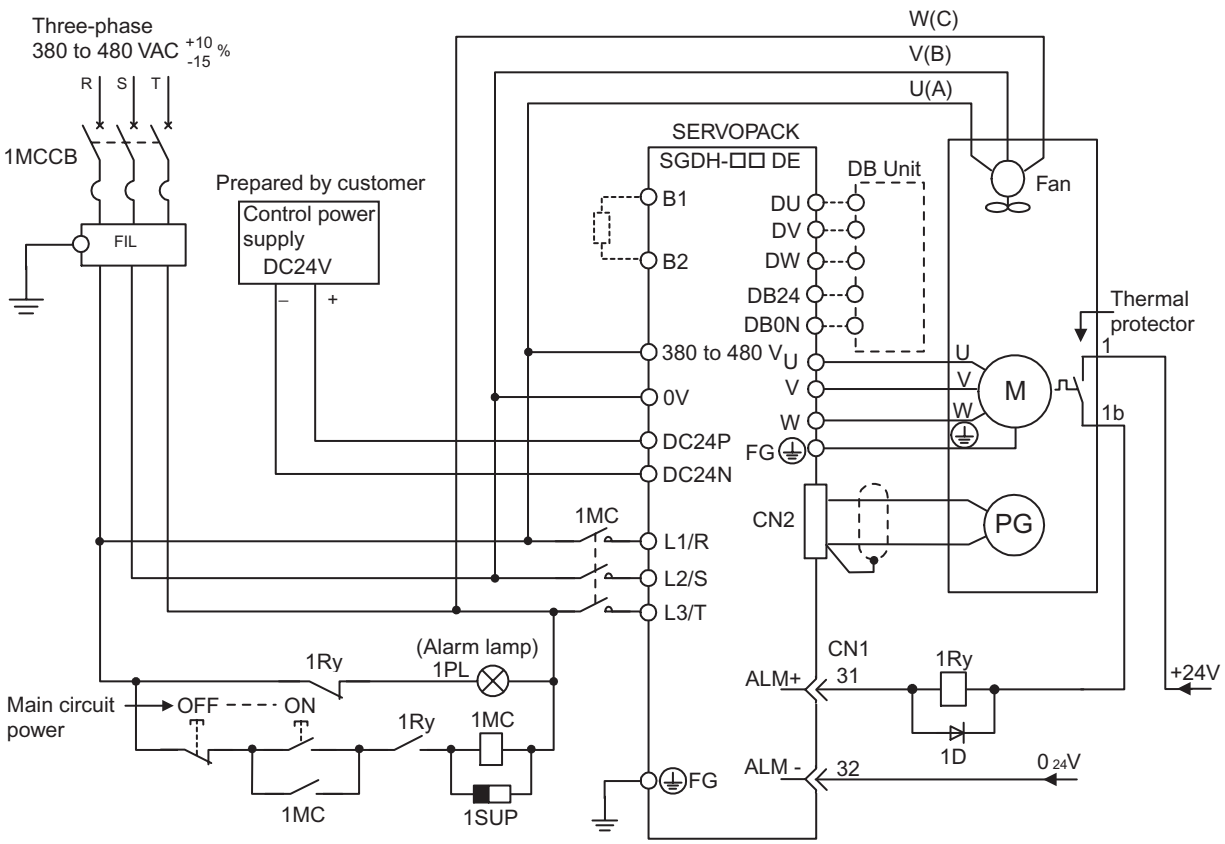
• Typical Wiring Example

Using 400 V, 22 kW or 30 kW



1MCCB : Circuit breaker (for inverter type)
FIL : Noise filter
1MC : Contactor
1Ry : Relay
1PL : Lamp for display
1SUP : Surge suppressor
1D : Flywheel diode

Using 400 V, 37 kW or 55 kW



1MCCB : Circuit breaker (for inverter type)
FIL : Noise filter
1MC : Contactor
1Ry : Relay
1PL : Lamp for display
1SUP : Surge suppressor
1D : Flywheel diode

■ Note

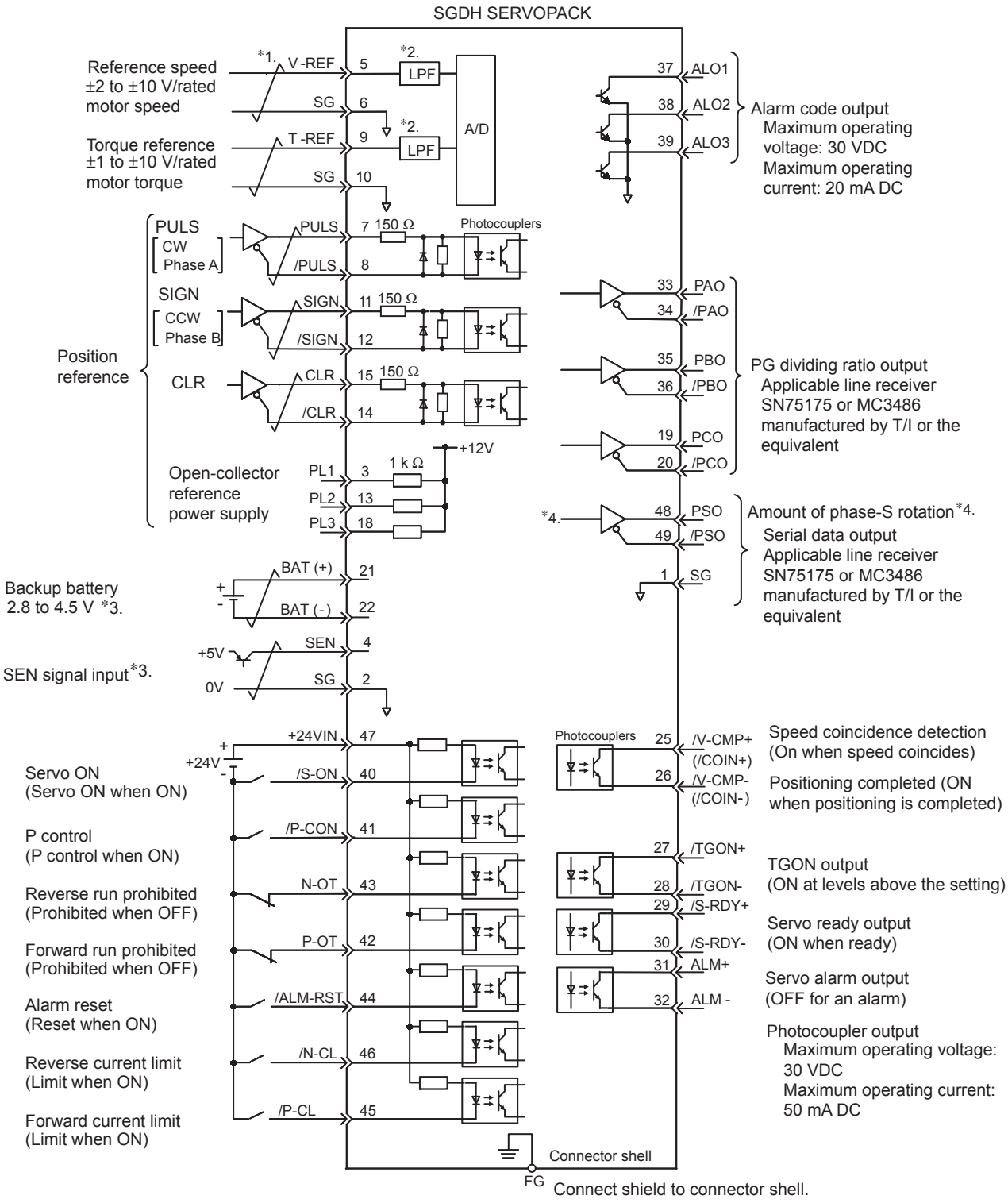
- Do not bundle or run power and signal lines together in the same duct. Keep power and signal lines separated by at least 30 cm (11.81 in).
- Use twisted-pair wires or multi-core shielded-pair wires for signal and encoder (PG) feedback lines. The length for wiring is 3 m (118.11 in) maximum for the reference input line.
- Do not touch the power terminal even if power was turned OFF. High voltage may still remain in SERVOPACK. Make sure the charge indicator is out first before starting an inspection.
- Avoid frequently turning power ON and OFF. Since the SGDH SERVOPACK has a capacitor in the power supply, a high charging current flows for 0.2 seconds when power is turned ON. Therefore, frequently turning the power ON and OFF causes the main circuit devices (such as capacitors and fuses) to deteriorate, resulting in unexpected problems.

2.4 I/O Signals

This section describes I/O signals for the SGDH SERVOPACK.

2.4.1 Examples of I/O Signal Connections

The following diagram shows a typical example of I/O signal connections.



*1. represents twisted-pair wires.
*2. The time constant for the primary filter is 47 μs.
*3. Connector when using an absolute encoder.
*4. Used only with an absolute encoder.

2.4.2 List of CN1 Terminals

The following diagram shows the layout and specifications of CN1 terminals.

■ CN1 Terminal Layout

2	SG	GND	1	SG	GND	27	/TGON+	TGON signal output	26	/V-CMP- (/COIN-)	Speed Coincidence Detection Output
4	SEN	SEN signal input	3	PL1	Open-collector reference power supply	29	/S-RDY+	Servo ready output	28	/TGON-	TGON signal output
6	SG	GND	5	V-REF	Speed Reference Input	31	ALM+	Servo alarm output	30	/S-RDY-	Servo ready output
8	/PULS	Reference pulse input	7	PULS	Reference pulse input	33	PAO	PG divided output phase A	32	ALM-	Servo alarm output
10	SG	GND	9	T-REF	Torque Reference Input	35	PBO	PG divided output phase B	34	/PAO	PG divided output phase A
12	/SIGN	Reference sign input	11	SIGN	Reference sign input	37	ALO1	Alarm code outputs	36	/PBO	PG divided output phase B
14	/CLR	Clear input	13	PL2	Open-collector reference power supply	39	ALO3	(open-collector output)	38	ALO2	Alarm code outputs
16	–	–	15	CLR	Clear input	41	P-CON	P operation input	40	/S-ON	Servo ON input
18	PL3	Open-collector reference power supply	17	–	–	43	N-OT	Reverse overtravel input	42	P-OT	Forward overtravel input
20	/PCO	PG divided output phase C	19	PCO	PG divided output phase C	45	/P-CL	Forward current limit ON input	44	/ALM-RST	Alarm reset input
22	BAT (-)	Battery (-)	21	BAT (+)	Battery (+)	47	+24V -IN	External input power supply	46	/N-CL	Reverse current limit ON input
24	–	–	23	–	–	49	/PSO	Phase-S signal output	48	PSO	Phase-S signal output
			25	/V-CMP+ (/COIN+)	Speed coincidence detection output				50	–	–

Note: 1. Do not use unused terminals for relays.
2. Connect the shield of the I/O signal cable to the connector shell. Connect to the FG (frame ground) at the SERVOPACK-end connector.

■ CN1 Specifications

Specifications for SERVOPACK Connectors	Applicable Receptacles		
	Solder Type	Case	Manufacturer
10250-52A2JL or Equivalent 50-p Right Angle Plug	10150-3000VE	10350-52A0-008	Sumitomo 3M Co.

2.4.3 I/O Signal Names and Functions

The following section describes SERVOPACK I/O signal names and functions

■ Input Signals

Table 2.3 Input Signal Names and Functions

Single Name		Pin No.	Functions		Reference
Common	/S-ON	40	Servo ON: Turns ON the servomotor when the gate block in the inverter is released.		4.5.2
	/P-CON	41	* Function selected via parameter.		–
			Proportional operation reference	Switches the speed control loop from PI (proportional/ integral) to P (proportional) control when ON.	4.2.1
			Direction reference	With internal reference speed selected: Switches the direction of rotation.	4.2.6
			Control mode switching	Position ↔ speed Control ↔ torque Torque ↔ speed } Enables control mode switching.	4.2.7
			Zero-clamp reference	Speed control with zero-clamp function: Reference speed is zero when ON.	4.4.3
			Reference pulse block	Position control with reference pulse stop: Stops reference pulse input when ON.	4.2.12
	P-OT N-OT	42 43	Forward Run prohibited Reverse Run prohibited	Overtravel prohibited: Stops servomotor when movable part travels beyond the allowable range of motion.	4.1.2
	/P-CL /N-CL	45 46	* Function selected via parameter.		–
			Forward current limit ON Reverse current limit ON	Current limit function used when ON.	4.1.3
			Internal speed switching	With internal reference speed selected: Switches the internal speed settings.	4.2.6
	/ALM - RST	44	Alarm reset: Releases the servo alarm state.		4.5.1
	+24VIN	47	Control power supply input for sequence signals: Users must provide the +24-V power supply. Allowable voltage fluctuation range: 11 to 25 V		4.2.4
	SEN	4 (2)	Initial data request signal when using an absolute encoder.		4.7.1
	BAT (+) BAT (-)	21 22	Connecting pin for the absolute encoder backup battery.		4.7.1

Table 2.3 Input Signal Names and Functions (cont'd)

Single Name		Pin No.	Functions		Reference
Speed	V-REF	5 (6)	Speed reference speed input: ±2 to ±10 V/rated motor speed (Input gain can be modified using a parameter.)		4.2.1
Torque	T-REF	9 (10)	Torque reference input: ±1 to ±10 V/rated motor torque (Input gain can be modified using a parameter.)		4.2.7
Position Reference	PULS /PULS SIGN /SIGN	7 8 11 12	Reference pulse input Line-driver Open-collector	Input mode • Sign + pulse train • CCW/CW pulse • Two-phase pulse (90° phase differential)	4.2.2
	CLR /CLR	15 14	Error counter clear: Clears the error counter during position control.		4.2.2
	PL1 PL2 PL3	3 13 18	+12-V pull-up power supply when PULS, SIGN and CLR reference signals are open-collector outputs (+12-V power supply is built into the SERVOPACK).		4.2.2

Note: 1. The functions allocated to /S-ON, /P-CON. P-OT, N-OT, /ALM-RST, /P-CL, and /N-CL input signals can be changed via parameters. Refer to *4.3.3 Input Circuit Signal Allocation*.
2. Pin numbers in parenthesis () indicate signal grounds.
3. The voltage input range for speed and torque references is a maximum of ±12 V.

■ Output Signals

Table 2.4 Output Signal Names and Functions

Signal Name		Pin No.	Functions		Reference
Common	ALM+ ALM-	31 32	Servo alarm: Turns OFF when an error is detected.		4.5.1
	/TGON+ /TGON-	27 28	Detection during servomotor rotation: Detects whether the servomotor is rotating at a speed higher than the motor speed setting. Motor speed detection can be set via parameter.		4.5.5
	/S-RDY+ /S-RDY-	29 30	Servo ready: ON if there is no servo alarm when the control/main circuit power supply is turned ON.		4.5.6
	PAO /PAO PBO /PBO PCO /PCO	33 (1) 34 35 36 19 20	Phase-A signal Phase-B signal Phase-C signal	Converted two-phase pulse (phase A and B) encoder output signal and origin pulse (phase C) signal: RS-422 or the equivalent	4.2.3
	PSO /PSO	48 49	Phase-S signal	With an absolute encoder: Outputs serial data corresponding to the number of revolutions (RS-422 or equivalent)	4.7.5
	ALO1 ALO2 ALO3	37 38 39 (1)	Alarm code output: Outputs 3-bit alarm codes. Open-collector: 30 V and 20 mA rating maximum		4.5.1
	FG	Shell	Connected to frame ground if the shield wire of the I/O signal cable is connected to the connector shell.		–
Speed	/V-CMP+ /V-CMP-	25 26	Speed coincidence (output in Speed Control Mode): Detects whether the motor speed is within the setting range and if it matches the reference speed value.		4.5.4

Table 2.4 Output Signal Names and Functions (cont'd)

Signal Name		Pin No.	Functions	Reference
Position	/COIN+ /COIN-	25 26	Positioning completed (output in Position Control Mode): Turns ON when the number of error pulses reaches the value set. The setting is the number of error pulses set in reference units (input pulse units defined by the electronic gear).	4.5.3
Not used.		16 17 23 24 50	These terminals are not used. Do not connect relays to these terminals.	-

Note: 1. Pin numbers in parenthesis () indicate signal grounds.
2. The functions allocated to /TGON, /S-RDY, and /V-CMP (/COIN) output signals can be changed via parameters. /CLT, /VCT, /BK, /WARN, and /NEAR signals can also be changed. Refer to *4.3.4 Output Circuit Signal Allocation*.

2.4.4 Interface Circuits

This section shows examples of SERVOPACK I/O signal connection to the host controller.

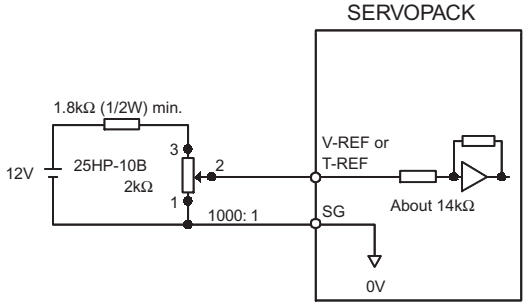
■ Interface for Reference Input Circuits

Analog Input Circuit

Analog signals are either speed or torque reference signals at the impedance below.

- Reference speed input: About 14 kΩ
- Reference torque input: About 14 kΩ

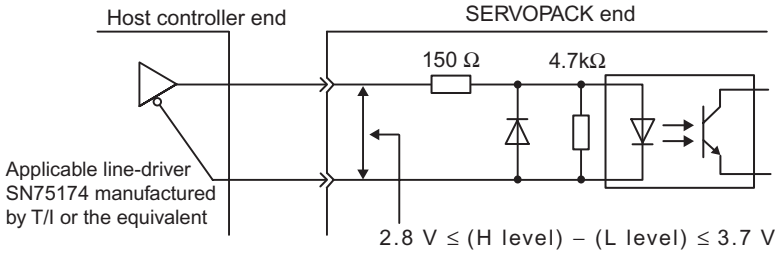
The maximum allowable voltages for input signals is ±12 V.



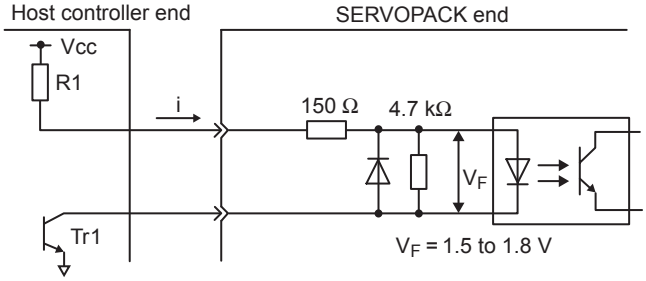
Reference Position Input Circuit

An output circuit for the reference pulse and error counter clear signal at the host controller can be either line-driver or open-collector outputs. These are shown below by type.

- Line-driver Output



- Open-collector Output, Example 1: Power Supply Provided by User

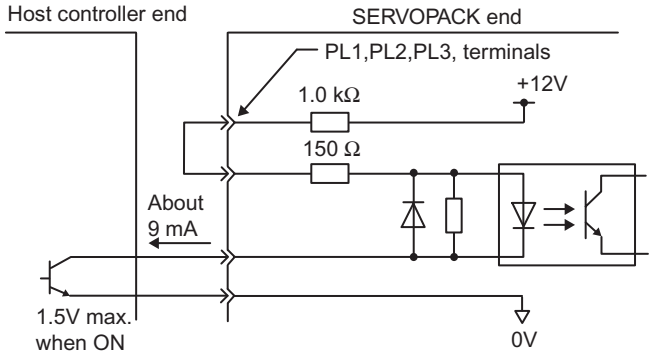


Use the examples below to set pull-up resistor R1 so the input current, i, falls between 7 and 15 mA.

Application Examples		
When Vcc is 24 V ± 5 %: R1 = 2.2 kΩ	When Vcc is 12 V ± 5 %: R1 = 1 kΩ	When Vcc is 5 V ± 5 %: R1 = 180 Ω

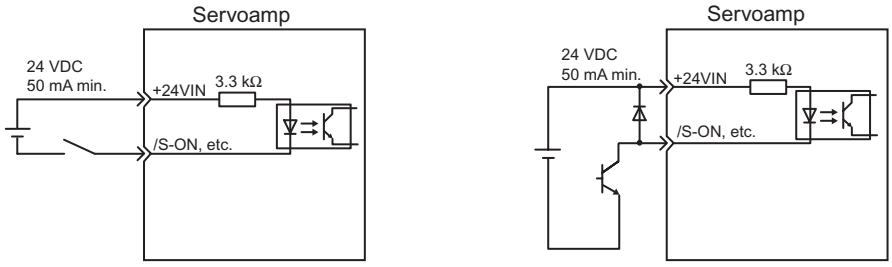
- Open-collector Output, Example 2: Using 12-V Power Supply Built into SERVOPACK

This circuit uses the 12-V power supply built into the SERVOPACK. The input is not insulated in this case.



■ Sequence Input Circuit Interface

The sequence input circuit interface connects through a relay or open-collector transistor circuit. Select a low-current relay otherwise a faulty contact will result.



■ Output Circuit Interfaces

Any of the following three types of SERVOPACK output circuits can be used. Form an input circuit at the host controller that matches one of these types.

- Connecting to a Line-driver Output Circuit

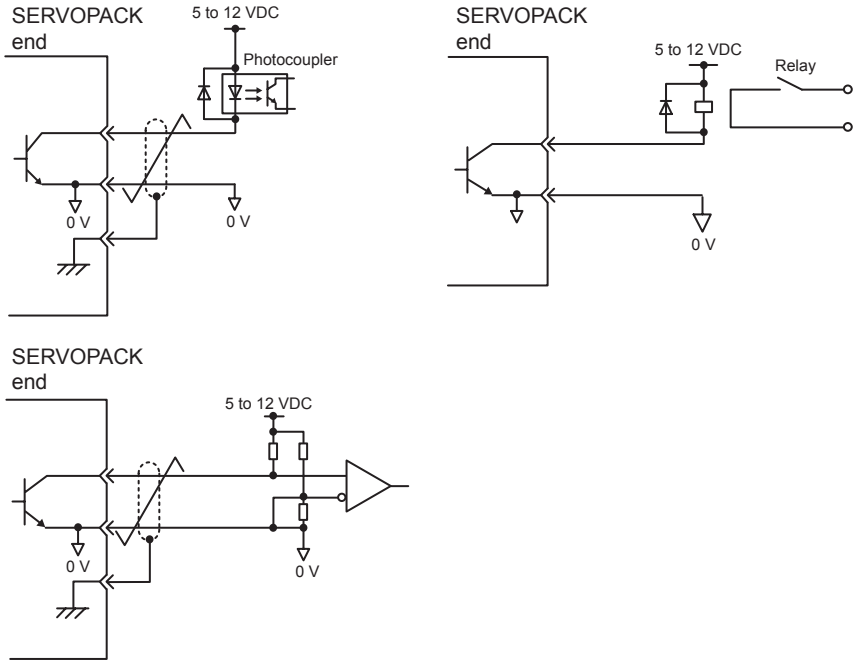
  Encoder serial data converted to two-phase (phase A and B) pulse output signals (PAO, /PAO, PBO, /PBO), origin pulse signals (PCO, /PCO) and phase-S rotation signals (PSO, /PSO) are output via line-driver output circuits that normally comprise the position control system at the host controller. Connect the line-driver output circuit through a line receiver circuit at the host controller.

  See *2.5 Wiring Encoders* for connection circuit examples.

- Connecting to an Open-collector Output Circuit

  Alarm code signals are output from open-collector transistor output circuits.

  Connect an open-collector output circuit through a photocoupler, relay or line receiver circuit.

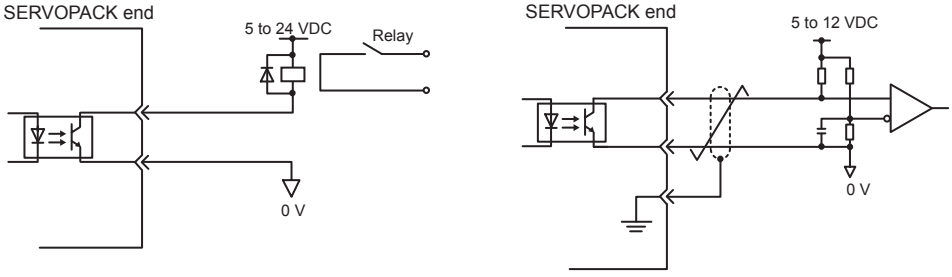


Note: The maximum allowable voltage and current capacities for open-collector output circuits are as follows.
- Voltage: 30 VDC max.
- Current: 20 mA DC max.

- Connecting to a Photocoupler Output Circuit

Photocoupler output circuits are used for servo alarm, servo ready, and other sequence output signal circuits.

Connect a photocoupler output circuit through a relay or line receiver circuit.



Note: The maximum allowable voltage and current capacities for photocoupler output circuits are as follows.
- Voltage: 30 VDC max.
- Current: 50 mA DC max.

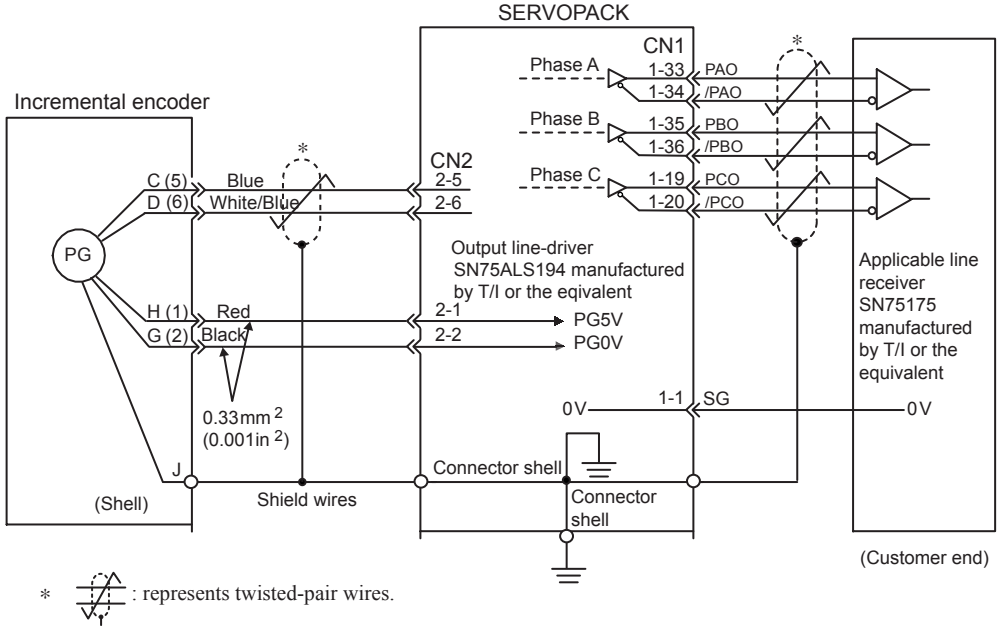
2.5 Wiring Encoders

The following sections describe the procedure for wiring a SERVOPACK to the encoder.

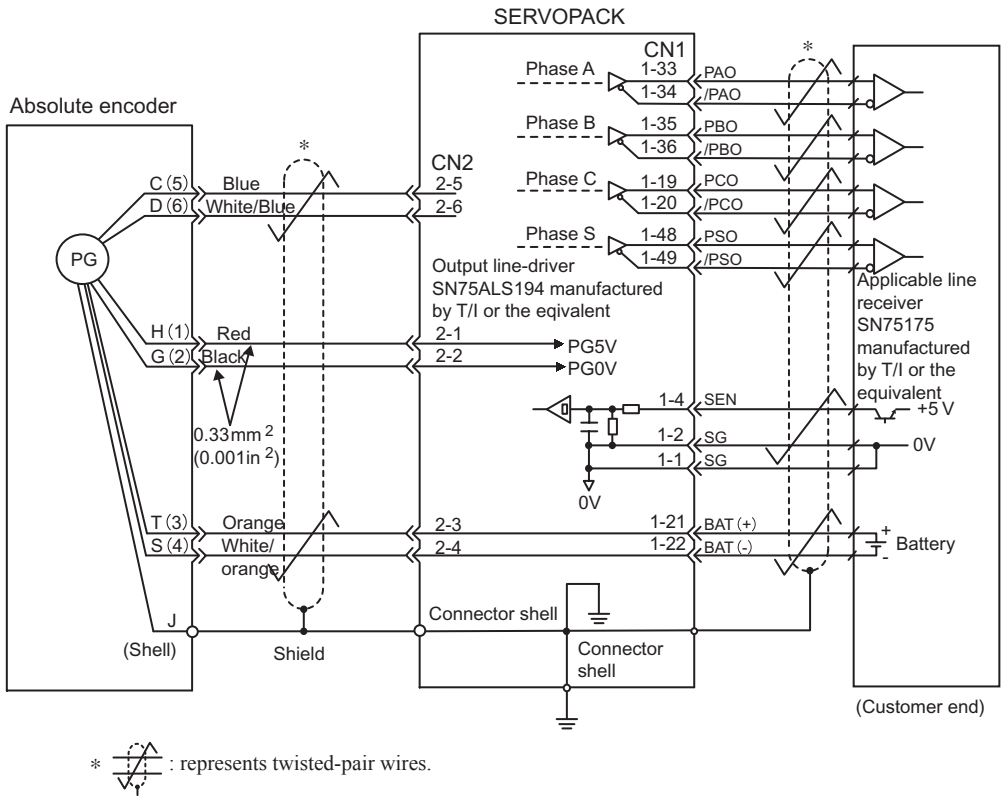
2.5.1 Connecting an Encoder (CN2) and Output Signals from the SERVOPACK (CN1)

The following diagrams show wiring for incremental and absolute encoders.

■ Incremental Encoders



■ Absolute Encoders



2.5.2 Terminal Layout and Types of CN2 Encoder Connector

The following diagram shows the layout and types of CN2 terminals.

■ CN2 Connector Terminal Layout

1	PG5V	PG power supply +5 V	2	PG 0 V	PG power supply 0 V
3	BAT (+)	Battery (+) (For an absolute encoder)	4	BAT (-)	Battery (-) (For an absolute encoder)
5	PS	PG serial signal input	6	/PS	PG serial signal input

■ CN2 Connector Models

SERVOPACK Connectors	Applicable Plug (or Socket)	
	Soldered Relay Plug (SERVOPACK Connector)	Soldered Relay Plug (Servomotor Connector)
53460-0611 Molex Japan Co., Ltd.	55100-0600 Molex Japan Co., Ltd.	L-shaped plug: MS3108B20-29S or Straight : MS3106B20-29S Cable clamp : MS3057-12A

Note: FA1394 is the product number for the SERVOPACK-end plug set from Molex Japan Co., Ltd.



Encoder cables are available from Yaskawa. See *Chapter 7 Servo Selection and Data Sheets* for more details on the cables.

2.5.3 Examples of Connecting I/O Signal Terminals

SGDH SERVOPACKs can be connected to the host controllers listed below. Connect the SERVOPACK to the host controller by referring to documentation for the host controller.

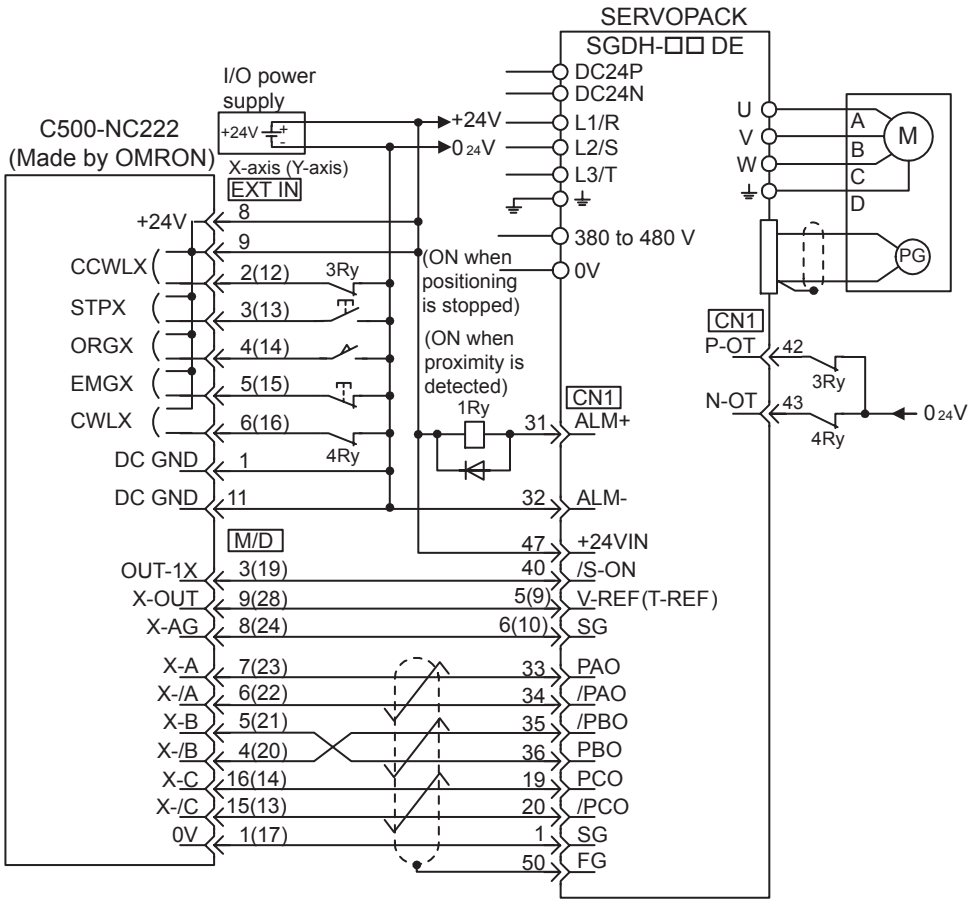
- MP920
- GL-Series B2833 Positioning Module
- GL-Series B2813 Positioning Module
- OMRON C500-NC222 and C500-NC112 Position Control Units
- MITSUBISHI AD72 and AD71 (B Type) Positioning Unit

Typical connection examples for the OMRON Position Control Unit and MITSUBISHI Positioning Unit are provided below.

■ Connection to OMRON C500-NC222 Position Control Unit

Speed/Torque

SERVOPACK for Speed/Torque Control



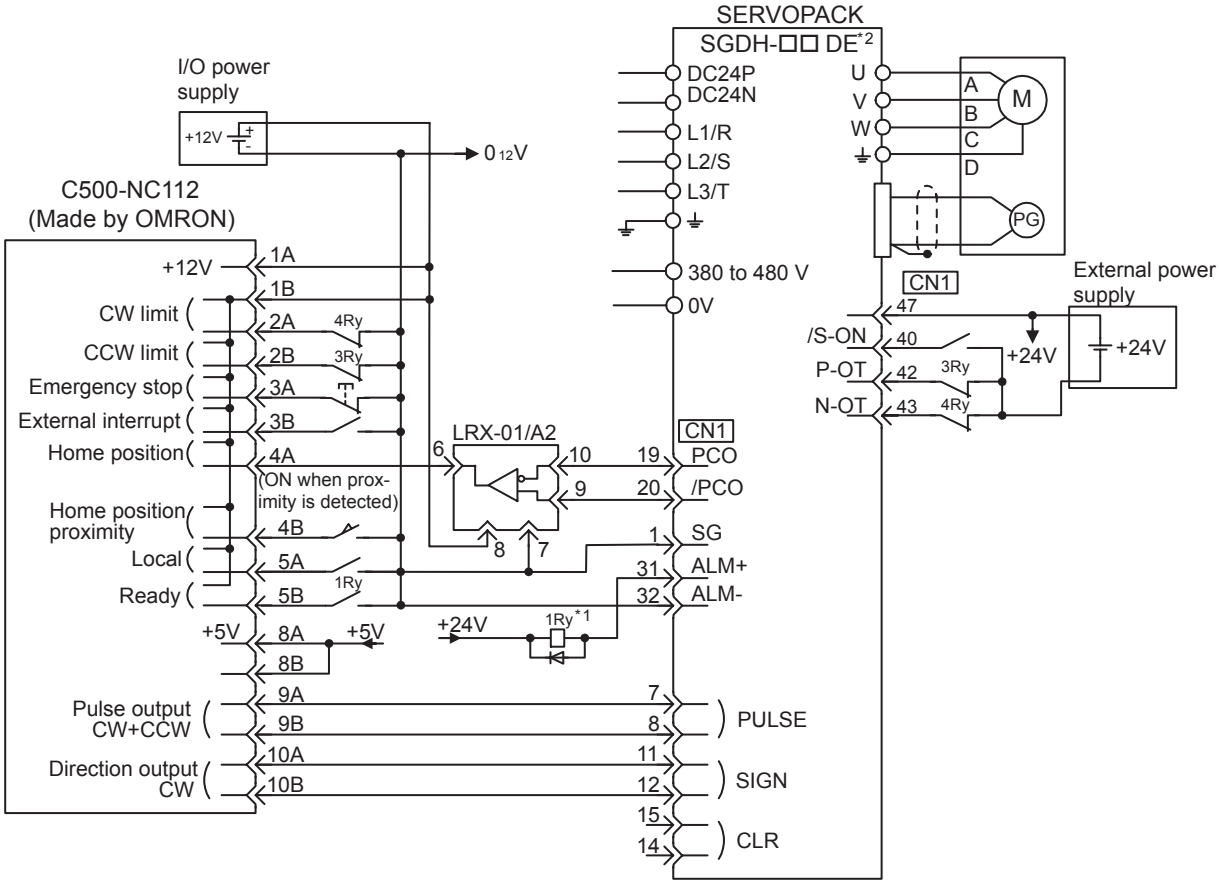
* These signals are output for approximately two seconds when the power is turned ON. Take this into consideration when designing a power ON sequence. Relay 1Ry is used to stop main circuit power supply to SERVOPACK.

Note: The signals shown here are applicable only to OMRON C500-NC222 Position Control Unit and Yaskawa SGDH-□□DE SERVOPACK.

■ Connection to OMRON C500-NC112 Position Control Unit

Position

SERVOPACK for Position Control



* 1. These signals are output for approximately two seconds when the power is turned ON. Take this into consideration when designing a power ON sequence. Relay 1Ry is used to stop main circuit power supply to SERVOPACK.

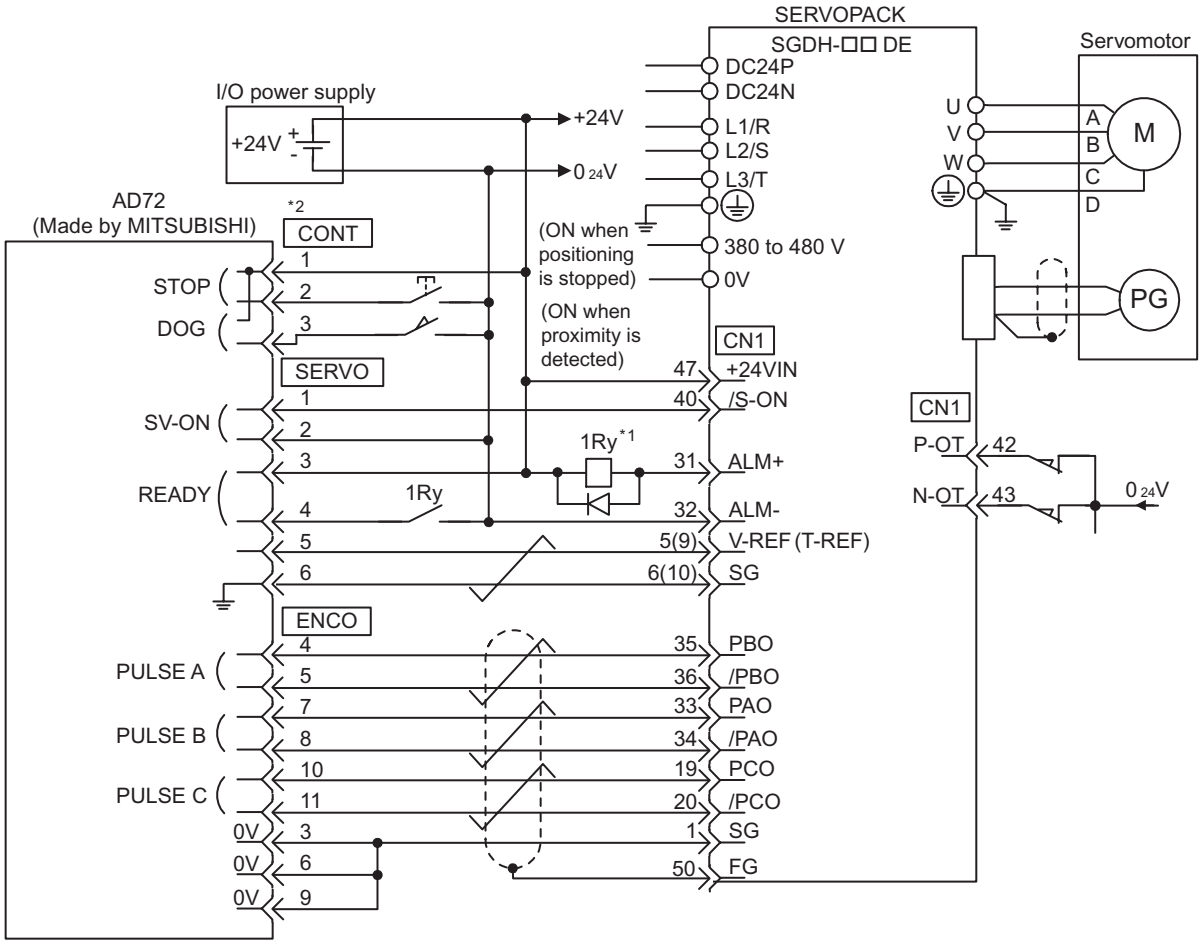
* 2. Change the Pn200.0 = 1 setting as follows:
Bit No.3 = 1
Bit No.4 = 0
Bit No.5 = 0

Note: The signals shown here are applicable only to OMRON C500-NC112 Position Control Unit and Yaskawa SGDH-□□DE SERVOPACK.

■ Connection to MITSUBISHI AD72 Positioning Unit

Speed/Torque

SERVOPACK for Speed/Torque Control



* 1. These signals are output for approximately two seconds when the power is turned ON. Take this into consideration when designing a power ON sequence. Relay 1Ry is used to stop main circuit power supply to SERVOPACK.

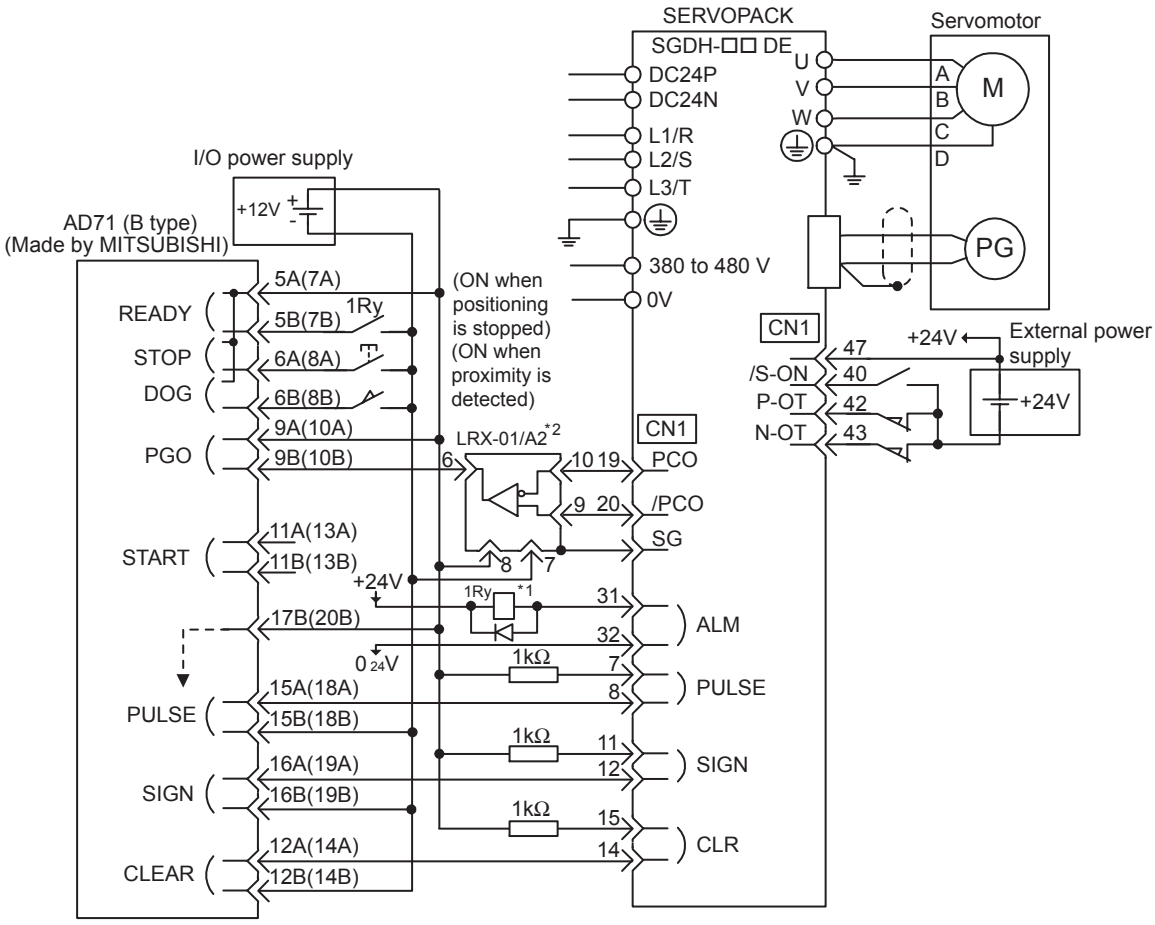
* 2. These pin numbers are the same for both X and Y axes.

Note: The signals shown here are applicable only to MITSUBISHI AD72 Positioning Unit and Yaskawa SGDH-□□DE SERVOPACK.

■ Connection to MITSUBISHI AD71 (B Type) Positioning Unit

Position

SERVOPACK for Position Control



* 1. These signals are output for approximately two seconds when the power is turned ON. Take this into consideration when designing a power ON sequence. Relay 1Ry is used to stop main circuit power supply to SERVOPACK.

* 2. Manufactured by Yaskawa Controls Co., Ltd.

Note: The signals shown here are applicable only to MITSUBISHI AD71 (B Type) Positioning Unit and Yaskawa SGDH-□□DE SERVOPACK.

3

Trial Operation

This chapter describes a two-step trial operation. Be sure to complete step 1 before proceeding to step 2.

3.1 Two-step Trial Operation ----------3-2
3.1.1 Step 1: Trial Operation for Servomotor without Load ---------- 3-3
3.1.2 Step 2: Trial Operation with the Servomotor Connected to the Machine 3-9
3.2 Supplementary Information on Trial Operation ----------3-10
3.2.1 Servomotors with Brakes ---------- 3-10
3.2.2 Position Control by Host Controller ---------- 3-11
3.3 Minimum Parameters and Input Signals ----------3-12
3.3.1 Parameters ---------- 3-12
3.3.2 Input Signals ---------- 3-13

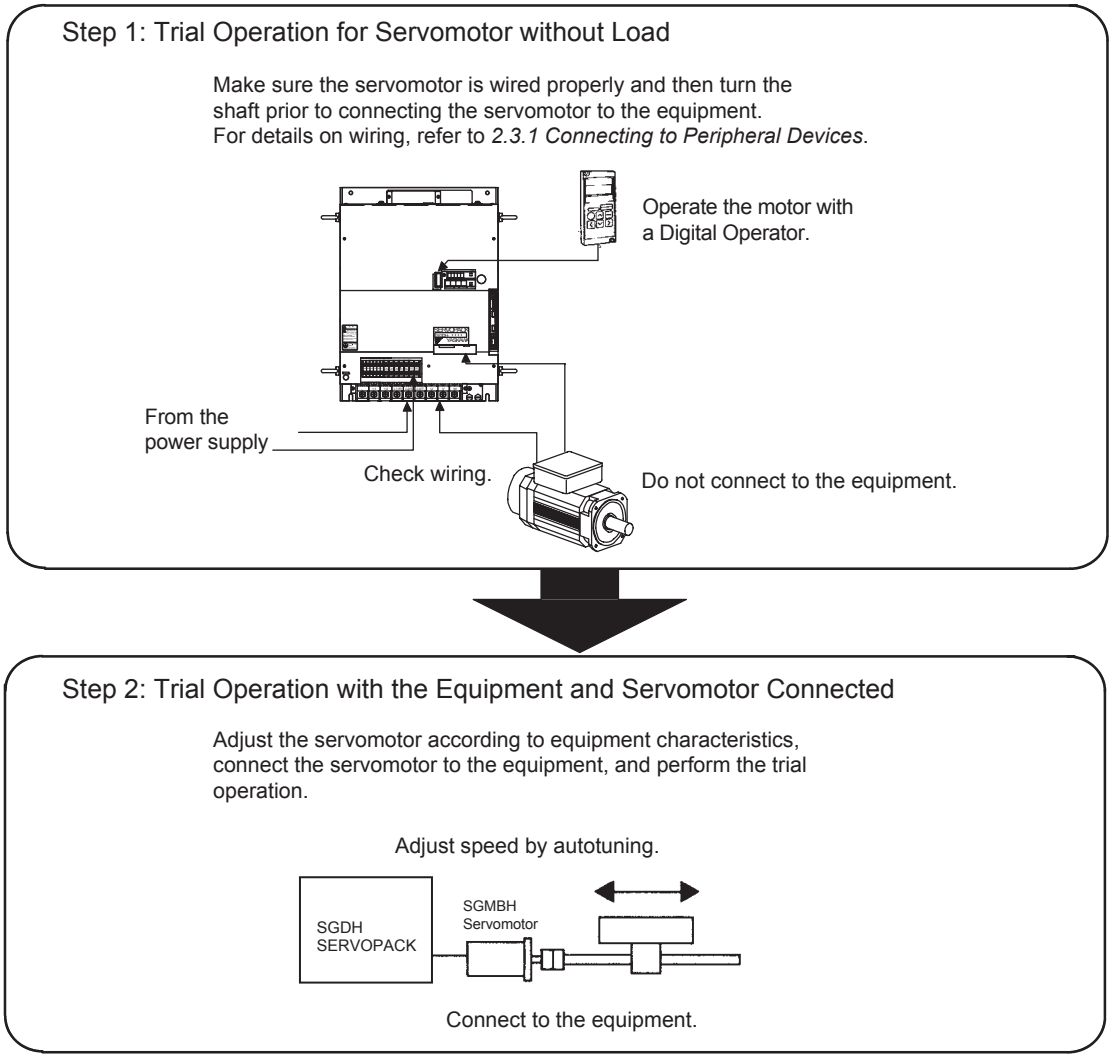
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3.1 Two-step Trial Operation

Make sure that all wiring is completed prior to starting trial operation. Perform the trial operation in the order given below (step 1 and 2) for your safety.

IMPORTANT

To prevent accidents, initially perform step 1 where the trial operation is conducted under no-load conditions (with all couplings and belts disconnected). Do not operate the servomotor while it is connected to the equipment.



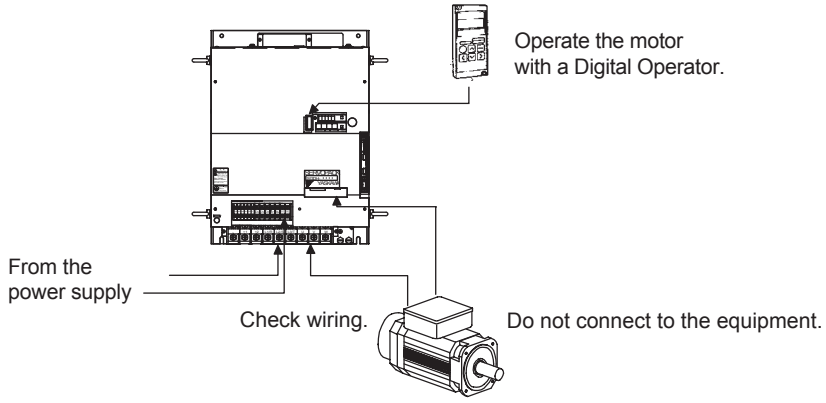
3.1.1 Step 1: Trial Operation for Servomotor without Load

In step 1, make sure that the servomotor is wired properly as shown below. Incorrect wiring is generally the reason why servomotors fail to operate properly during trial operation.

- Check main power supply circuit wiring.
- Check servomotor wiring.
- Check CN1 I/O signal wiring.

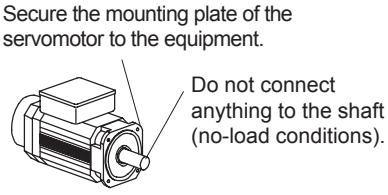
Make sure the host controller and other adjustments are completed as much as possible in step 1 (prior to connecting the servomotor to equipment).

Conduct a test run for the motor without load according to the following procedure. See *3.2.1 Servomotors with Brakes* if you are using a servomotor with brakes.



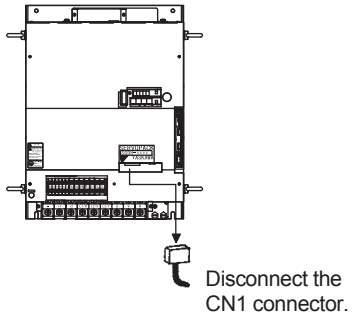
1. Secure the servomotor.

   Secure the servomotor mounting plate to the equipment in order to prevent the servomotor from moving during operation. In this case, be sure to disconnect the coupling and belt.



2. Check the wiring.

   Disconnect the CN1 connector and check servomotor wiring in the power supply circuit. CN1 I/O signals are not used, so leave the connector disconnected.



3. Turn ON power.

   Turn ON SERVOPACK power. If the SERVOPACK has turned ON normally, the LED display on the Digital Operator will appear as shown on the right. Power is not supplied to the servomotor because the servo is OFF.

   If an alarm display appears on the LED indicator as shown on the right, the power supply circuit, servomotor wiring, or encoder wiring is incorrect. In this case, turn OFF power and take appropriate action. See *8.2.3 Alarm Display Table*.

Normal display



Alternate display

Example of Alarm Display

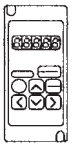


4. Operate with the Digital Operator.

   Operate the servomotor using the Digital Operator. Check to see if the servomotor runs normally.

   See *6.2.2 Controlling Operation Through the Digital Operator* for more details on the procedure.

Operation by Digital Operator



If an alarm occurs, the power supply circuit, motor wiring, or encoder wiring is incorrect.

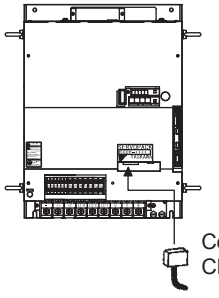
5. Connect the signal lines.

   Use the following procedure to connect the CN1 connector.

   a) Turn OFF power.

   b) Connect the CN1 connector.

   c) Turn ON power again.

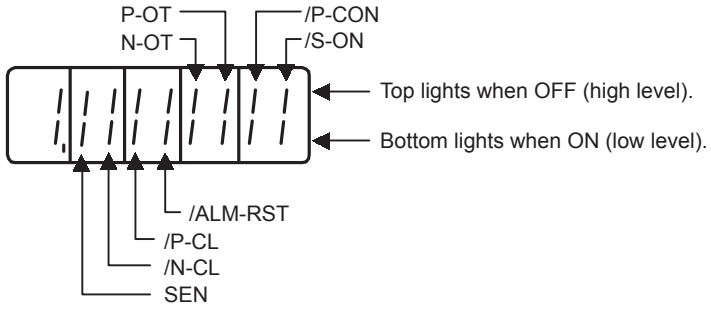


6. Check the input signals.

   Check input signal wiring in Monitor Mode using the Digital Operator. See *6.1.7 Operation in Monitor Mode* for more details on the procedure.

   Turn ON and OFF each signal line to see if the LED monitor bit display on the panel changes as shown below.

Input signal LED display



Input Signal Status	LED Display
OFF (high level)	Top LED indicators light.
ON (low level)	Bottom LED indicators light.

IMPORTANT

The servomotor will not operate properly if the following signal lines are not wired correctly. Short the signal lines if they will not be used. The input signal selections (parameters Pn50A to Pn50D) can be used to eliminate the need for external short circuiting.

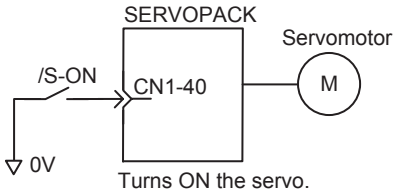
Signal Symbol	Connector Pin No.	Description
P-OT	CN1-42	The servomotor can rotate in the forward direction when this signal line is low (0 V).
N-OT	CN1-43	The servomotor can rotate in the reverse direction when this signal line is low (0 V).
/S-ON	CN1-40	The servomotor is turned ON when this signal line is low (0 V). Leave the servomotor OFF.
+24VIN	CN1-47	Control power supply terminal for sequence signals.

INFO

If an absolute encoder is being used, the servo will not turn ON when the servo ON signal (/S-ON) is input unless the SEN signal is also ON.

When the SEN signal is checked in monitor mode, the top of the LED will light because the SEN signal is high when ON.

7. Turn ON the servo.



Turn ON the servo using the following procedure.

a) Make sure there are no reference signals input.

- Set V-REF (CN1-5) and T-REF (CN1-9) to 0 V for speed and torque control.
- Set PULS (CN1-7) and SIGN (CN1-11) to low for position control.

b) Turn ON the servo ON signal.

Display with the servo ON.



Set /S-ON (CN1-40) to 0 V. If normal, the servomotor will turn ON and the LED indicator on the front panel will display as shown above. If an alarm display appears, take appropriate action as described in *8.2 Troubleshooting*.

IMPORTANT

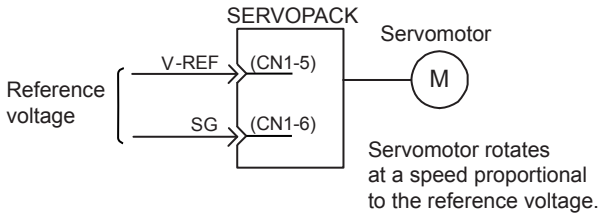
If there is noise in the reference voltage for speed control, the "-" on the left of the 7-segment LED may flash.

8. Operate using reference input.

The operating procedure here depends on the parameter settings (control mode selection at memory switch Pn000.1). Use the following procedure for operations with speed and position control.

■ Operating Procedure in Speed Control Mode: Set Pn000.1 to 0

Standard speed control setting is described here.



1. Gradually increase the reference speed input (V-REF, CN1-5) voltage. The servomotor will rotate.
2. Check the following items in Monitor Mode. See *6.1.7 Operation in Monitor Mode*.

Un000	Actual motor speed
Un001	Reference speed

   - Has the reference speed been input?
   - Is the motor speed as designed?
   - Does the reference speed coincide the actual motor speed?
   - Does the servomotor stop when the speed reference is 0?

3. If the servomotor rotates at extremely slow speed with 0 V specified for the reference voltage, correct the reference offset value as described in *6.2.3 Automatic Adjustment of the Speed and Torque Reference Offset* or *6.2.4 Manual Adjustment of the Speed and Torque Reference Offset*.
4. Reset the parameters shown below to change the motor speed or direction of rotation.

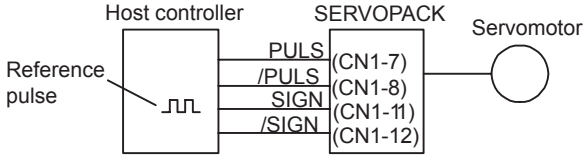
Pn300	Speed Reference Input Gain See *4.2.1 Speed Reference*.
Pn000.0	Rotation Direction Selection See *4.1.1 Switching Servomotor Rotation Direction*.

■ Operating Procedure in Position Control Mode: Set Pn000.1 to 1

1. Set the parameter Pn200.0 so the reference pulse form is the same as the host controller output form.

   Selecting the reference pulse form: See *4.2.2 Position Reference*.

2. Input a slow speed pulse from the host controller and execute low-speed operation.



3. Check the following items in Monitor Mode. See *6.1.7 Operation in Monitor Mode*.

Un000	Actual motor speed
Un007	Reference pulse speed display
Un008	Position offset

   - Has the reference pulse been input?
   - Is the motor speed as designed?
   - Does the reference pulse coincide with the actual motor speed?
   - Does the servomotor stop when the reference pulse is turned OFF?

4. Reset the parameters shown below to change the motor speed or direction of rotation.

Pn202, Pn203	Electronic Gear Ratio See *4.2.5 Using the Electronic Gear Function*.
Pn000.0	Rotation Direction Selection See *4.1.1 Switching Servomotor Rotation Direction*.

If an alarm occurs or the servomotor fails to operate during the above operation, CN1 connector wiring is incorrect or parameter settings do not match the host controller specifications. Check the wiring and review the parameter settings, then repeat step 1.

INFO

Reference

- List of Alarms: See *8.2.3 Alarm Display Table*.
- List of Parameters: See *Appendix A List of Parameters*.

3.1.2 Step 2: Trial Operation with the Servomotor Connected to the Machine

⚠ CAUTION

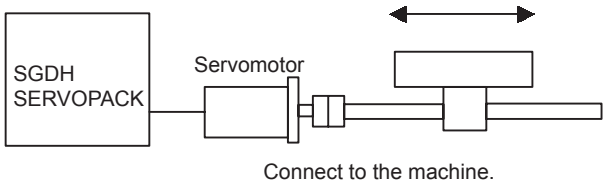
- Follow the procedure below for step-2 operation precisely as given.

  Malfunctions that occur after the servomotor is connected to the equipment not only damage the equipment, but may also cause an accident resulting death or injury.

Before proceeding to step 2, repeat step 1 (servomotor trial operation without a load) until you are fully satisfied that all items including parameters and wiring have been tested completely.

After step 1 has been completed, proceed to step 2 for trial operation with the servomotor connected to the equipment. The purpose of step 2 is to adjust the SERVOPACK according to equipment characteristics.

- Use autotuning to match the SERVOPACK to equipment characteristics.
- Match the direction of rotation and speed to equipment specifications.
- Check the final control form.



Follow the procedures below to perform the trial operation.

1. Make sure power is OFF.
2. Connect the servomotor to the equipment.

   See *7.4.1 Servomotors* for more details on connecting the servomotor.
3. Use autotuning to match the SERVOPACK to equipment characteristics.

   Refer to *5.3 Autotuning*.
4. Operate the servomotor by reference input.

   As in step 1 (servomotor trial operation with no-load), execute operation by reference input as described in *3.1.1 Step 1: Trial Operation for Servomotor without Load*. Tune to match the host controller at this time as well.
5. Set and record user settings.

   Set parameters as required and record all settings for use later in maintenance.

INFO

The servomotor will not be broken in completely during the trial operation. Therefore, let it the system run for a sufficient amount of additional time to ensure that it is properly broken in.

3.2 Supplementary Information on Trial Operation

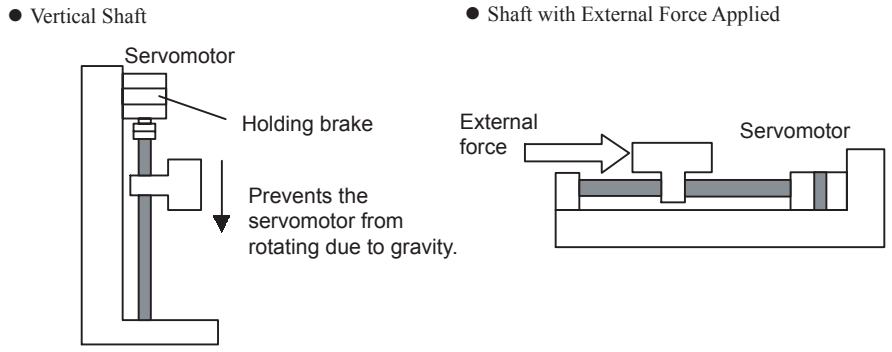
Always refer to this information before starting trial operation in the following instances:

- 3.2.1 Servomotors with Brakes
- 3.2.2 Position Control by Host Controller

3.2.1 Servomotors with Brakes

Use servomotors with brakes for vertical shaft applications or when external force is applied to the shaft to prevent the shaft from rotating due to gravity or external force when power is lost.

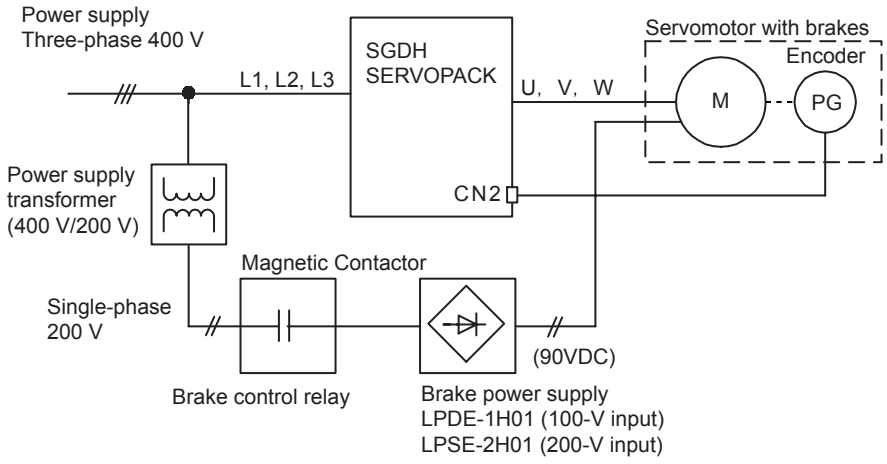
The SERVOPACK uses the brake interlock output (/BK) signal to control holding brake operation when using servomotors with brakes.



IMPORTANT

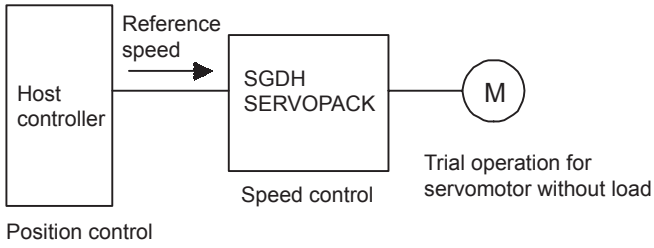
To prevent faulty operation due to gravity or external force, make sure that the servomotor and holding brake operate normally with the servomotor disconnected from the equipment. When both of them operate normally, connect the servomotor to the equipment to start trial operation.

The following figure shows wiring for a servomotor with brakes. See *4.4.4 Using the Holding Brake* for details on wiring.



3.2.2 Position Control by Host Controller

If position control from the host controller has not been confirmed, disconnect the servomotor from the equipment and perform a trial operation, otherwise the servomotor may run out of control. Check servomotor operation as described in the following table.



Reference from the Host Controller	Check Item	Check Method	Review Items
JOG Operation (Constant Reference Speed Input from Host Controller)	Motor speed	Check motor speed as follows: • Use the speed monitor (Un000) on the Panel Operator. • Run the servomotor at low speed. Input a reference speed of 60 min^{-1} for example to check to see if the servomotor makes one revolution per second.	Check the parameter setting at Pn300 to see if reference speed gain is correct.
Simple Positioning	No. of motor rotations	Input a reference equivalent to one servomotor rotation and visually check to see if the shaft makes one revolution.	Check the parameter setting at Pn201 to see if the number of dividing pulses is correct.
Overtravel (P-OT and N-OT Used)	Whether the servomotor stops rotating when P-OT and N-OT signals are input	Check to see if the servomotor stops when P-OT and N-OT signals are input during continuous servomotor operation.	Review P-OT and N-OT wiring if the servomotor does not stop.

3.3 Minimum Parameters and Input Signals

This section describes the minimum parameters and input signals required for trial operation.

3.3.1 Parameters

See *6.1.6 Operation in Parameter Setting Mode* for more details on setting parameters.

Turn OFF power once after changing any parameter except Pn300. The change will be valid when power is turned ON again.

Basic Parameters

Pn000.1	Function Selection Basic Switches: Control Method Selection	See *4.3.5*.

Speed Control

Pn300	Speed Reference Input Gain	See *4.2.1*.
Pn201	PG Divider	See *4.2.3*.

Position Control

Pn200.0	Reference Pulse Form	See *4.2.2*.
Pn202	Electronic Gear Ratio (Numerator)	See *4.2.5*.
Pn203	Electronic Gear Ratio (Denominator)	See *4.2.5*.

Changing Servomotor Rotation Direction

The wiring may be incorrect if the specified direction of rotation differs from the actual direction of rotation. Recheck the wiring and correct if necessary. Use the following parameter to reverse the direction of rotation.

Pn000.0	Function Selection Basic Switches: Direction Selection	See *4.1.1*.

3.3.2 Input Signals

Refer to the relevant page for details on each input signal.

Input signal selection settings through parameters can be used to eliminate the need for external short circuits.

Signal Name		Pin No.	Contents
/S-ON	Servo ON	CN1-40	See *4.5.2 Using the Servo ON Input Signal* for more details on turning ON and OFF the servomotor.
P-OT	Forward run prohibited	CN1-42	See *4.1.2 Setting the Overtravel Limit Function* for more details on the overtravel limit switch.
N-OT	Reverse run prohibited	CN1-43	

4

Parameter Settings and Functions

This chapter describes the procedure for setting and applying parameters.

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4.1.2 Setting the Overtravel Limit Function ---------- 4-5
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■ Before Reading this Chapter

This chapter describes the use of each CN1 connector I/O signals in the SGDH SERVOPACK as well as the procedure for setting the related parameters for the intended purposes.

The following sections can be used as references for this chapter.

- List of CN1 I/O signals: See *2.4.3 I/O Signal Names and Functions*.
- CN1 I/O signal terminal layout: See *2.4.2 List of CN1 Terminals*.
- List of Parameters: See *Appendix A List of Parameters*.
- Parameter setting procedure: See *6.1.6 Operation in Parameter Setting Mode*.

The CN1 connector is used to exchange signals with the host controller and external circuits.

■ Parameter Configurations

Parameters are comprised of the types shown in the following table. See *Appendix A* .

Type	Parameter No.	Description
Function Selection Constants	Pn000 to Pn003	Select basic and application functions such as the type of control or the stop mode used when an alarm occurs.
Servo Gain and Other Constants	Pn100 to Pn123	Set numerical values such as speed and position loop gains.
Position Control Constants	Pn200 to Pn208	Set position control parameters such as the reference pulse input form and gear ratio.
Speed Control Constants	Pn300 to Pn308	Set speed control parameters such as speed reference input gain and soft start acceleration/deceleration time.
Torque Control Constants	Pn400 to Pn409	Set torque control parameters such as the torque reference input gain and forward/reverse torque limits.
Sequence Constants	Pn500 to Pn512	Set output conditions for all sequence signals and changes I/O signal selections and allocations.
Others	Pn600 to Pn601	Specify the capacity for an external regenerative resistor and reserved constants.
Auxiliary Function Execution	Fn000 to Fn014	Execute auxiliary functions such as JOG Mode operation.
Monitor Modes	Un000 to Un00D	Enable speed and torque reference monitoring, as well as monitoring to check whether I/O signals are ON or OFF.

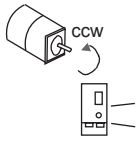
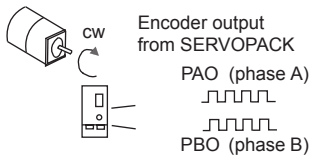
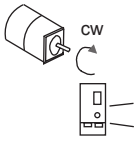
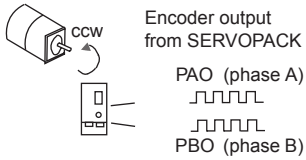
4.1 Settings According to Device Characteristics

This section describes the procedure for setting parameters according to the dimensions and performance of the equipment used.

4.1.1 Switching Servomotor Rotation Direction

The SERVOPACK has a Reverse Rotation Mode that reverses the direction of servomotor rotation without rewiring. Forward rotation in the standard setting is defined as counterclockwise as viewed from the load.

With the Reverse Rotation Mode, the direction of servomotor rotation can be reversed without changing other items. The direction (+, -) of shaft motion is reversed.

	Standard Setting	Reverse Rotation Mode
Forward Reference		
Reverse Reference		

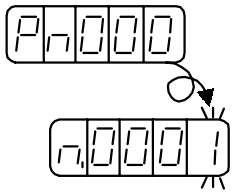
■ Setting Reverse Rotation Mode

Use parameter Pn000.0.

Pn000.0	Rotation Direction Selection	Factory Setting: 0	Speed/Torque Control, Position Control

Use the following settings to select the direction of servomotor rotation.

Setting	Contents	
0	Forward rotation is defined as counterclockwise (CCW) rotation as viewed from the load.	(Standard setting)
1	Forward rotation is defined as clockwise (CW) rotation as viewed from the load.	(Reverse Rotation Mode)



4.1.2 Setting the Overtravel Limit Function

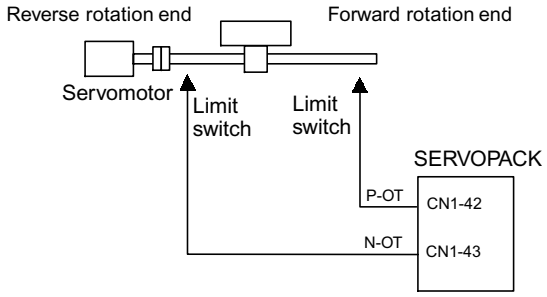
The overtravel limit function forces movable equipment parts to stop if they exceed the allowable range of motion.

■ Using the Overtravel Function

To use the overtravel function, connect the overtravel limit switch input signal terminals shown below to the correct pins of the SERVOPACK CN1 connector.

→ Input P-OT CN1-42	Forward Run Prohibited (Forward Overtravel)	Speed/Torque Control, Position Control
→ Input N-OT CN1-43	Reverse Run Prohibited (Reverse Overtravel)	Speed/Torque Control, Position Control

Connect limit switches as shown below to prevent damage to the devices during linear motion.



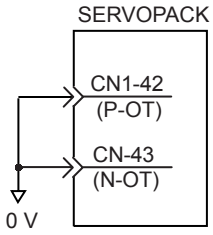
Drive status with an input signal ON or OFF is shown in the following table.

P-OT	CN1-42 at low level when ON	Forward rotation allowed. Normal operation status.
	CN1-42 at high level when OFF	Forward run prohibited (reverse rotation allowed).
N-OT	CN1-43 at low level when ON	Reverse rotation allowed. Normal operation status.
	CN1-43 at high level when OFF	Reverse run prohibited (forward rotation allowed).

■ Enabling/Disabling Input Signals

Set the following parameters to specify whether input signals are used for overtravel or not. The factory setting is "used."

Pn50A.3	P-OT Signal Mapping (Forward Run Prohibit Input Signal)	Factory Setting: 2	Speed/Torque Control, Position Control
Pn50B.0	N-OT Signal Mapping (Reverse Run Prohibit Input Signal)	Factory Setting: 3	Speed/Torque Control, Position Control



The short-circuit wiring shown in the figure can be omitted when P-OT and N-OT are not used.

Parameter	Setting	Item
Pn50A.3	2 (Factory setting)	Uses the P-OT input signal for prohibiting forward rotation. (Forward rotation is prohibited when CN1-42 is open and is allowed when CN1-42 is at 0 V.)
	8	Does not use the P-OT input signal for prohibiting forward rotation. (Forward rotation is always allowed and has the same effect as shorting CN1-42 to 0 V.)
Pn50B.0	3 (Factory setting)	Uses the N-OT input signal for prohibiting reverse rotation. (Reverse rotation is prohibited when CN1-43 is open and is allowed when CN1-43 is at 0 V.)
	8	Does not use the N-OT input signal for prohibiting reverse rotation. (Reverse rotation is always allowed and has the same effect as shorting CN1-43 to 0 V.)

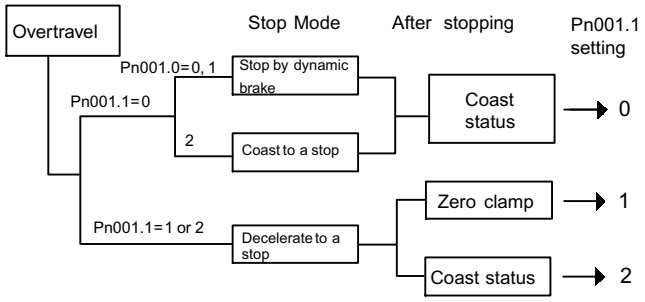
■ Servomotor Stop Mode for P-OT and N-OT Input Signals

Set the following parameters to specify the Servomotor Stop Mode when P-OT and N-OT input signals are used.

Specify the Servomotor Stop Mode when either of the following signals is input during servomotor operation.

- Forward run prohibited input (P-OT, CN1-42)
- Reverse run prohibited input (N-OT, CN1-43)

Pn001.1	Overtravel Stop Mode	Factory Setting: 0	Speed/Torque Control, Position Control



INFO

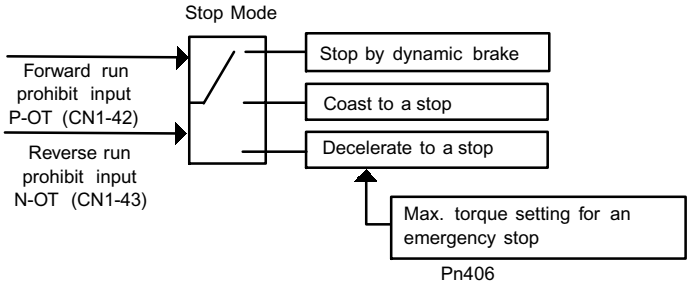
For torque control, the servomotor will be placed in coast status after either decelerating or coasting to a stop (according to the stop mode set in Pn001.0), regardless of the setting of Pn001.1.

Parameter	Setting	Item
Pn001.1	0	Stops the servomotor the same way as turning the servo OFF (according to Pn001.0).
	1	Decelerates the servomotor to a stop at the preset torque, and then locks the servomotor in Zero Clamp Mode. Torque setting: Pn406 emergency stop torque
	2	Decelerates the servomotor to a stop at the preset torque, and puts the servomotor in coast status. Torque setting: Pn406 emergency stop torque

Pn406 specifies the stop torque applied for overtravel when the input signal for prohibiting forward or reverse rotation is used.

The torque limit is specified as a percentage of rated torque.

Pn406	Emergency Stop Torque	Unit: %	Setting Range: 0 to Max. Torque	Factory Setting: 800	Valid when Pn001.1 is 1 or 2



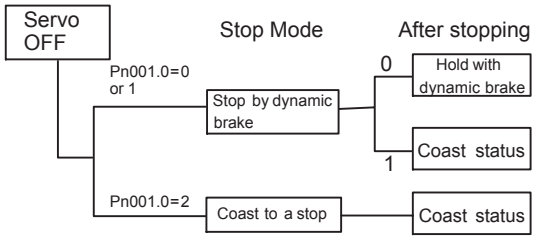
■ Servo OFF Stop Mode Selection

The SGDH SERVOPACK turns OFF under the following conditions:

- The Servo ON input signal (/S-ON, CN1-40) is turned OFF.
- A Servo alarm occurs.
- Power is turned OFF.

Specify the Stop Mode if any of these occurs during operation.

Pn001.0	Servo OFF or Alarm Stop Mode	Factory Setting: 0	



The dynamic brake electrically applies a brake by using a resistor to consume servomotor rotation energy.

See *4.4.2 Using the Dynamic Brake.*

Parameter	Setting	Item
Pn001.0	0 (Factory setting)	Uses the dynamic brake to stop the servomotor. Maintains dynamic brake after the servomotor stops.
	1	Uses the dynamic brake to stop the servomotor. Releases dynamic brake after the servomotor stops, and the servomotor coasts to a stop.
	2	Coasts the servomotor to a stop. The servomotor is turned OFF and stops due to equipment friction.

Note: If the servomotor is stopped or rotating at extremely low speed when the items above are set at 0 (dynamic brake status after stopping with the dynamic brake), then braking power is not generated and the servomotor will stop the same as in coast status.

4.1.3 Limiting Torques

The SGDH SERVOPACK limits torques as follows:

- Level 1: Limits maximum output torque to protect the equipment or workpiece. (Internal Torque Limit)
- Level 2: Limits torque after the servomotor moves the equipment to a specified position. (External Torque Limit)
- Level 3: Always limits output torque rather than speed.
- Level 4: Switches between speed and torque limit.

Application of levels 1 and 2 in the torque limit function are described below.

■ Setting Level 1: Internal Torque Limits

Maximum torque is limited to the values set in the following parameters.

Pn402	Forward Torque Limit	Unit: %	Setting Range: 0 to 800	Factory Setting: 800	Speed/Torque Control, Position Control
Pn403	Reverse Torque Limit	Unit: %	Setting Range: 0 to 800	Factory Setting: 800	Speed/Torque Control, Position Control

This parameter sets the maximum torque limits for forward and reverse rotation.

Use this parameter when torque must be limited due to equipment conditions.

The torque limit function always monitors torque and outputs the signals below when the limit is reached.

The following signals are output by the torque limit function.

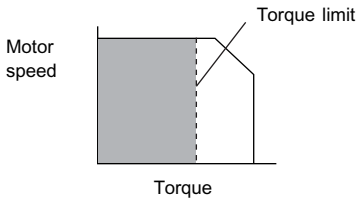
• /CLT • Monitor Mode Un006
Condition that outputs a /CLT signal: Pn50F.0 allocates an output terminal from SO1 to SO3.

The torque limit is specified as a percentage of rated torque.

INFO

If torque limit is set higher than the maximum torque of the servomotor, the maximum torque of the servomotor is the limit.

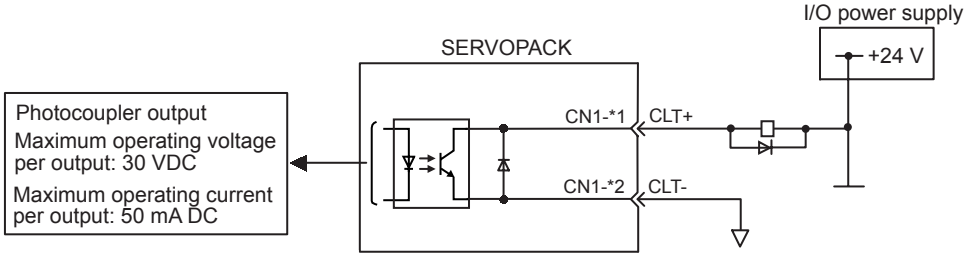
Application Example: Equipment Protection



Too small a torque limit will result in a insufficient torque during acceleration and deceleration.

Using /CLT Signal

The following section describes the use of the contact output signal /CLT as a torque limit output signal.



Output → /CLT CN1-*1	Torque Limit Output	Speed/Torque Control, Position Control

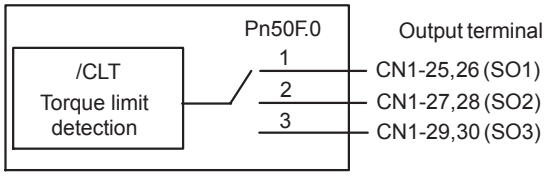
This signal indicates whether servomotor output torque (current) is being limited.

ON Status	The circuit between CN1-*1 and *2 is closed. CN1-*1 is at low level.	Servomotor output torque is being limited. (Internal torque reference is greater than the limit setting.)
OFF Status	The circuit between CN1-*1 and *2 is opened. CN1-*1 is at high level.	Servomotor output torque is not being limited. (Internal torque reference is less than the limit setting.)

Settings: Pn402 (Forward Torque Limit)
Pn403 (Reverse Torque Limit)
Pn404 (Forward External Torque Limit): /P-CL input only
Pn405 (Reverse External Torque Limit): /N-CL input only

When the /CLT signal is used, the following parameter must be used to select the output signal.

Pn50F	Output Signal Selections 2	Factory Setting: 0000	Speed/Torque Control, Position Control



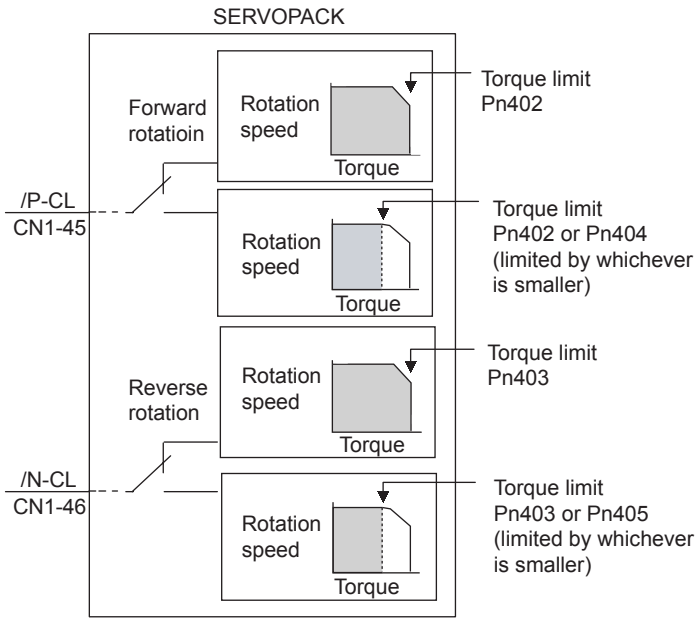
Use the following table to select which terminal will output the /CLT signal.

Parameter	Setting	Output Terminal (CN1-)	
		*1	*2
Pn50F.0	0	-	-
	1	25	26
	2	27	28
	3	29	30

Note: Multiple signals allocated to the same output circuit are output using OR logic. Set other output signals to a value other than that allocated to the /CLT signal in order to output the /CLT signal alone. See *4.3.4 Output Circuit Signal Allocation*.

■ Setting Level 2: External Torque Limit

A contact input signal is used to enable the torque (current) limits previously set in parameters. Torque limits can be set separately for forward and reverse rotation.



→ Input /P-CL CN1-45	Forward External Torque Limit Input	Speed/Torque Control, Position Control
→ Input /N-CL CN1-46	Reverse External Torque Limit Input	Speed/Torque Control, Position Control

This is the external torque (current) limit input for forward and reverse rotation.

Confirm the allocation of input signals when using this function.(Refer to *4.3.3 Input Circuit Signal Allocation*.) Factory settings are given in the following table.

/P-CL	CN1-45 at low level when ON	Use forward torque limit.	Limit: Pn404
	CN1-45 at high level when OFF	Do not use forward torque limit. Normal operation.	-
/N-CL	CN1-46 at low level when ON	Use reverse torque limit.	Limit: Pn405
	CN1-46 at high level when OFF	Do not use reverse torque limit. Normal operation.	-

The following output signals and monitor methods are used when torque is being limited.

• /CLT • Monitor Mode Un005: Nos. 6 and 7 (With factory settings) (Refer to *6.1.7 Operation in Monitor Mode*.) Un006: Depending on output signal allocation conditions.
Condition that outputs a /CLT signal: Pn50F.0 allocates an output terminal from SO1 to SO3.

Application Examples:

- Forced stop.
- Robot holding a workpiece.

Pn404	Forward External Torque Limit	Unit: %	Setting Range: 0 to 800	Factory Setting: 100	Speed/Torque Control, Position Control
Pn405	Reverse External Torque Limit	Unit: %	Setting Range: 0 to 800	Factory Setting: 100	Speed/Torque Control, Position Control

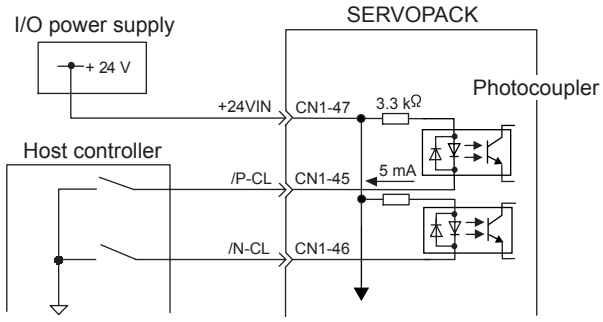
Set the torque limits when the torque is limited by an external contact input.

/P-CL (CN1-45) Input	Pn404 torque limit applied.
/N-CL (CN1-46) Input	Pn405 torque limit applied.

See *4.2.10 Torque Limiting by Analog Voltage Reference, Function 1*.

Using /P-CL and /N-CL Signals

The procedure for using /P-CL and /N-CL as torque limit input signals is illustrated below.

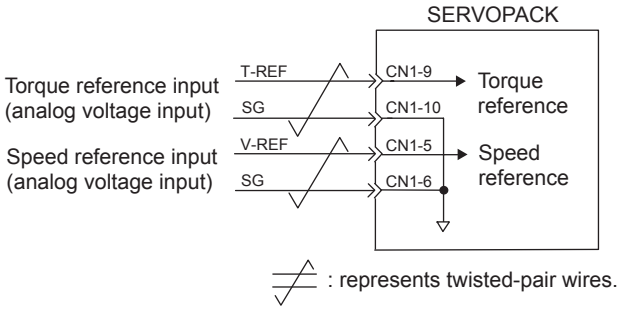


4.2 Settings According to Host Controller

This section describes the procedure for connecting a Σ-II Series Servo to a host controller, including the procedure for setting related parameters.

4.2.1 Speed Reference

Input the speed reference using the following input signal speed reference input. Since this signal has various uses, set the optimum reference input for the system created.

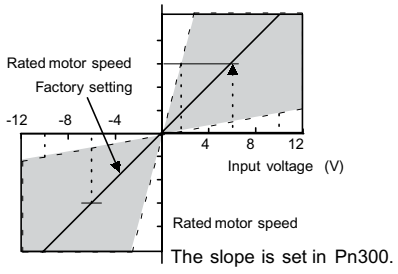


→ Input V-REF CN1-5	Speed Reference Input	Speed Control
→ Input SG CN1-6	Signal Ground	Speed Control

The above inputs are used for speed control (analog reference). (Pn000.1 = 0, 4, 7, 9, or A)

Always wire for normal speed control.

The motor speed is controlled in proportion to the input voltage between V-REF and SG.



■ Setting Examples

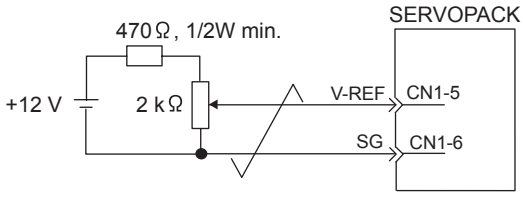
Pn300 = 600: This setting means that 6 V is equivalent to the rated motor speed.

◀ EXAMPLE ▶

Speed Reference Input	Rotation Direction	Motor Speed	SGMBH Servomotor
+6V	Forward rotation	Rated motor speed	1500 min^{-1}
+1V	Forward rotation	(1/6) rated motor speed	250 min^{-1}
-3V	Reverse rotation	(1/2) rated motor speed	750 min^{-1}

Parameter Pn300 can be used to change the voltage input range.

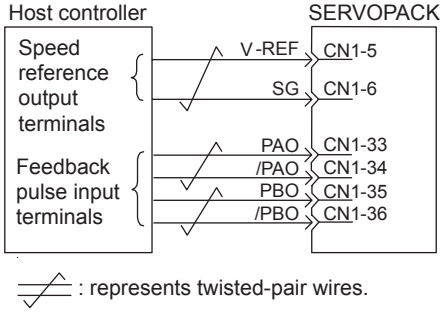
■ Input Circuit Example



- Always use twisted-pair cable for noise control.

  Recommended variable resistor: Model 25HP-10B manufactured by Sakae Tsushin Kogyo Co., Ltd.

Connect V-REF and SG to the speed reference output terminals on the host controller when using a host controller, such as a programmable controller, for position control.

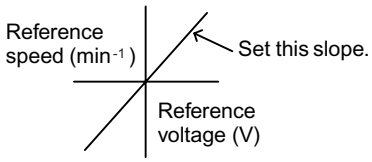


Adjust Pn300 according to output voltage specifications.

Adjust the speed reference input gain at the following parameter.

Pn300	Speed Reference Input Gain	Unit: 0.01V/rated motor speed	Setting Range: 150 to 3000	Speed Control

Set the voltage range for the speed reference input V-REF at CN1-5 according to host controller and external circuit output form.



The factory setting is adjusted so that a 6-V input is equivalent to the rated motor speed of all applicable servomotors.

INFO The maximum allowable voltage to the speed reference input (between CN1-5 and 6) is ± 12 VDC.

Using the /P-CON Signal

→ Input /P-CON CN1-41	Proportional Control Reference	Speed Control, Position Control

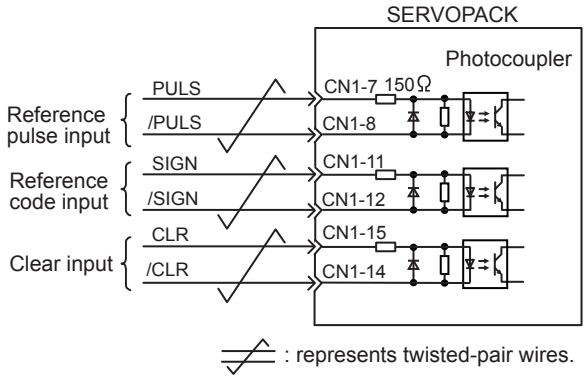
The /P-CON input signal switches the Speed Control Mode from PI (proportional-integral) to P (proportional) control in order to reduce servomotor rotation and minute vibrations due to speed reference input drift. The use of this signal will vary with applications because servomotor rigidity (holding force) drops when the servomotor is stopped.

4.2.2 Position Reference

The reference pulse, reference code, and clear inputs are used for the position reference. Since this signal can be used in different ways; set the optimum reference input for the system created.

■ Reference by Pulse Input

Positioning is controlled by inputting a move reference pulse.

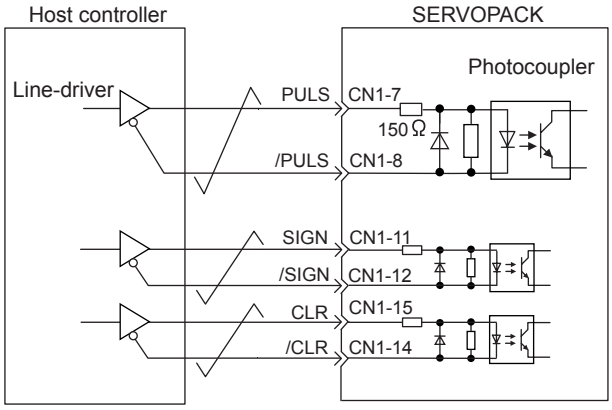


Any of the following forms can be used for the position reference:

- Line-driver output
- +12-V open-collector output
- +5-V open-collector output

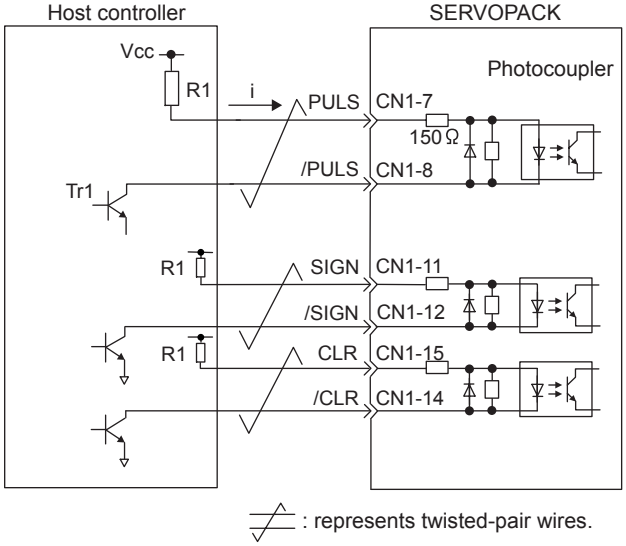
Connection Example 1: Line-driver Output

Applicable line driver: SN75174 manufactured by Texas Instruments Inc., MC3487 or equivalent



Connection Example 2: Open-collector Output

Set limiting resistor R1 so that input current, i, falls within the following range:
Input current i: 7 to 15 mA



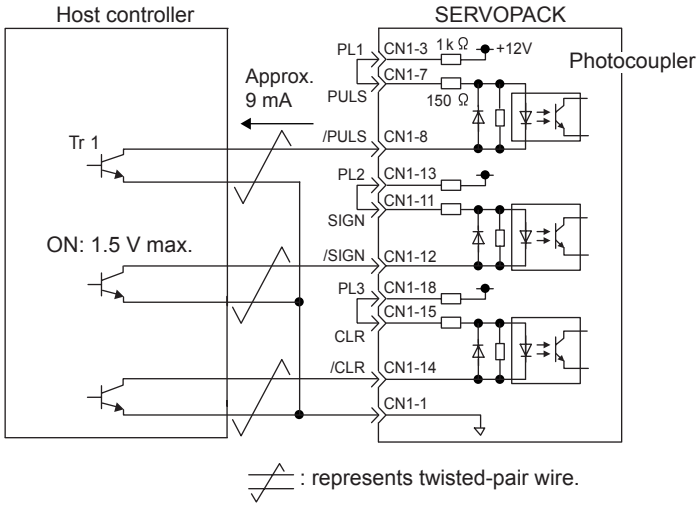
◀ EXAMPLE ▶

- When Vcc is +12 V: R1 = 1 kΩ
- When Vcc is +5 V: R1 = 180 Ω

Note: The following table shows the signal logic for an open-collector output.

When Tr1 is ON	Equivalent to high-level input
When Tr1 is OFF	Equivalent to low-level input

This circuit uses the 12-V power supply built into the SERVOPACK. Input is not insulated.



IMPORTANT

The noise margin of the input signal will decrease if the reference pulse is given using an open-collector output. Set parameter Pn200.3 to 1 if the position drifts due to noise.

■ Selecting a Reference Pulse Form

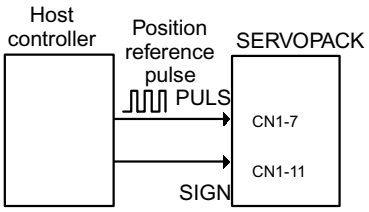
Use the following parameters to select the reference pulse form used.

→ Input PULS CN1-7	Reference Pulse Input	Position Control
→ Input /PULS CN1-8	Reference Pulse Input	Position Control
→ Input SIGN CN1-11	Reference Sign Input	Position Control
→ Input /SIGN CN1-12	Reference Sign Input	Position Control

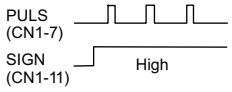
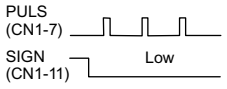
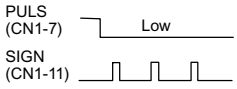
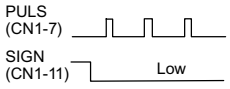
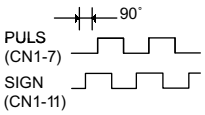
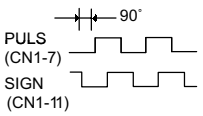
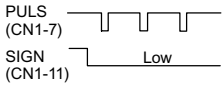
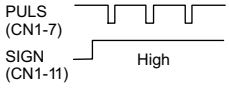
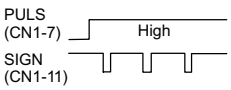
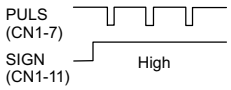
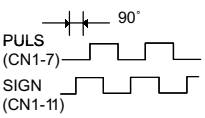
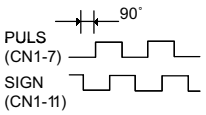
The servomotor only rotates at an angle proportional to the input pulse.

Pn200.0	Reference Pulse Form	Factory Setting: 0	Position Control

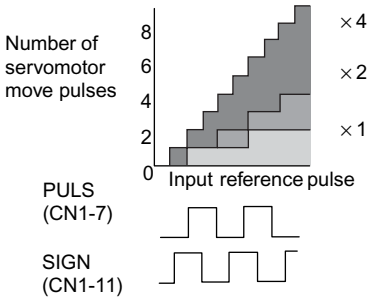
Set reference pulse form input to the SERVOPACK from the host controller.



Since the reference pulse form can be selected from among those listed below, set one according to host controller specifications.

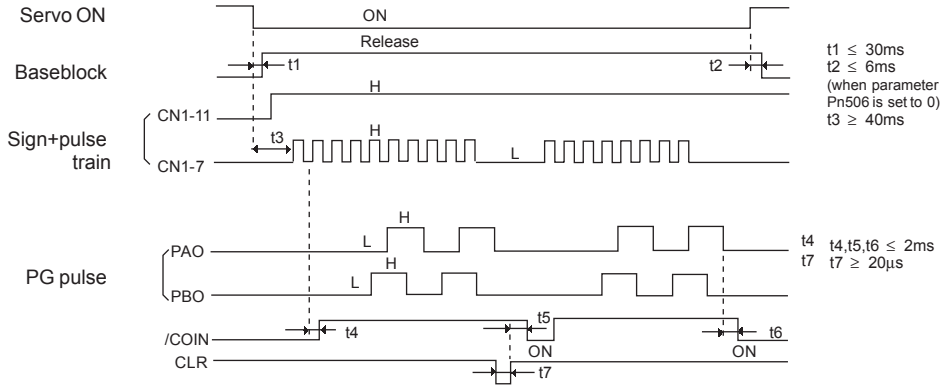
Parameter Pn200.0	Reference Pulse Form	Input Pulse Multiplier	Logic	Forward Rotation Reference	Reverse Rotation Reference
0	Sign + pulse train	-	Positive logic		
1	CW pulse + CCW pulse	-			
2 3 4	Two-phase pulse train with 90° phase differential	× 1 × 2 × 4			
5	Sign + pulse train	-	Negative logic		
6	CW pulse + CCW pulse	-			
7 8 9	Two-phase pulse train with 90° phase differential	× 1 × 2 × 4			

Input Pulse Multiplier



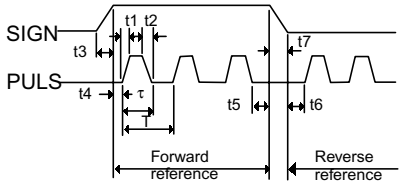
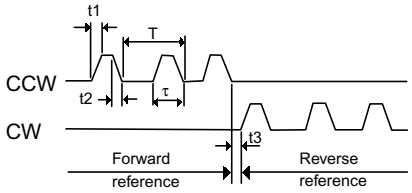
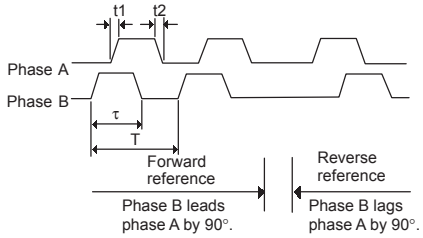
The input pulse multiplier function can be used if the reference form is a two-phase pulse train with a 90° phase differential. The electronic gear function can also be used to convert input pulses.

Example of I/O Signal Generation Timing



Note: 1. The interval from the time the servo ON signal is turned ON until a reference pulse is input must be at least 40 ms. Otherwise the reference pulse may not be input.
2. The error counter clear signal must be ON for at least 20 µs.

Reference Pulse Input Signal Timing

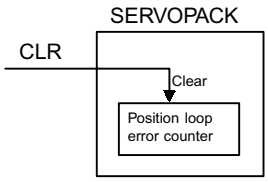
Reference Pulse Form	Electrical Specifications		Comments
Sign + pulse train input (SIGN + PULS signal) Maximum reference frequency: 500 kpps (200-kpps open-collector output)		t1, t2 ≤ 0.1µs t3, t7 ≤ 0.1µs t4, t5, t6 > 3µs τ ≥ 1.0µs (τ/T) × 100 ≤ 50 %	Sign (SIGN) H = Forward reference L = Reverse reference
CW pulse + CCW pulse Maximum reference frequency: 500 kpps (200-kpps open-collector output)		t1, t2 ≤ 0.1µs t3 > 3µs τ ≥ 1.0µs (τ/T) × 100 ≤ 50 %	
Two-phase pulse train with 90° phase differential (phase A + phase B) Maximum reference frequency × 1: 500 kpps (200-kpps open-collector output) × 2: 400 kpps × 4: 200 kpps		t1, t2 ≤ 0.1µs τ ≥ 1.0µs (τ/T) × 100 = 50 %	Parameter Pn200.0 is used to switch the input pulse multiplier mode.

■ Error Counter Clear Input

The procedure for clearing the error counter is described below.

→ Input CLR CN1-15	Clear Input	Position Control
→ Input /CLR CN1-14	Clear Input	Position Control

The following occurs when the CLR signal is set to high level.

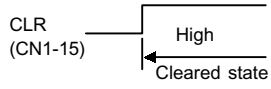
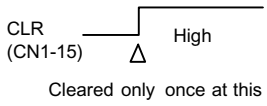
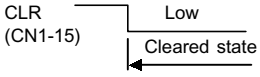
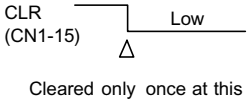


- The error counter inside the SERVOPACK is set to 0.
- Position loop control is prohibited.

Use this signal to clear the error counter from the host controller or select the following clear operation through parameter Pn200.1

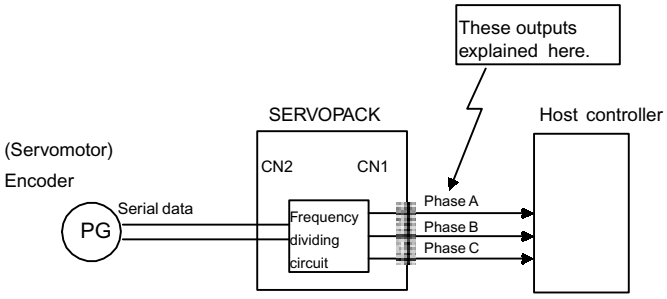
Pn200.1	Error Counter Clear Signal Form	Factory Setting: 0	Position Control

Select the pulse form for the error counter clear signal CLR (CN1-15).

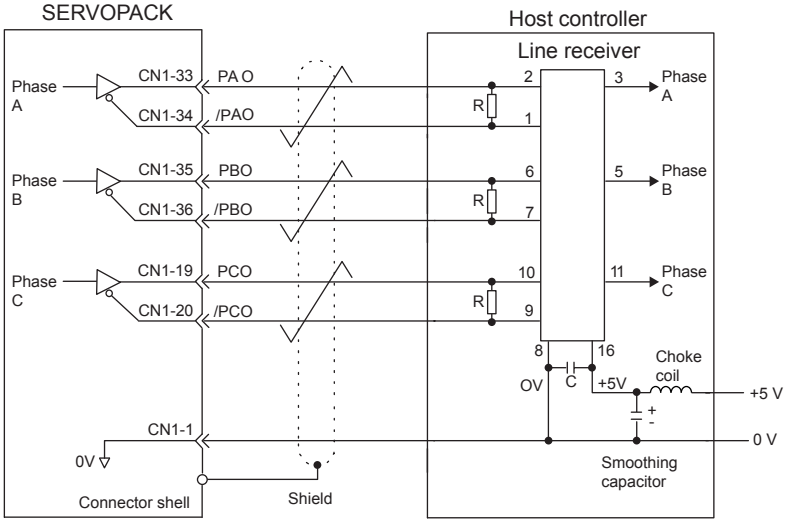
Pn200.1 Setting	Description	Clear Timing
0	Clears the error counter when the CLR signal goes high. Error pulses do not accumulate as long as the signal remains high.	
1	Clears the error counter on the rising edge of the CLR signal. Clears the error counter only once on the rising edge of the CLR signal.	
2	Clears the error counter when the CLR signal goes low. Error pulses do not accumulate as long as the signal remains low.	
3	Clears the error counter on the falling edge of the CLR signal. Clears the error counter only once on the falling edge of the CLR signal.	

4.2.3 Using the Encoder Signal Output

Encoder output signals divided [1] inside the SERVOPACK can be output externally. These signals can be used to form a position control loop in the host controller.



The output circuit is for line-driver output. Connect each signal line according to the following circuit diagram.



: represents twisted-pair wires.

Applicable line receiver: SN75175 manufactured by Texas Instruments Inc., MC3486 or the equivalent.
R (terminator): 220 to 470 Ω
C (decoupling capacitor): 0.1 μF

TERMS

[1] Dividing

Dividing means converting an input pulse train from the encoder mounted on the servomotor according to the preset pulse density and outputting the converted pulse. The units are pulses per revolution.

■ I/O Signals

I/O signals are described below.

Output → PAO CN1-33	Encoder Output Phase A	Speed/Torque Control, Position Control
Output → /PAO CN1-34	Encoder Output Phase /A	Speed/Torque Control, Position Control
Output → PBO CN1-35	Encoder Output Phase B	Speed/Torque Control, Position Control
Output → /PBO CN1-36	Encoder Output Phase /B	Speed/Torque Control, Position Control
Output → PCO CN1-19	Encoder Output Phase C	Speed/Torque Control, Position Control
Output → /PCO CN1-20	Encoder Output Phase /C	Speed/Torque Control, Position Control

Divided encoder signals are output.

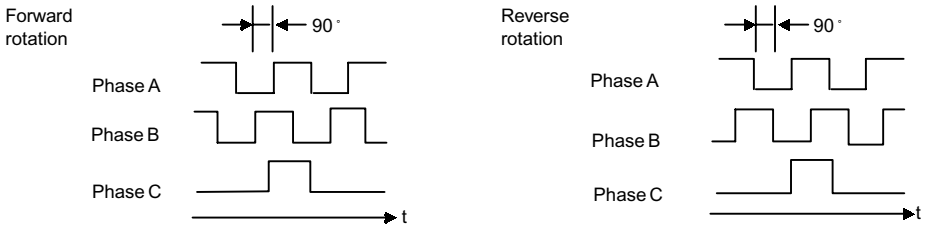
Always connect these signal terminals when a position loop is formed in the host controller for position control.

Set a dividing ratio at the following parameter.

PG Dividing Ratio	Pn201

The dividing ratio setting is not related to the gear ratio setting (Pn202 and 203) for the SERVOPACK electronic gear function during position control.

Output Phase Form



→ Input SEN CN1-4	SEN Signal Input	Speed/Torque Control
→ Input SG CN1-2	Signal Ground	Speed/Torque Control
Output → PSO CN1-48	Encoder Output Phase S	Speed/Torque Control, Position Control
Output → /PSO CN1-49	Encoder Output Phase /S	Speed/Torque Control, Position Control
→ Input BAT (+) CN1-21	Battery (+)	Speed/Torque Control, Position Control
→ Input BAT (-) CN1-22	Battery (-)	Speed/Torque Control, Position Control

Use SEN to BAT (-) signals for absolute encoders. See *4.7 Absolute Encoders* for more details.

Output → SG CN1-1	Signal Ground	Speed/Torque Control, Position Control

SG: Connect to 0 V on the host controller.

IMPORTANT

When using the SERVOPACK phase-C pulse signal to return to the machine origin, always turn the servomotor at least twice before starting the zero point return operation.

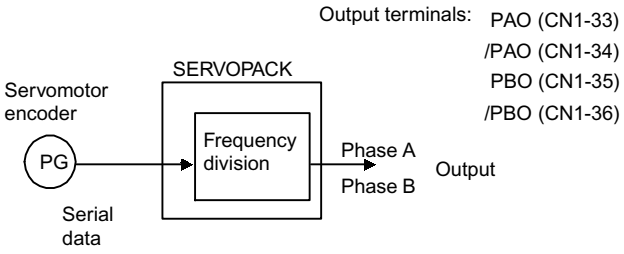
If the configuration of the mechanical system prevents turning the servomotor before the zero point return operation, then perform the zero point return operation at a servomotor speed of 600 min^{-1} or below.The phase-C pulse signal may not be correctly output if the servomotor is turned faster than 600 min^{-1}.

■ Pulse Divider Setting

Set the pulse dividing ratio in the following parameter.

Pn201	PG Divider	Unit: P/R	Setting Range: 16 to 16384	Factory Setting: 16384	Speed/Torque Control, Position Control

This parameter sets the number of output pulses for PG output signals (PAO, /PAO, PBO, /PBO) sent externally.

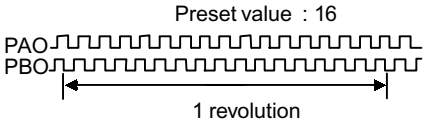


Pulses from the servomotor encoder (PG) are divided by the preset number of pulses before being output.

The set value is the number of output pulses per revolution. Set this value according to the reference unit of the machine or controller to be used.

The setting range varies according to the encoder used.

Setting Example



Servomotor Model and Encoder Specifications	Resolution (Bits)	Number of Encoder Pulses Per Revolution (P/R)	Setting Range
A	13	2048 P/R	16 to 2048
B, 1	16	16384 P/R	16 to 16384
C, 2	17		

INFO

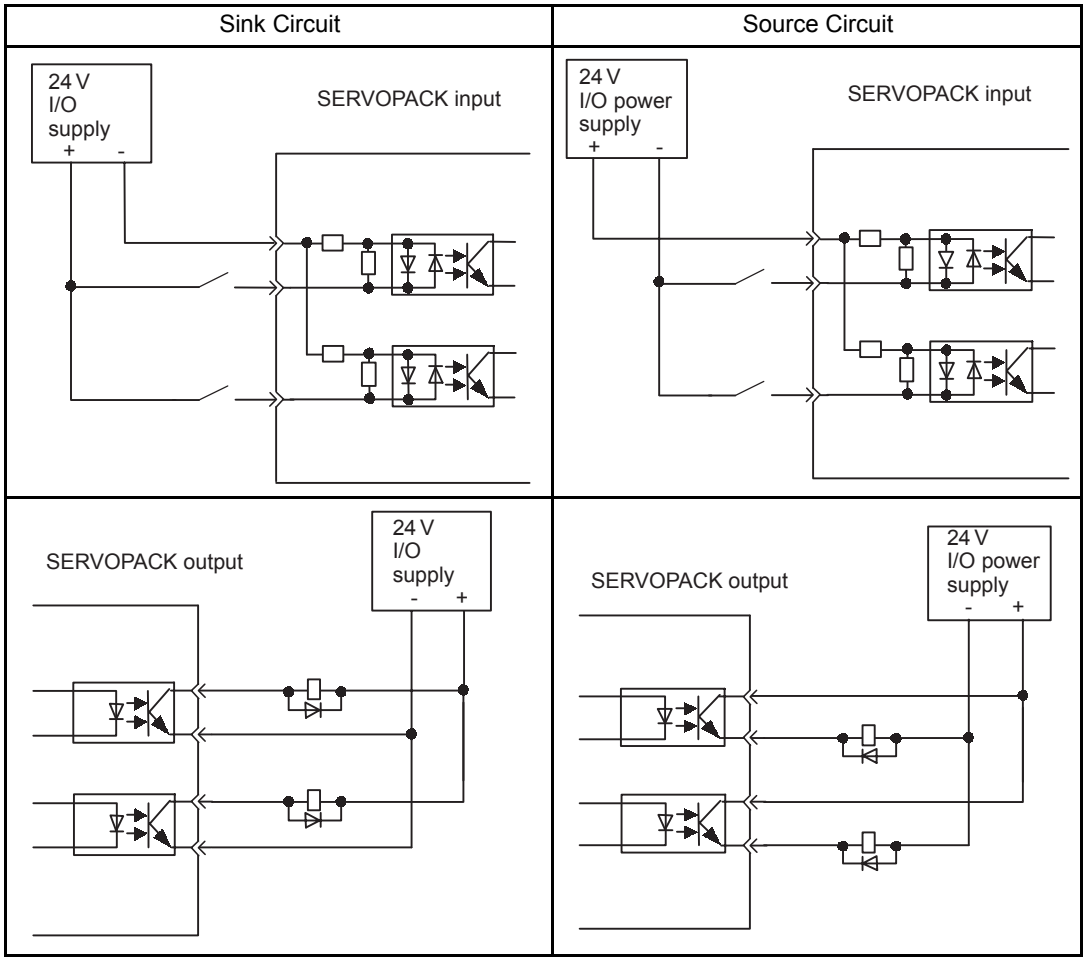
1. Turn OFF power once and turn ON again after changing the parameter.
2. A 13-bit encoder will run at 2048 P/R even if the setting at Pn201 is set higher than 2049.

4.2.4 Sequence I/O Signals

Sequence I/O signals are used to control SERVOPACK operation. Connect these signal terminals as required.

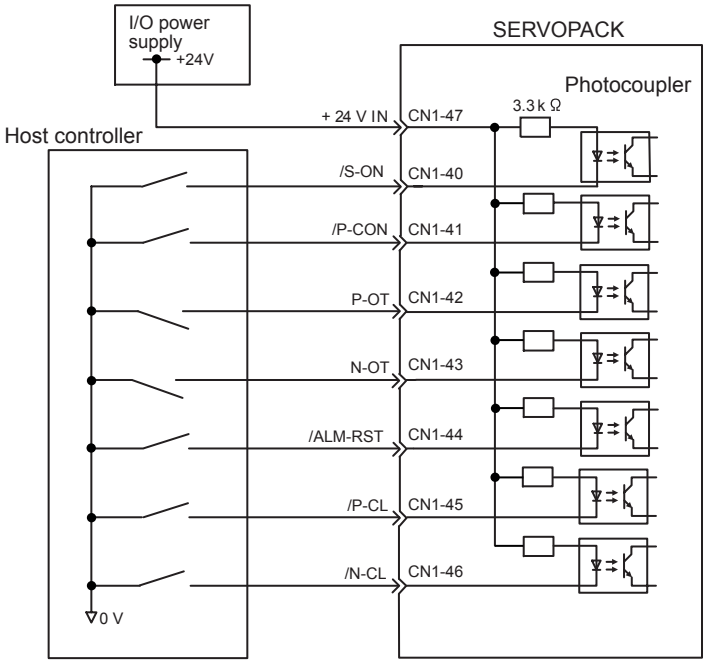
■ Sink Circuit and Source Circuit

The SERVOPACK's I/O circuit uses a bidirectional photocoupler. Select either the sink circuit or the source circuit according to the specifications required for each machine.



■ Input Signal Connections

Connect the sequence input signals as shown below.



IMPORTANT

Provide an external input power supply; the SERVOPACK does not have an internal 24-V power supply.

- External power supply specifications: 24±1 VDC, 50 mA min.

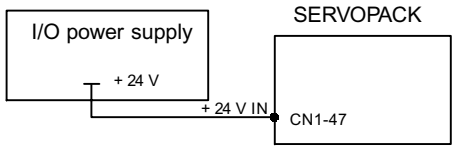
Yaskawa recommends using the same external power supply as that used for output circuits. The allowable voltage range for the 24-V sequence input circuit power supply is 11 to 25 V. Although a 12-V power supply can be used, contact faults can easily occur for relays and other mechanical contacts under low currents. Confirm the characteristics of relays and other mechanical contacts before using a 12-V power supply.

The function allocation for sequence input signal circuits can be changed.

See *4.3.3 Input Circuit Signal Allocation* for more details.

→ Input +24VIN CN1-47	External I/O Power Supply Input	Speed/Torque Control, Position Control

The external power supply input terminal is common to sequence input signals.

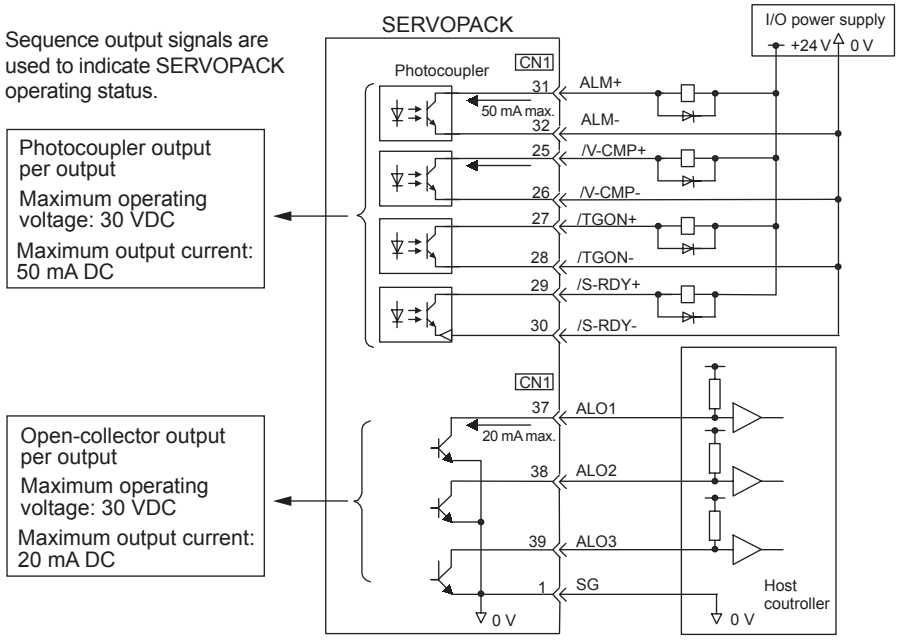


Connect a 24-V external I/O power supply.

Contact input signals:
/S-ON (CN1-40)
/P-CON (CN1-41)
P-OT (CN1-42)
N-OT (CN1-43)
/ALM-RST (CN1-44)
/P-CL (CN1-45)
/N-CL (CN1-46)

■ Output Signal Connections

Connect the sequence output signals as shown in the following figure.



IMPORTANT

Provide an external input power supply; the SERVOPACK does not have an internal 24-V power supply. Yaskawa recommends using the same type of external power supply as that used for input circuits.

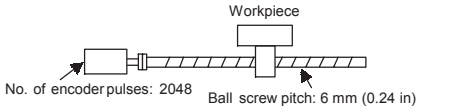
Function allocation for some sequence output signal circuits can be changed.

See *4.3.4 Output Circuit Signal Allocation* for more details.

4.2.5 Using the Electronic Gear Function

The electronic gear function enables the servomotor travel distance per input reference pulse to be set to any value. It allows the host controller generating pulses to be used for control without having to consider the equipment gear ratio or the number of encoder pulses.

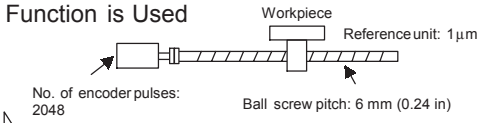
When the Electronic Gear Function is Not Used



To move a workpiece 10 mm (0.39 in):

1 revolution is 6 mm. Therefore,
10 ÷ 6 = 1.6666 revolutions.
2048 × 4 pulses is 1 revolution. Therefore,
1.6666 × 2048 × 4 = 13653 pulses.
13653 pulses are input as references.
The equation must be calculated at the host controller .

When the Electronic Gear Function is Used



Equipment conditions and reference units must be defined for the electronic gear function beforehand.

To move a workpiece 10 mm (0.39 in):
Reference unit is 1µm. Therefore,

$$\frac{10\ mm}{1\ \mu} = 10000\ pulses$$

4

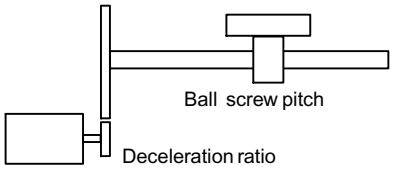
■ Setting the Electronic Gear

Calculate the electronic gear ratio (B/A) using the following procedure, and set the values in parameters Pn202 and 203.

1. Check equipment specifications.

   Items related to the electronic gear:

   - Deceleration ratio
   - Ball screw pitch
   - Pulley diameter



2. Check the number of encoder pulses for the SGMBH servomotor.

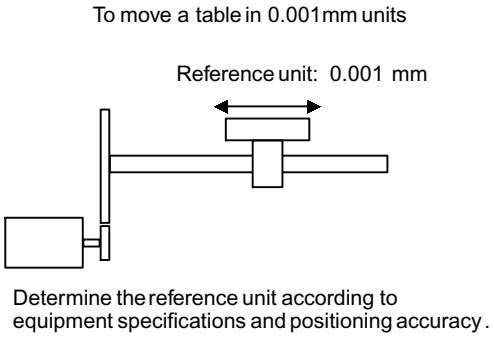
Servomotor Model and Encoder Specifications	Encoder Type	Number of Encoder Pulses Per Revolution (P/R)	
C	Incremental encoder	17-bit	32768
2	Absolute encoder	17-bit	32768
3	Absolute encoder (option)	20-bit	262144

INFO

The number of bits representing the resolution of the applicable encoder is not the same as the number of encoder signal pulses (phase A and B) output from the SERVOPACK.

3. Determine the reference unit used.

   A reference unit is the minimum position data unit used to move a load. (Minimum unit of reference from the host controller.)



◀ EXAMPLE ▶

- 0.01 mm (0.0004 in), 0.001 mm, 0.1°, 0.01 inch.
  A reference unit of one pulse moves the load by one reference unit.
- When the reference unit is 1 μm
  If a reference of 50000 units is input, the load moves 50 mm (1.97 in) (50000 × 1μm).

4. Determine the load travel distance per load shaft revolution in reference units.

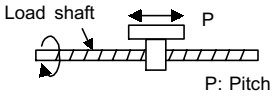
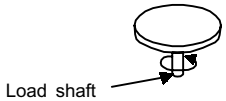
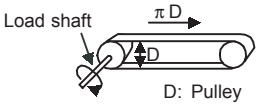
Travel distance per load shaft revolution (reference unit)

$$= \frac{\text{Travel distance per load shaft revolution}}{\text{Reference unit}}$$

◀ EXAMPLE ▶

- When the ball screw pitch is 5 mm (0.20 in) and the reference unit is 0.001 mm

$$\frac{5}{0.001} = 5000 \text{ (reference unit)}$$

Ball Screw	Disc Table	Belt and Pulley
 1 revolution = $\frac{P}{\text{reference unit}}$	 1 revolution = $\frac{360^\circ}{\text{reference unit}}$	 1 revolution = $\frac{\pi D}{\text{reference unit}}$

5. Electronic gear ratio is given as $\left(\frac{B}{A}\right)$.

   If the decelerator ratio of the motor and the load shaft is given as $\left(\frac{n}{m}\right)$ where m is the rotation of the motor and n is the rotation of the load shaft,

$$\text{Electronic gear ratio } \left(\frac{B}{A}\right) = \frac{\text{No. of encoder pulses} \times 4}{\text{Travel distance per load shaft revolution (reference unit)}} \times \frac{m}{n}$$

IMPORTANT

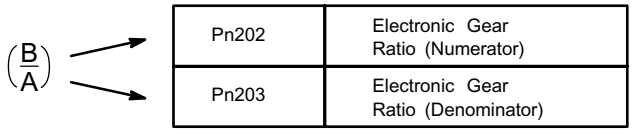
Make sure the electronic gear ratio satisfies the following condition:

$$0.01 \leq \text{Electronic gear ratio}\left(\frac{B}{A}\right) \leq 100$$

The SERVOPACK will not work properly if the electronic gear ratio is outside this range. In this case, modify the load configuration or reference unit.

6. Set the parameters.

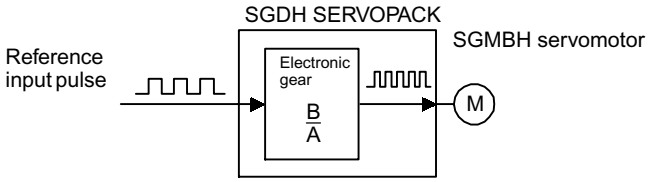
   Reduce the electronic gear ratio $\left(\frac{B}{A}\right)$ to the lower terms so that both A and B are integers smaller than 65535, then set A and B in the respective parameters.



   That is all that is required to set the electronic gear ratio.

Pn202	Electronic Gear Ratio (Numerator)	Unit: None	Setting Range: 1 to 65535	Factory Setting: 4	Position Control
Pn203	Electronic Gear Ratio (Denominator)	Unit: None	Setting Range: 1 to 65535	Factory Setting: 1	Position Control

   Set the electronic gear ratio according to equipment specifications.



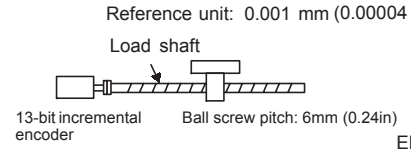
   Electronic gear ratio $\left(\frac{B}{A}\right) = \frac{Pn202}{Pn203}$

- B = [(Number of encoder pulses) × 4] × [motor speed]
- A = [Reference units (travel distance per load shaft revolution)] × [load shaft revolution speed]

■ Electronic Gear Setting Examples

The following examples show electronic gear settings for different load mechanisms.

Ball Screw

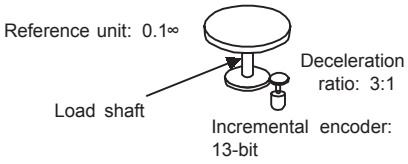


$$\text{Travel distance per load shaft revolution} = \frac{6\ \text{mm}}{0.001\ \text{mm}} = 6000$$

$$\text{Electronic gear ratio } \left(\frac{B}{A}\right) = \frac{2048 \times 4 \times 1}{6000 \times 1} = \frac{Pn202}{Pn203}$$

Preset Values	Pn202	8192
	Pn203	6000

Disc Tables

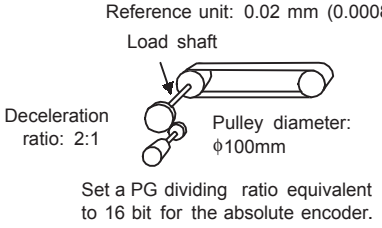


$$\text{Travel distance per load shaft revolution} = \frac{360°}{0.1°} = 3600$$

$$\text{Electronic gear ratio } \left(\frac{B}{A}\right) = \frac{2048 \times 4 \times 3}{3600 \times 1} = \frac{Pn202}{Pn203}$$

Preset Values	Pn202	24576
	Pn203	3600

Belts and Pulleys



$$\text{Travel distance per load shaft revolution} = \frac{3.14 \times 100\ \text{mm}}{0.02\ \text{mm}} = 15700$$

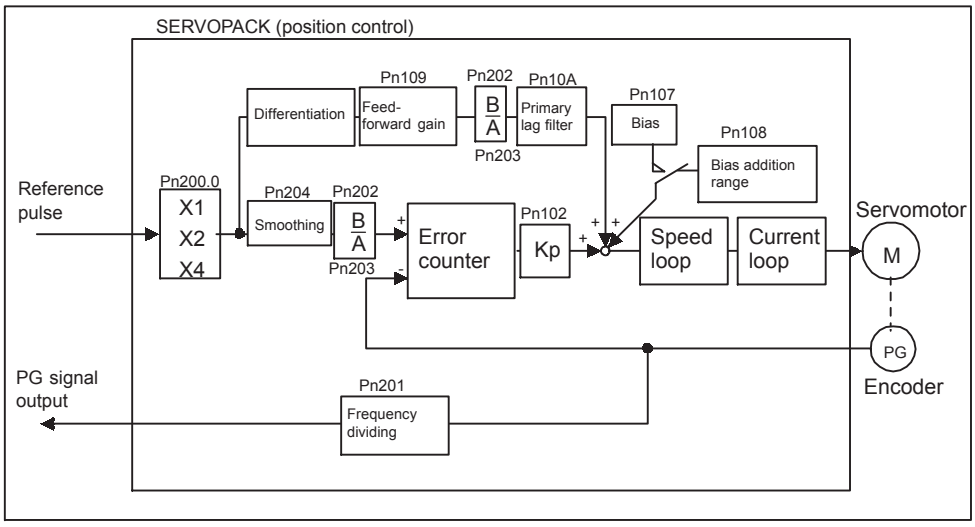
$$\text{Electronic gear ratio } \left(\frac{B}{A}\right) = \frac{16384 \times 4 \times 2}{15700 \times 1} = \frac{Pn202}{Pn203}$$

$$= \frac{131072}{15700} = \frac{32768}{3925}$$

Preset Values	Pn202	32768
	Pn203	3925

■ Control Block Diagram

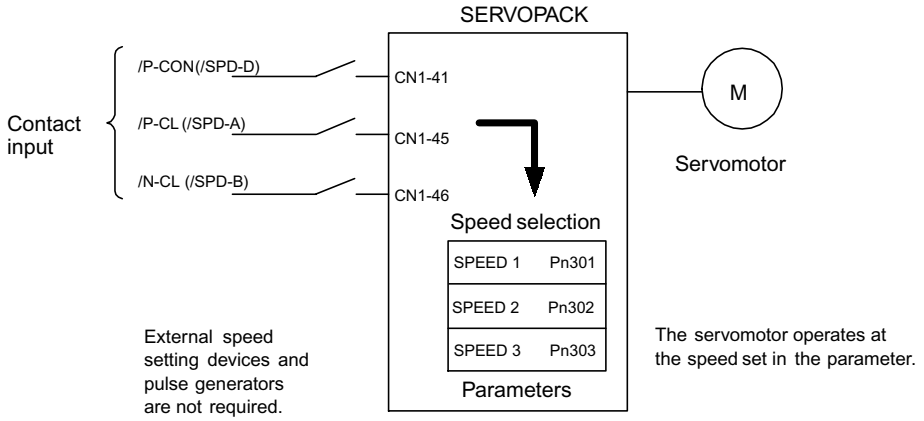
The following diagram illustrates a control block for position control.



4

4.2.6 Contact Input Speed Control

The contact input speed control function provides easy-to-use speed control. It allows the user to initially set three different motor speeds with parameters, select one of the speeds externally by contact input, and operate the servomotor.



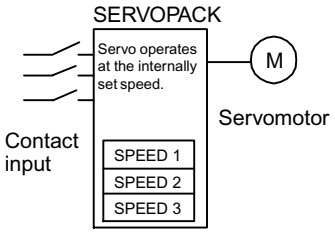
■ Using Contact Input Speed Control

Follow steps 1 to 3 below to use the contact input speed control function.

1. Set contact input speed control as shown below.

Pn000.1	Control Mode Selection	Factory Setting: 0	Speed/Torque Control, Position Control

The speed can be controlled via contact inputs.



Meanings for the following signals change when the contact input speed control function is used.

Pn000.1 Setting	Description	Input Signal			
0, 1, 2, 7, 8, 9, A, B	Contact input speed control function not used.	/P-CON (CN1-41)		Used to switch between P and PI control.	
		/P-CL (CN1-45)		Used to switch between forward external torque limit ON and OFF.	
		/N-CL (CN1-46)		Used to switch between reverse external torque limit ON and OFF.	
3, 4, 5, 6	Contact input speed control function used.	/P-CON (/SPD-D)	/P-CL (/SPD-A)	/N-CL (/SPD-B)	Speed Setting
		Direction of rotation 0: Forward 1: Reverse	0	0	0 reference, etc.
			0	1	SPEED1 (Pn301)
			1	1	SPEED2 (Pn302)
			1	0	SPEED3 (Pn303)

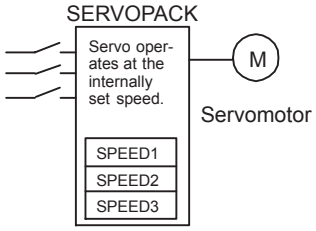
Note: 1. 0: OFF (high level); 1: ON (low level)
2. /P-CON, /P-CL and /N-CL functions change as shown in the table above when Pn000.1 is set to 3, 4, 5, or 6. The function is switched automatically when Pn50A. 0 is set to 0.
3. The /SPD-D, /SPD-A, and /SPD-B signals can be used only when signals are allocated to the input circuits. See *4.3.3 Input Circuit Signal Allocation*.

2. Set the motor speeds with the following parameters.

Pn301	Speed 1 (SPEED 1) (Contact Input Speed Control)	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 100	Speed Control
Pn302	Speed 2 (SPEED 2) (Contact Input Speed Control)	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 200	Speed Control
Pn303	Speed 3 (SPEED 3) (Contact Input Speed Control)	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 300	Speed Control

These parameters are used to set motor speeds when the contact input speed control function is selected. If the setting is higher than the maximum motor speed of the servomotor, then the servomotor will rotate at its maximum speed.

Contact Input Speed Control

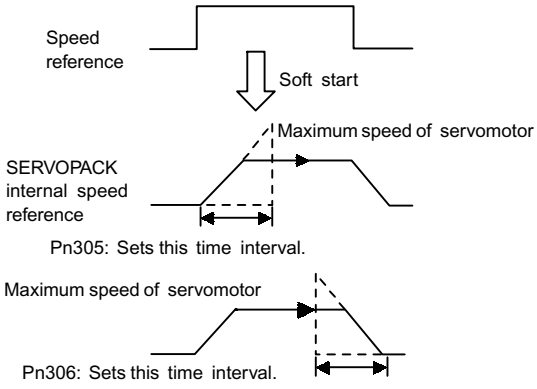


Speed selection input signals /P-CL (SPD-A) (CN1-45) and /N-CL (/SPD-B) (CN1-46) and the rotation direction selection signal /P-CON (/SPD-D) (CN1-41) enable the servomotor to run at the preset speeds.

3. Set the soft start time.

Pn305	Soft Start Acceleration Time	Unit: ms	Setting Range: 0 to 10000	Factory Setting: 0	Speed Control
Pn306	Soft Start Deceleration Time	Unit: ms	Setting Range: 0 to 10000	Factory Setting: 0	Speed Control

The SERVOPACK internal speed reference controls speed by applying this acceleration setting.



Smooth speed control can be performed by inputting a progressive speed reference or using contact input speed control. Set each constant to 0 for normal speed control.

Set these parameters as follows:

- Pn305: The time interval from the time the motor starts until the motor maximum speed is reached.
- Pn306: The time interval from the time the motor is operating at the motor maximum speed until it stops.

■ Operation by Contact Input Speed Control

The following describes operation by contact input speed control.

Start and Stop

The following input signals are used to start and stop the servomotor.

→ Input /P-CL CN1-45	Speed Selection 1 (Forward External Torque Limit Input)	Speed/Torque Control, Position Control
→ Input /N-CL CN1-46	Speed Selection 2 (Reverse External Torque Limit Input)	Speed/Torque Control, Position Control

- Use the following table when contact input speed control is used.

Contact Signal			Parameter	Selected Speed
/P-CON (/SPD-D)	/P-CL (/SPD-A)	/N-CL (/SPD-B)	Pn000.1	
-	0	0	3	Stopped by an internal speed reference of 0.
			4	Analog speed reference (V-REF) input
			5	Pulse reference input (position control)
			6	Analog torque reference input (torque control)
Direction of rotation 0: Forward 1: Reverse	0	1	3, 4, 5, 6 Common	SPEED 1 (Pn301)
	1	1		SPEED 2 (Pn302)
	1	0		SPEED 3 (Pn303)

Note: 1. 0: OFF (high level); 1: ON (low level)
2. Input signals indicated by the horizontal bar (-) are optional.

- When contact input speed control is not used, input signals are used as external torque limit inputs.

INFO

The contact input speed control function is used only when signals are allocated to /SPD-D, /SPD-A, and /SPD-B.

Direction of Rotation Selection

The input signal /P-CON (/SPD-D) is used to specify the direction of servomotor rotation.

→ Input P-CON CN1-41	Proportional Control Reference, etc.	Speed/Torque Control, Position Control

- When contact input speed control is used, the input signal /P-CON (/SPD-D) specifies the direction of servomotor rotation.

/P-CON (/SPD-D)	Meaning
0	Forward rotation
1	Reverse rotation

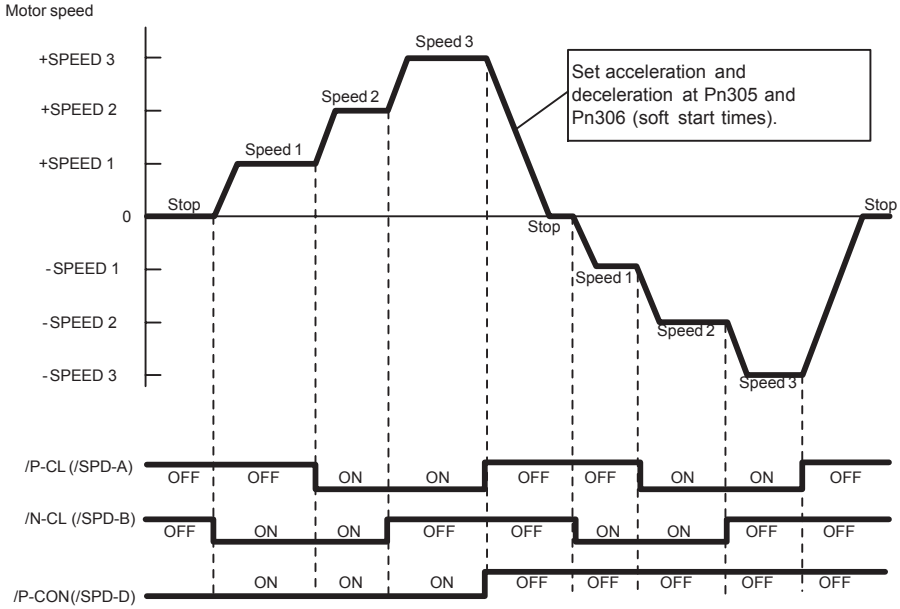
Note: 0: OFF (high level); 1: ON (low level)

When contact input speed control is not used, the /P-CON signal is used for proportional control, zero clamping, and torque/speed control switching.

■ Example of Contact Input Speed Control Operation

The following example shows operation by contact input speed control. Using the soft start function reduces physical shock when the speed is changed.

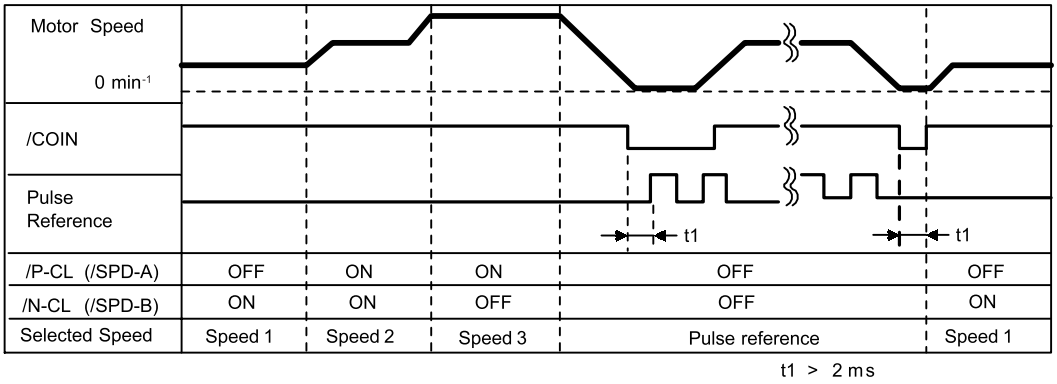
Contact Input Speed Control



IMPORTANT

The soft start function is available only when contact input speed control is used with Pn000.1 set to 5, and is not available when a pulse reference input is used. If Contact Input Speed Control Mode is switched to Pulse Reference Input Mode while the servomotor is operating at speed 1, speed 2, or speed 3, the SERVOPACK will not receive a reference pulse until the positioning completed signal / COIN is output. Always start pulse reference output from the host controller after a positioning completed signal is output from the SERVOPACK.

Signal Generation Timing for Position Control



Note: 1. The above figure illustrates signal generation timing when the soft start function is used.
2. The value of t1 is not affected by the use of the soft start function. A maximum 2-ms delay occurs when the /P-CL (/SPD-A) or /N-CL (/SPD-B) signal is read.

4.2.7 Using Torque Control

The SGDH SERVOPACK limits torque as shown below.

- Level 1: Limits maximum output torque to protect the equipment or workpiece. (internal torque limit)
- Level 2: Limits torque after the servomotor moves the equipment to a specified position. (external torque limit)
- Level 3: Always limits output torque rather than speed.
- Level 4: Switches between speed and torque limit.

The following describes uses for levels 3 and 4 in the torque control function.

■ Torque Control Selection

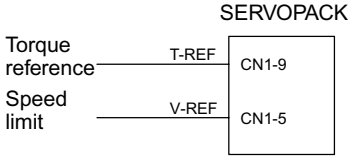
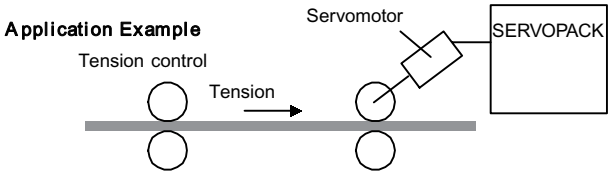
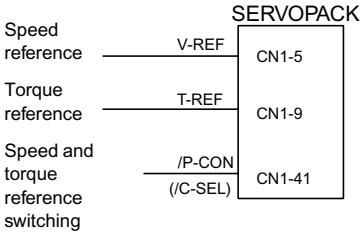
Set in the following parameters to select level 3 or 4 torque control.

Pn000.1	Control Mode Selection	Factory Setting: 0	Speed/Torque Control, Position Control

A torque reference is input from the host controller to the SERVOPACK in order to control torque.

Application Examples

- Tension control
- Pressure control

Pn000.1	Control Mode
2	**Torque Control** This is a dedicated Torque Control Mode. • A torque reference is input from T-REF (CN1-9). • Speed reference input V-REF (CN1-5) can be used for speed control if Pn002.1 is set to 1. • Parameter Pn407 can be used for maximum speed control.  **Application Example** 
9	**Torque Control ↔ Speed Control (Analog Reference)** Switches between torque and speed control. • V-REF (CN1-5) inputs a speed reference or speed limit. • T-REF (CN1-9) inputs a torque reference, torque feed-forward reference or torque limit depending on the control mode. • /P-CON (/C-SEL) (CN1-41) is used to switch between torque and speed control.  CN1-41 is open. — Torque control CN1-41 is 0 V. — Speed control **Torque Control: When /P-CON (/C-SEL) is OFF** • The T-REF reference controls toque. • V-REF can be used to limit servomotor speed when Pn002.1 is set to 1. V-REF voltage (+) limit servomotor speed during forward and reverse rotation. • Parameter Pn407 can be used to limit the maximum servomotor speed.

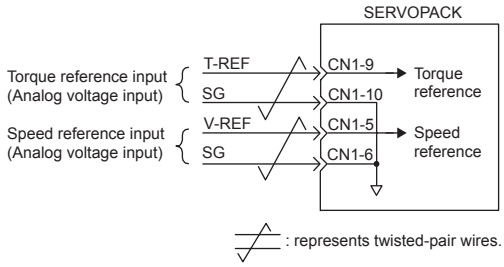
<table>
<tr><th>Pn000.1</th><th>Control Method</th></tr>
<tr><td>9</td><td>Speed Control: When /P-CON (/C-SEL) is ON
Set the parameter Pn002.0 as shown below.
<table>
<tr><th>Parameter Pn002.0</th><th>Torque Reference Input (T-REF) (CN1-9,10)</th><th>Contents</th><th>Remarks</th></tr>
<tr><td>0</td><td>-</td><td>Normal speed control</td><td></td></tr>
<tr><td>1</td><td>Torque limit input</td><td>Torque limit speed control by analog voltage reference</td><td>See 4.2.10 Torque Limiting by Analog Voltage Reference, Function 1 for more details on torque limit speed control by analog voltage reference.</td></tr>
<tr><td>2</td><td>Torque feed-forward input</td><td>Speed control with torque feed-forward</td><td>See 4.2.8 Torque Feed-forward Function for more details on torque feed-forward speed control.</td></tr>
</table></td></tr>
<tr><td>8</td><td>Position Control ↔ Torque Control
Can be used to switch between speed (contact reference) and torque control.
• /P-CON (/C-SEL) (CN1-41) is used to switch between position and torque control.
<table>
<tr><td>CN1-41 is open.</td><td>Position control</td></tr>
<tr><td>CN1-41 is 0 V.</td><td>Torque control</td></tr>
</table>
Position Control: When /P-CON (/C-SEL) is OFF
Set the parameter Pn002.0 as shown below.
<table>
<tr><th>Parameter Pn002.0</th><th>Torque Reference Input (T-REF) (CN1-9,10)</th><th>Contents</th><th>Remarks</th></tr>
<tr><td>0</td><td>-</td><td>Normal position control</td><td></td></tr>
<tr><td>1</td><td>Torque limit input</td><td>Torque limit position control by analog voltage reference</td><td>See 4.2.10 Torque Limiting by Analog Voltage Reference, Function 1 for more details on torque limit position control by analog voltage reference.</td></tr>
<tr><td>2</td><td>Torque feed-forward input</td><td>Position control with torque feed-forward</td><td>See 4.2.8 Torque Feed-forward Function for more details on torque feed-forward position control.</td></tr>
</table></td></tr>
<tr><td>6</td><td>Speed Control (Contact Reference) ↔ Torque Control
Can be used to switch between speed (contact reference) and torque control.
• /P-CL (/SPD-A) (CN1-45) and /N-CL (SPD-B) (CN1-46) are used to switch control.
<table>
<tr><th>/P-CL (/SPD-A) CN1-45</th><th>/N-CL (/SPD-B) CN1-46</th><th></th></tr>
<tr><td>0</td><td>0</td><td>Torque control</td></tr>
<tr><td>0</td><td>1</td><td rowspan="3">Speed control (Contact reference)</td></tr>
<tr><td>1</td><td>1</td></tr>
<tr><td>1</td><td>0</td></tr>
</table>
0: OFF
1: ON</td></tr>
</table>

Note: Input signal /C–SEL can be used only when a signal is allocated to the input circuit. See *4.3.3 Input Circuit Signal Allocation*.

■ Input Signals

Torque Reference Inputs

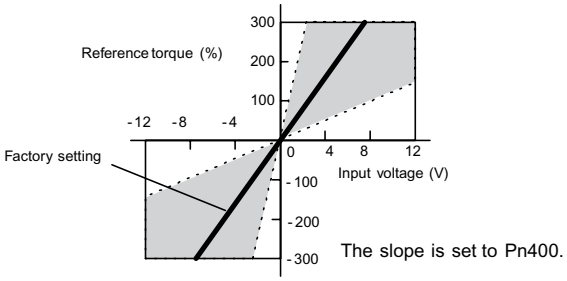
The following input signals are used for torque control.



→ Input T-REF CN1-9	Torque Reference Input	Speed/Torque Control
→ Input SG CN1-10	Signal Ground for the Torque Reference Input	Speed/Torque Control

These signals are used when torque control is selected.

Servomotor torque is controlled so that it is proportional to the input voltage between T-REF and SG.



- Factory Settings

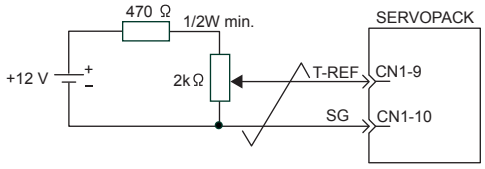
  Pn400 = 30: This setting means that 3 V is equivalent to the rated torque.

◀ EXAMPLE ▶

  +3 V input: Rated torque in the forward direction
  +9 V input: 300% of rated torque in the forward direction
  -0.3 V input: 10% of rated torque in the reverse direction

  Parameter Pn400 can be used to change the voltage input range.

- Example of an Input Circuit



Always use twisted-pair cable for noise control.

Recommended variable resistor: Model 25HP-10B manufactured by Sakae Tsushin Kogyo Co., Ltd.

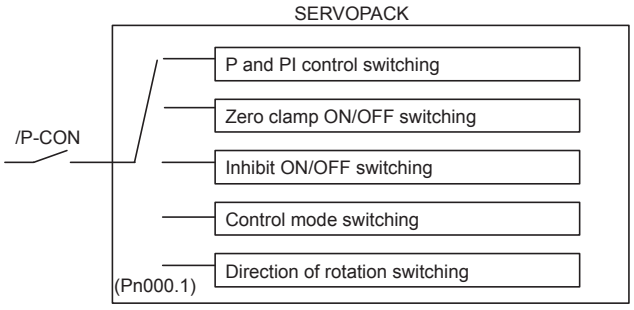
Speed Reference Inputs

Refer to *4.2.1 Speed Reference*.

Using the /P-CON Signal

→ Input /P-CON CN1-41	Proportional Control, etc.	Speed/Torque Control, Position Control

The function of the input signal /P-CON varies with the setting at Pn000.1.



Pn000.1 Setting	/P-CON Function
0, 1	Switches between P (proportional) and PI (proportional-integral) control.
2	Not used.
3, 4, 5, 6	Switches the direction of rotation in Contact Input Speed Control Mode.
7, 8, 9	Switches the control mode.
A	Turns ON/OFF zero clamp.
B	Turns inhibit ON/OFF.

INFO

The /P-CON signal function switches automatically when Pn50A.0 is set to 0.

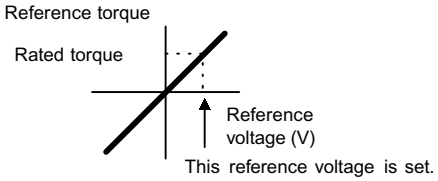
■ Parameters

The following parameter is used for torque control. Set the parameter according to the servo system used.

Pn400	Torque Reference Input Gain	Unit: 0.1 V/rated torque	Setting Range: 10 to 100	Factory Setting: 30	Speed/Torque Control

The parameter sets the voltage range for torque reference input T-REF (CN1-9). Set the range according to host computer and the output state of external circuit.

The factory setting is 30, so the rated torque output is 3 V (30×0.1).



Two speed limit functions during torque control are available by the parameter setting as shown below.

Pn200.1 Setting	Description
0	Uses speed limit set by Pn407. (internal speed limit function)
1	Uses V-REF (CN1-5 and 6) as external speed limit input and sets speed limit by voltage which input to V-REF and Pn300. (external speed limit function)

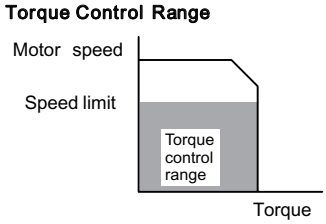
Internal Speed Limit Function

Pn407	Speed Limit during Torque Control	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 10000	Speed/Torque Control

The parameter sets a motor speed limit when torque control is selected.

It is used to prevent excessive equipment speed during torque control.

Since the speed limit detection signal /VLT functions the same in torque control as the /CLT signal, see *4.1.3 Limiting Torques*, where the /CLT signal is described.



The maximum speed of the servomotor will be used if Pn407 is set to a value higher than the maximum speed of the servomotor.

External Speed Limit Function

This function uses V-REF (CN1-5) as external speed limit input and sets input voltage range by Pn300. Set the range according to host computer and the output state of external circuit.

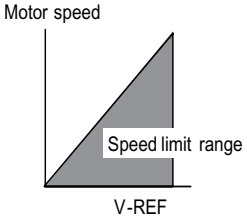
Pn300	Speed Reference Input Gain	Unit: 0.01V/rated speed	Setting Range: 150 to 3000	Factory Setting: 600	Speed/Torque Control

The factory setting is ±1% of the rated motor speed or 6 V.

INFO

■ Principle of Speed Control

Torque reversely proportional to the difference between the speed limit and the speed is fed back to return the system to within the control speed range when the control speed range is exceeded. The actual motor speed limit will thus be increased by negative loads.

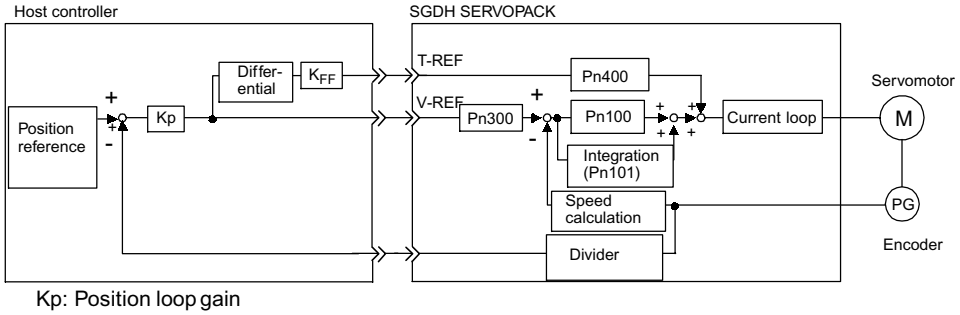


4.2.8 Torque Feed-forward Function

The torque feed-forward function is used only in control mode except for torque control.

This function shortens positioning time, differentiates a speed reference at the host controller to generate a torque feed-forward reference, and inputs this reference together with the speed reference to the SERVOPACK. Too high a torque feed-forward value will result in overshooting or undershooting. To prevent this, set the optimum value while observing system response.

Connect a speed reference signal line to V-REF (CN1-5 and 6) and a torque feed-forward reference signal line to T-REF (CN1-9 and 10).



Kp: Position loop gain

K_{FF}: Feed-forward gain

■ Using the Torque Feed-forward Function

To use the torque feed-forward function, set the following parameter to 2.

Pn002.0	Speed Control Option (T-REF Terminal Allocation)	Factory Setting: 0	Speed Control, Position Control

This setting enables the torque feed-forward function.

Pn002.0 Setting	Description
0	None.
1	T-REF terminal used for external torque limit input.
2	T-REF terminal used for torque feed-forward input.

The torque feed-forward function cannot be used with torque limiting by analog voltage reference described in *4.2.10 Torque Limiting by Analog Voltage Reference, Function 1*.

■ Setting

Torque feed-forward is set using parameter Pn400.

The factory setting at Pn400 is 30. If, for example, the torque feed-forward value is ±3 V, then torque is limited to ±100% of the rated torque.

Pn400	Torque Reference Input Gain	Unit: 0.1 V/rated torque	Setting Range: 10 to 100	Factory Setting: 30	Speed/Torque Control, Position Control

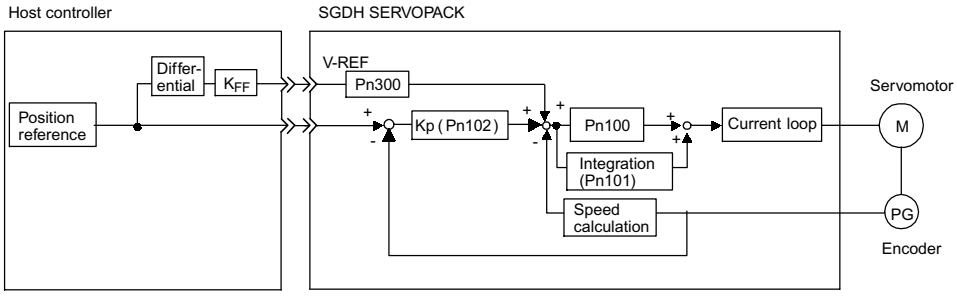
4.2.9 Speed Feed-forward Function

The speed feed-forward function uses analog voltages and is effective only for position control.

The feed-forward function can be used to shorten positioning time. The host controller creates a feed-forward reference based on the differential of the position reference.

Overshooting and undershooting can result if too much feed-forward is used. Set the optimum settings based on the actual response.

The position reference from the host controller is connected to PULS and SIGN (CN1-7, 8, 11, and 12) and the speed feed-forward reference is connected to V-REF (CN1-5 and 6).



Kp: Position loop gain
K_{FF}: Feed-forward gain

■ Using the Speed Feed-forward Function

Set the following parameter to 1 to use the analog voltage speed feed-forward function.

Pn207.1	Position Control Option	Factory Setting: 0	Position Control

This setting will enable the speed feed-forward function.

Pn207.1 Setting	Description
0	No feed-forward function
1	V-REF terminal used for a speed feed-forward input.

■ Setting

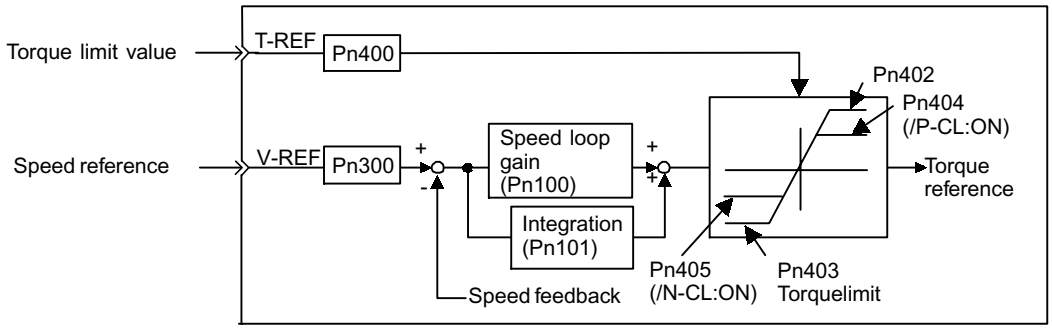
The speed feed-forward value is set in parameter Pn300.

The factory setting of Pn300 is 600, for which a speed feed-forward value of ±6 V will produce the rated speed.

Pn300	Speed Reference Input Gain	Unit: 0.01V/ rated speed	Setting Range: 150 to 3000	Factory Setting: 600	Speed/Torque Control, Position Control

4.2.10 Torque Limiting by Analog Voltage Reference, Function 1

Torque limiting by analog voltage reference limits torque by assigning a torque limit in an analog voltage to the T-REF terminal (CN1-9 and 10). It cannot be used for torque control because the torque reference input terminal T-REF is used as an input terminal.



■ Using Torque Limiting by Analog Voltage Reference

To use this function, set the following parameter to 1.

Pn002.0	Speed Control Option (T-REF Terminal Allocation)	Factory Setting: 0	Speed Control, Position Control

This parameter can be used to enable torque limiting by analog voltage reference.

Torque limiting cannot be set separately for forward and reverse rotation.

Pn002.0 Setting	Description
0	None.
1	T-REF terminal used for external torque limit input.
2	T-REF terminal used for torque feed-forward input.

This function cannot be used with the torque feed-forward function described in *4.2.8 Torque Feed-forward Function*.

■ Setting

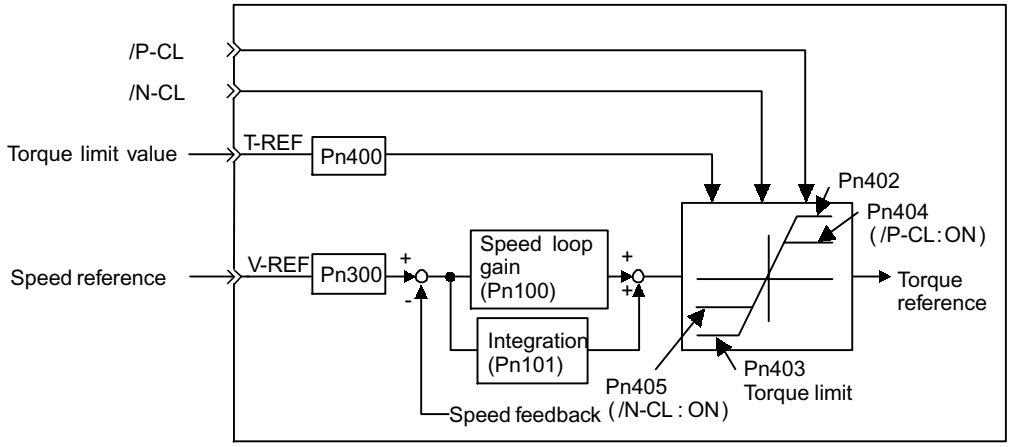
The torque limit input gain is set at parameter Pn400.

The factory setting at Pn400 is 30. If, for example, the torque limit is ±3 V, then torque is limited to 100% of the rated torque. (A torque value higher than 100% torque is clamped at 100%.)

Pn400	Torque Reference Input Gain	Unit: 0.1 V/rated torque	Setting Range: 10 to 100	Factory Setting: 30	Speed/Torque Control, Position Control

4.2.11 Torque Limiting by Analog Voltage Reference, Function 2

Torque limiting by analog voltage reference limits torque by assigning a torque limit in an analog voltage to the T-REF terminal (CN1-9 and 10). It cannot be used for torque control because the torque reference input terminal T-REF is used as an input terminal. If the /P-CL signal (CN1-45) is ON, a forward torque limit is applied, and if the /N-CL signal (CN1-46) is ON, a reverse torque limit is applied.



■ Using Torque Limiting by Analog Voltage Reference

To use this function, set the following parameter to 3.

Pn002.0	Speed Control Option (T-REF Terminal Allocation)	Factory Setting: 0	Speed/Position Control

This setting will enable torque limiting by analog voltage reference, function 2.

Pn002.0 Setting	Description
0	None
1	T-REF terminal used for external torque limit input.
2	T-REF terminal used for torque feed-forward input.
3	T-REF terminal used for external torque limiting input when P-CL or N-CL is ON.

This torque limiting function cannot be used at the same time as the torque feed-forward function.

Confirm the allocation of input signals when using this function. (Refer to *4.3.3 Input Circuit Signal Allocation*.) Factory settings are given in the following table.

/P-CL	CN1-45 at low level when ON	Forward torque limit applied.	Limit: Pn404 or T-REF input, whichever is smaller.
	CN1-45 at high level when OFF	Forward torque limit not applied. Normal operation.	-
/N-CL	CN1-46 at low level when ON	Reverse torque limit applied.	Limit: Pn405 or T-REF input, whichever is smaller.
	CN1-46 at high level when OFF	Reverse torque limit not applied. Normal operation.	-

■ Setting

The torque limit input gain is set at parameter Pn400.

The factory setting at Pn400 is 30. If, for example, the torque limit is ±3 V, then torque is limited to 100% of the rated torque. (A torque value higher than 100% torque is clamped at 100%. A 100% torque will also be used as the limit if the input torque limit value is -3 V.)

Pn400	Torque Reference Input Gain	Unit: 0.1 V/rated torque	Setting Range: 10 to 100	Factory Setting: 30	Speed/Torque Control, Position Control

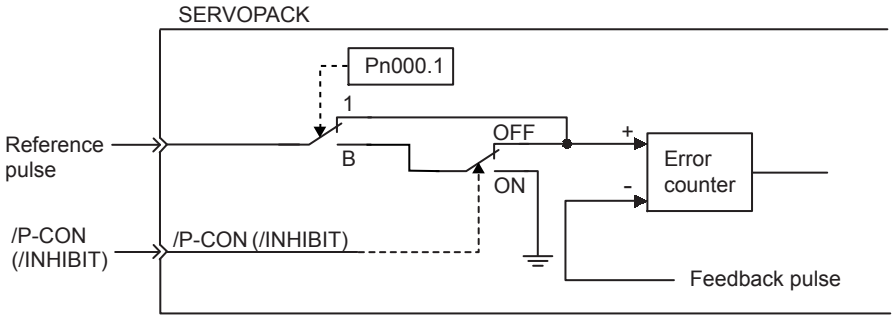
The settings of the following parameters are also valid. The torque limit will be either the torque limit value for the analog voltage reference or the setting of Pn404/Pn405, whichever is smaller.

Pn404	Forward External Torque Limit	Unit: %	Setting Range: 0 to 800	Factory Setting: 100	Speed/Torque Control, Position Control
Pn405	Reverse External Torque Limit	Unit: %	Setting Range: 0 to 800	Factory Setting: 100	Speed/Torque Control, Position Control

4.2.12 Reference Pulse Inhibit Function (INHIBIT)

This function inhibits the SERVOPACK from counting input reference pulses during position control.

The servomotor remains locked (clamped) while the function is in use. The /P-CON (/INHIBIT) signal is used to enable or disable the function.



■ Using Reference Pulse Inhibit Function (INHIBIT)

To use the inhibit function, set the parameter as shown below.

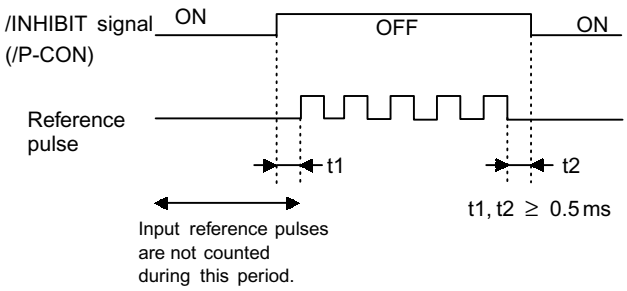
Pn000.1	Control Method Selection	Factory Setting: 0	Position Control

The following settings enable the inhibit function.

Pn000.1 Setting	Description	
1	Disables the inhibit function. Always counts reference pulses.	
B	Enables the inhibit function. The /P-CON (/INHIBIT) signal is used to enable or disable the inhibit function.	
	/P-CON (/INHIBIT)	Description
	OFF	Counts reference pulses.
	ON	Prohibits the SERVOPACK from counting reference pulses. The servomotor remains locked.

Note: Parentheses () around an /INHIBIT signal indicate that a signal has been allocated to the input circuit. See *4.3.3 Input Circuit Signal Allocation*.

■ Relationship between Inhibit Signal and Reference Pulses

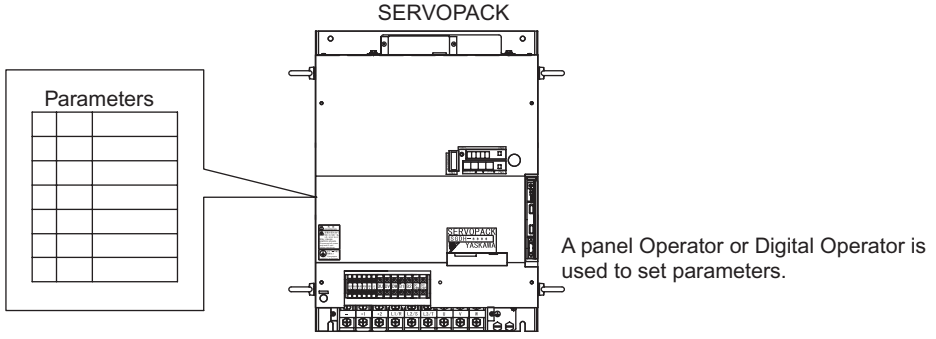


4.3 Setting Up the SERVOPACK

This section describes the procedure for setting parameters to operate the SGDH SERVOPACK.

4.3.1 Parameters

The Σ-II Series SERVOPACK provides many functions and has parameters that allow the user to specify functions and perform fine adjustments.



Parameters are divided into the following three groups.

Parameter	Function
Pn000 to Pn601	Specify SERVOPACK functions, set servo gains, etc.
Fn000 to Fn013	Execute auxiliary functions such as JOG Mode operations and zero point searches.
Un000 to Un00D	Enable monitoring the motor speed and torque reference on the panel display.

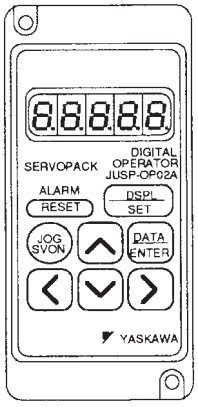
Appendix A List of Parameters shows a list of parameters provided for reference. Connect these signal terminals as required. See *6.1.6 Operation in Parameter Setting Mode* for more details on the procedure for setting parameters.

4.3.2 JOG Speed

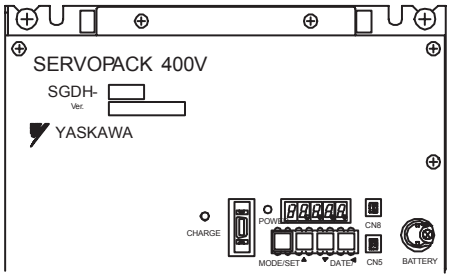
Use the following parameter to set or modify motor speed when operating the servomotor from a Panel or Digital Operator.

Pn304	Jog Speed	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 500	Speed/Torqque Control, Position Control

Use this parameter to set the motor speed when operating the SERVOPACK from a Panel or Digital Operator. If the setting is higher than the maximum motor speed of the servomotor, then the servomotor will rotate at its maximum speed.



Digital Operator



Panel Operator

4.3.3 Input Circuit Signal Allocation

The functions allocated to sequence input signal circuits can be changed. CN1 connector input signals are allocated with the factory settings as shown in the following table.

CN1 Connector Terminal Numbers	Input Terminal Name	Factory Setting	
		Symbol	Name
40	SI0	/S-ON	Servo ON
41	SI1.	/P-CON	(Proportional control reference) *
42	SI2	P-OT	Forward run prohibited
43	SI3	N-OT	Reverse run prohibited
44	SI4	/ALM-RST	Alarm reset
45	SI5	/P-CL	(Forward current limit) *
46	SI6	/N-CL	(Reverse current limit) *

* The functions of these input signals are automatically switched according to the setting at parameter Pn000.1 as long as Pn50A.0 is set to 0.

The following parameter is used to enable input signal allocation.

Pn50A.0	Input Signal Allocation Mode	Factory Setting: 0	Speed/Torque Control, Position Control

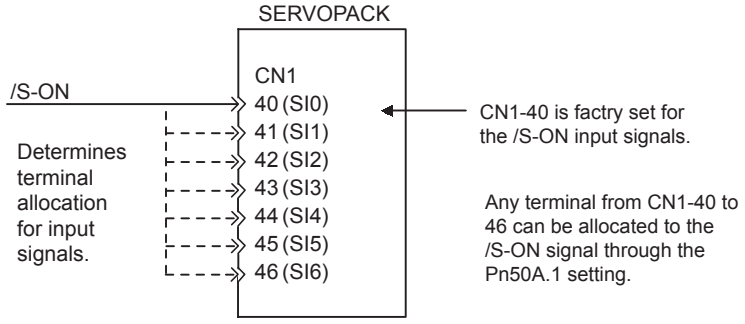
Pn50A.0 Setting	Description
0	Factory setting for sequence input signal allocation. This setting is the same as Yaskawa SGDB-□AD□ SERVOPACKs.
1	Enables any sequence input signal settings.

INFO

In the factory setting, Pn50A.0 is set to 0. Functions in this manual are generally described for the factory settings.

■ Input Signal Allocation

The following signal can be allocated when Pn50A.0 is set to 1.



The following table shows the parameter factory settings for input signal selections 1 to 4.

Pn50A	Input Signal Selections 1	Factory Setting: 2100	Speed/Torque Control, Position Control
Pn50B	Input Signal Selections 2	Factory Setting: 6543	Speed/Torque Control, Position Control
Pn50C	Input Signal Selections 3	Factory Setting: 8888	Speed/Torque Control, Position Control
Pn50D	Input Signal Selections 4	Factory Setting: 8888	Speed/Torque Control, Position Control

Select the input terminal on the CN1 connector that will be used for each input signal.

• Examples of Input Signal Allocation

The procedure used to allocate sequence input signals is described using the /S-ON signal as a typical example.

Pn50A.1 Setting	Description	Remarks
0	Inputs the /S-ON signal from the SI0 (CN1-40) input terminal.	Signal Polarity: Normal Example: Servo-ON signal (/S-ON) is valid when low (ON).
1	Inputs the /S-ON signal from the SI1 (CN1-41) input terminal.	
2	Inputs the /S-ON signal from the SI2 (CN1-42) input terminal.	
3	Inputs the /S-ON signal from the SI3 (CN1-43) input terminal.	
4	Inputs the /S-ON signal from the SI4 (CN1-44) input terminal.	
5	Inputs the /S-ON signal from the SI5 (CN1-45) input terminal.	
6	Inputs the /S-ON signal from the SI6 (CN1-46) input terminal.	
7	Sets /S-ON signal so that it is always valid.	Set the Servo-ON signal (/S-ON) so that it is always valid or always invalid.
8	Sets /S-ON signal so that it is always invalid.	
9	Inputs the S-ON signal from the SI0 (CN1-40) input terminal.	Signal Polarity: Reversed * Example: Servo-ON signal (/S-ON) is valid when high (OFF).
A	Inputs the S-ON signal from the SI1 (CN1-41) input terminal.	
B	Inputs the S-ON signal from the SI2 (CN1-42) input terminal.	
C	Inputs the S-ON signal from the SI3 (CN1-43) input terminal.	
D	Inputs the S-ON signal from the SI4 (CN1-44) input terminal.	
E	Inputs the S-ON signal from the SI5 (CN1-45) input terminal.	
F	Inputs the S-ON signal from the SI6 (CN1-46) input terminal.	

* Settings 9 through F can be used to reverse signal polarity.

IMPORTANT

If reverse polarity is set for the Servo-ON, Forward Run Prohibit, or Reverse Run Prohibit signals, safe operation may not occur when troubles, such as broken signal lines, occur. You must confirm operational safety if setting reverse polarity is necessary for one or more of these signals.

As shown in the table above, the /S-ON signal can be allocated to any input terminal from SI0 to SI6. /S-ON is always input when Pn50A.1 is set to 7, and an external signal line would therefore not be needed.

The /S-ON signal is not used when Pn50A.1 is set to 8. This setting is meaningful only in the following instances.

- When the factory set input signal are to be replaced by another input signal.
- The signal must be left ON (low level) during normal operation to make the signal valid when OFF (high level) when forward run prohibit (P-OT) and reverse run prohibit (N-OT) are input. The input terminal signal line must be left ON even in system configurations that do not require this signal, but unnecessary wiring can be eliminated by setting Pn50A.1 to 8.



Signals are input with OR logic when multiple signals are allocated to the same input circuit.

• Allocating Other Input Signals

Input signal allocation can be changed as shown below.

Table 4.1 Allocation of Other Input Signals

Input Signal		Parameter		Description
Name	Applicable Logic	Number	Setting	
Proportional Control Reference (/P-CON)	ON (low level)	Pn50A.2	0	Inputs the signal on the left from the SI0 (CN1-40).
			1	Inputs the signal on the left from the SI1 (CN1-41).
			2	Inputs the signal on the left from the SI2 (CN1-42).
			3	Inputs the signal on the left from the SI3 (CN1-43).
			4	Inputs the signal on the left from the SI4 (CN1-44).
			5	Inputs the signal on the left from the SI5 (CN1-45).
			6	Inputs the signal on the left from the SI6 (CN1-46).
			7	Sets the signal on the left to always enabled.
			8	Sets the signal on the left to always disabled.
			9	Inputs the reverse of the signal on the left from the SI0 (CN1-40).
			A	Inputs the reverse of the signal on the left from the SI1 (CN1-41).
			B	Inputs the reverse of the signal on the left from the SI2 (CN1-42).
			C	Inputs the reverse of the signal on the left from the SI3 (CN1-43).
			D	Inputs the reverse of the signal on the left from the SI4 (CN1-44).
			E	Inputs the reverse of the signal on the left from the SI5 (CN1-45).
			F	Inputs the reverse of the signal on the left from the SI6 (CN1-46).
Forward Run Prohibit (P-OT)	OFF (high level)	Pn50A.3	0 to F	Same as above. *
Reverse Run Prohibit (N-OT)	OFF (high level)	Pn50B.0	0 to F	Same as above. *
Alarm Reset (/ARM-RST)	ON (low level)	Pn50B.1	0 to F	Same as above. *
Forward Current Limit (/P-CL)	ON (low level)	Pn50B.2	0 to F	Same as above. *
Reverse Current Limit (/N-CL)	ON (low level)	Pn50B.3	0 to F	Same as above. *
Contact Input Speed Control Selection (/SPD-D)	-	Pn50C.0	0 to F	Same as above. *
Contact Input Speed Control Selection (/SPD-A)	-	Pn50C.1	0 to F	Same as above. *
Contact Input Speed Control Selection (/SPD-B)	-	Pn50C.2	0 to F	Same as above. *
Control Mode Selection (/C-SEL)	ON (low level)	Pn50C.3	0 to F	Same as above. *
Zero Clamp (/ZCLAMP)	ON (low level)	Pn50D.0	0 to F	Same as above. *

Table 4.1 Allocation of Other Input Signals (cont'd)

Input Signal		Parameter		Description
Name	Applicable Logic	Number	Setting	
Reference Pulse Inhibit (/INHIBIT)	ON (low level)	Pn50D.1	0 to F	Same as above. *
Gain Switching (/G-SEL)	ON (low level)	Pn50D.2	0 to F	Same as above. *

* Same as above indicates that the parameter can be set to from 0 to F to allocate input signals to the following terminals, as shown in the example for the Proportional Control Reference (/P-CON).
1. Allocation to input terminals SI0 to SI6
2. Setting to always valid or always invalid
3. Allocation to input terminals SI0 to SI6 and receiving the signals at the SERVOPACK with the reverse logic of the input signal

4.3.4 Output Circuit Signal Allocation

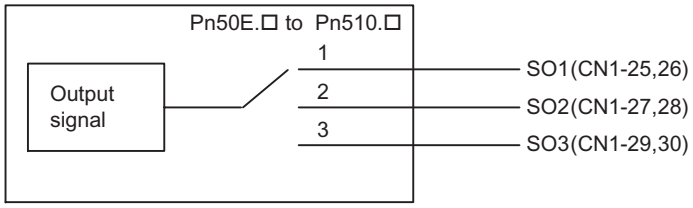
Output signal functions can be allocated to the sequence signal output circuits shown below.

CN1 Connector Terminal Numbers	Output Terminal Name	Factory Setting		Comments
		Symbol	Name	
25	SO1	/V-CMP+ (/COIN+)	Speed coincidence detection (positioning completed)	The signal output will vary depending on the control mode.
26 (SG)		/V-CMP- (/COIN-)		
27	SO2	/TGON+	Rotation detection	
28 (SG)		/TGON-		
29	SO3	/S-RDY+	Servo ready	
30 (SG)		/S-RDY-		

The output signal selection parameters and their factory settings are shown below.

Pn50E	Output Signal Selections 1	Factory Setting: 3211	Speed/Torque Control, Position Control
Pn50F	Output Signal Selections 2	Factory Setting: 0000	Speed/Torque Control, Position Control
Pn510	Output Signal Selections 3	Factory Setting: 0000	Speed/Torque Control, Position Control

Select the CN1 connector terminals that will output the signals.



Output Signal	Parameter		Description
	Number	Setting	
Positioning Completed (/COIN)	Pn50E.0	0	Disabled (Not used for the output signal on the left.)
		1	Outputs the signal on the left from the SO1 (CN1-25 and 26) output terminal.
		2	Outputs the signal on the left from the SO2 (CN1-27 and 28) output terminal.
		3	Outputs the signal on the left from the SO3 (CN1-29 and 30) output terminal.
Speed Coincidence Detection (/V-CMP)	Pn50E.1	0 to 3	Same as above.
Rotation Detection(/TGON)	Pn50E.2	0 to 3	Same as above.
Servo Ready (/S-RDY)	Pn50E.3	0 to 3	Same as above.
Torque Limit Detection (/CLT)	Pn50F.0	0 to 3	Same as above.
Speed Limit Detection (/VLT)	Pn50F.1	0 to 3	Same as above.
Brake Interlock (/BK)	Pn50F.2	0 to 3	Same as above.
Warning (/WARN)	Pn50F.3	0 to 3	Same as above.
Near (/NEAR)	Pn510.0	0 to 3	Same as above.
Not used.	-	-	-

Note: “Same as above” means output signals are disabled or allocated to output terminals SO1 to SO3 through parameter settings 0 to 3.



Multiple signals allocated to the same output circuit are output using OR logic. Signals that are not detected are invalid. For example, the positioning completed signal /COIN is invalid in Speed Control Mode.

The following parameter can be used to reverse the signals output on output terminals SO1 to SO3.

Pn512	Output Signal Reversal Settings	Factory Setting: 0000	Speed/Torque Control, Position Control

The settings specify which of the connector CN1 output signals are to be reversed.

Output Signal	Parameter		Meaning
	Number	Setting	
SO1 (CN1-25, 26)	Pn512.0	0	Output signal not reversed.
		1	Output signal reversed.
SO2 (CN1-27, 28)	Pn512.1	0	Output signal not reversed.
		1	Output signal reversed.
SO3 (CN1-29, 30)	Pn512.2	0	Output signal not reversed.
		1	Output signal reversed.
Not used.	Pn512.3	-	-

4.3.5 Control Mode Selection

The SGDH SERVOPACK offers speed control, position control, torque control, and the other control modes shown in the following table.

The following parameter is used to set the control mode.

Pn000.1	Control Mode Selection	Factory Setting: 0	Speed/Torque Control, Position Control

Pn000.1 Setting	Control Mode
0	Speed Control (Analog Reference)
1	Position Control (Pulse Train Reference)
2	Torque Control (Analog Reference)
3	Contact Input Speed Control Selection (Contact Reference)
4	Contact Input Speed Control Selection (Contact Reference) ↔ Speed Control (Analog Reference)
5	Contact Input Speed Control Selection (Contact Reference) ↔ Position Control (Pulse Train Reference)
6	Contact Input Speed Control Selection (Contact Reference) ↔ Torque Control (Analog Reference)
7	Position Control (Pulse Train Reference) ↔ Speed Control (Analog Reference)
8	Position Control (Pulse Train Reference) ↔Torque Control (Analog Reference)
9	Torque Control (Analog Reference) ↔ Speed Control (Analog Reference)
A	Speed Control (Analog Reference) ↔ Zero Clamp Control
B	Position Control (Pulse Train Reference) ↔ Position Control (Inhibit)

■ Description of Control Modes

The control modes are described below.

Speed Control (Analog Reference)

This mode controls speed using an analog voltage input reference. See *4.2.1 Speed Reference*.

Position Control (Pulse Train Reference)

This mode controls positioning using a pulse train input reference. See *4.2.2 Position Reference*.

Torque Control (Analog Reference)

This mode controls torque using an analog voltage input reference. See *4.2.7 Using Torque Control*.

Contact Input Speed Control Selection (Contact Reference)

This mode uses the /P-CON (/SPD-D), /P-CL (/SPD-A), and /N-CL (/SPD-B) input signals to control speed as it switches among the three preset operating speeds in the SERVOPACK. See *4.2.6 Contact Input Speed Control*.

Contact Input Speed Control Selection (Contact Reference) ↔ Speed Control (Analog Reference)

This mode controls speed by switching between contact reference and analog voltage reference speed control. Analog voltage reference speed control is enabled when both /P-CL (/SPD-A) and /N-CL (/SPD-B) input signals are OFF (high level). See *4.2.6 Contact Input Speed Control*.

Contact Input Speed Control Selection (Contact Reference) ↔ Position Control (Pulse Train Reference)

This mode switches between contact reference speed control and pulse train reference position control. Pulse train reference position control is enabled when both /P-CL (/SPD-A) and /N-CL (/SPD-B) input signals are OFF (high level). See *4.2.6 Contact Input Speed Control*.

Contact Input Speed Control Selection (Contact Reference) ↔ Torque Control (Analog Reference)

This mode switches between contact reference speed control and analog voltage reference torque control. Torque control using an analog voltage reference is enabled when both /P-CL (/SPD-A) and /N-CL (/SPD-B) input signals are OFF (high level). See *4.2.6 Contact Input Speed Control*.

Position Control (Pulse Train Reference) ↔ Speed Control (Analog Reference)

This mode switches between position and speed control through the /P-CON (/C-SEL) signal.

Position Control (Pulse Train Reference) ↔ Torque Control (Analog Reference)

This mode switches between position and torque control through the /P-CON (/C-SEL) signal.

Torque Control (Analog Reference) ↔ Speed Control (Analog Reference)

This mode switches between torque and speed control through the /P-CON (/C-SEL) signal. See *4.2.7 Using Torque Control*.

Speed Control (Analog Reference) ↔ Zero Clamp

This speed control mode is used to set the zero clamp function when the SERVOPACK is stopped. Zero clamp operates when the /P-CON (/ZCLAMP) signal is ON (low level). See *4.4.3 Using the Zero Clamp Function*.

Position Control (Pulse Train Reference) ↔ Position Control (Inhibit)

This mode controls positioning by inhibiting reference pulse input through the /P-CON (/INHIBIT) signal. See *4.2.12 Reference Pulse Inhibit Function (INHIBIT)*.

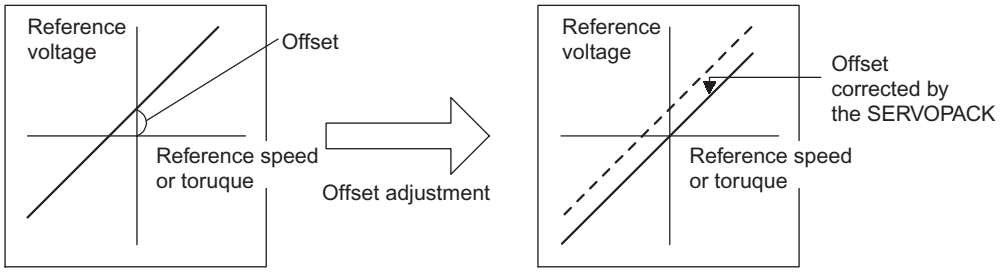
4.4 Setting Stop Functions

This section describes the procedure used to stop the SERVOPACK stably.

4.4.1 Adjusting Offset

■ When the Servomotor Will Not Stop

The servomotor may rotate at very low speed and not stop even when 0 V is specified as the reference voltage for SERVOPACK speed and torque control (analog reference). This happens when the reference voltage from the host controller or external circuit is slightly offset (in mV units). The servomotor will stop if this offset is properly adjusted to 0 V.



■ Reference Offset Adjustment

The following methods can be used to adjust the reference offset to 0 V.

Automatic Adjustment of Reference Offset	The reference offset value is automatically set to 0 V.
Manual Adjustment of Reference Offset	The reference offset value can be adjusted manually.

IMPORTANT

If a position loop is formed in the host controller, be sure to make manual offset adjustment and do not make automatic reference offset adjustment.

See the following sections in *Chapter 6 Using the Digital Operator* for more details on adjustment procedures.

Automatic Adjustment of Reference Offset	*6.2.3 Automatic Adjustment of the Speed and Torque Reference Offset*
Manual Adjustment of Reference Offset	*6.2.4 Manual Adjustment of the Speed and Torque Reference Offset*

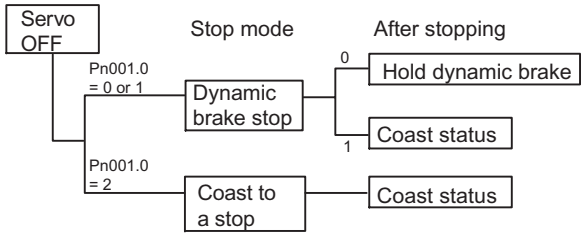
4.4.2 Using the Dynamic Brake

To stop the servomotor by applying the dynamic brake (DB)[1], set the desired mode in the following parameter. The servomotor will stop due to equipment friction if the dynamic brake is not applied.

Pn001.0	Servo OFF or Alarm Stop Mode	Factory Setting: 0	Speed/Torque Control, Position Control

The SGDH SERVOPACK turns OFF under the following conditions:

- The Servo ON input signal (/S-ON, CN1-40) is turned OFF.
- A Servo alarm occurs.
- Main power is turned OFF.



Specify the Stop Mode if any of these occurs during operation.

Pn001.0 Setting	Description
0	Uses the dynamic brake to stop the servomotor. Maintains dynamic brake after the servomotor stops. *
1	Uses the dynamic brake to stop the servomotor. Releases dynamic brake after the servomotor stops, and the servomotor coasts to a stop.
2	Coasts the servomotor to a stop. The servomotor is turned OFF and motion stops due to equipment friction.

* If the servomotor is stopped or moving at extremely low speed, it will coast to a stop.

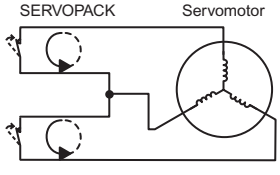
IMPORTANT

The dynamic brake is an emergency stop function. Do not repeatedly start and stop the servomotor using the servo ON signal (/S-ON) or by repeatedly turning power ON and OFF. Frequently turning power ON and OFF causes internal elements of the SERVOPACK to deteriorate, resulting in unexpected problems.

TERMS

[1] Dynamic brake (DB)

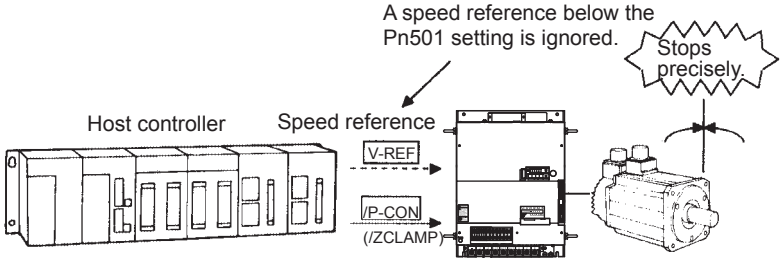
The dynamic brake is a common way of suddenly stopping a servomotor. Built into the SERVOPACK, the dynamic brake suddenly stops a servomotor by electrically shorting its electrical circuit.



4.4.3 Using the Zero Clamp Function

The zero clamp function is used for systems where the host controller does not form a position loop for the speed reference input.

In other words, this function is used to stop and lock the servomotor even when the input voltage of speed reference V-REF is not 0 V. An internal position loop is temporarily formed to clamp the servomotor within one pulse when the zero clamp function is turned ON. Even if the servomotor is forcibly rotated by external force, it will still return to the zero clamp position.



■ Parameter Setting

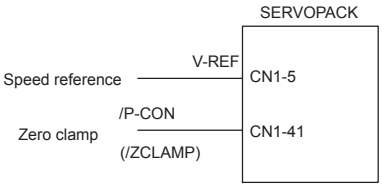
Set the following parameter so that the input signal /P-CON (/ZCLAMP) can be used to enable or disable the zero clamp function.

Pn000.1	Control Method Selection	Factory Setting: 0	Speed Control

→ Input /P-CON CN1-41	Proportional Control, etc.	Speed/Torque Control, Position Control

INFO

The /ZCLAMP signal can be used when an input circuit signal is allocated. See *4.3.3 Input Circuit Signal Allocation*.

Pn000.1 Setting	Control Mode	
A	Zero Clamp Control Mode This mode allows the zero clamp function to be set when the servomotor stops. • The speed reference is input from V-REF (CN1-5). • /P-CON (/ZCLAMP)(CN1-41) is used to turn the zero clamp function ON and OFF. CN1-41 is open (OFF). — Turns the zero clamp function OFF. CN1-41 is 0 V (ON). — Turns the zero clamp function ON.	 Zero clamp is performed when the following two conditions are satisfied: Condition 1: /P-CON (/ZCLAMP) is ON. Condition 2: Speed reference is below the setting at Pn501.

■ Setting

Use the following parameter to set the motor speed level at which zero clamp is performed.

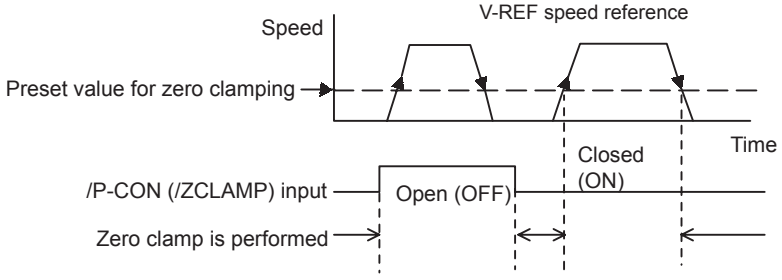
Pn501	Zero Clamp Level	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 10	Speed Control

Set the motor speed at which zero clamp is performed if zero clamp speed control is selected. Even if this value is set higher than the maximum speed of the servomotor, the maximum speed will be used.

Zero Clamp Conditions

Zero clamp is performed when all the following conditions are satisfied:

- Zero clamp speed control is selected (parameter Pn000.1 is set to A).
- /P-CON (/ZCLAMP)(CN1-41) is ON (0V).
- Speed reference drops below the setting of Pn501.

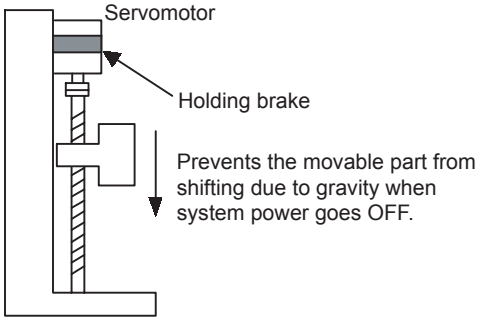


INFO

When the /ZCLAMP signal is allocated, the zero clamp operation will be used even for speed control (Pn000.1 = 0).

4.4.4 Using the Holding Brake

The holding brake is used when a servodrive controls a vertical axis. In other words, a servomotor with brake prevents the movable part from shifting due to gravity when system power goes OFF.

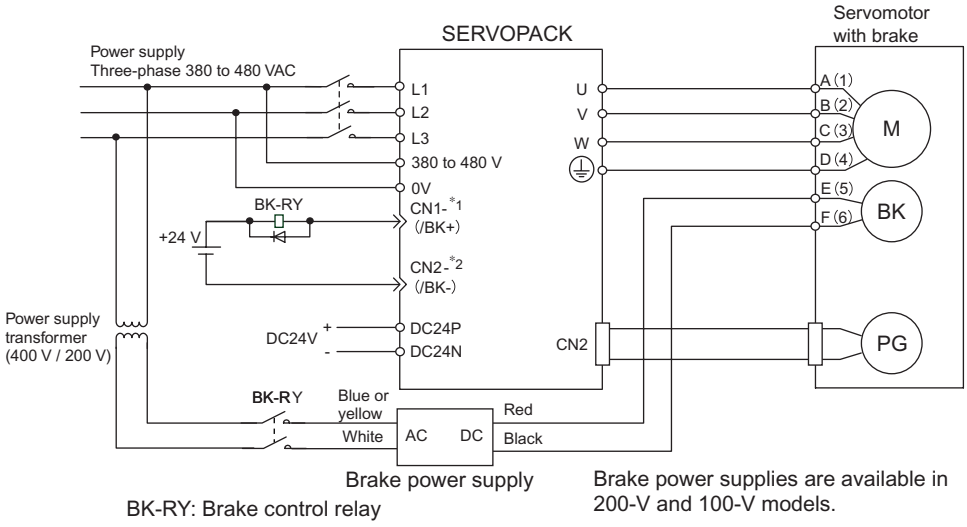


IMPORTANT

The brake built into the SGMBH servomotor with brakes is a de-energization brake, which is used only to hold and cannot be used for braking. Use the holding brake only to hold a stopped motor. Brake torque is at least 120% of the rated motor torque.

■ Wiring Example

Use the SERVOPACK contact output signal /BK and the brake power supply to form a brake ON/OFF circuit. The following diagram shows a standard wiring example.



*1 and *2 are the output terminals allocated with Pn50F.2.

Output → /BK	Brake Interlock Output	Speed/Torque Control, Position Control

This output signal controls the brake when using a servomotor with a brake and does not have to be connected when using a servomotor without a brake.

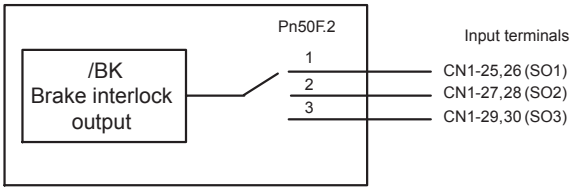
ON:	Closed or low level	Releases the brake.
OFF:	Open or high level	Applies the brake.

Related Parameters

Pn506	Time Delay from Brake Reference until Servo OFF
Pn507	Speed Level for Brake Reference Output during Motor Operation
Pn508	Timing for Brake Reference Output during Motor Operation

The output signal in the following parameter must be selected when the /BK signal is used.

Pn50F	Output Signal Selections 2	Factory Setting: 0000	Speed/Torque Control, Position Control



Select the /BK output terminal.

Parameter	Setting	Output Terminal (CN1-)	
		*1	*2
Pn50F.2	0	-	-
	1	25	26
	2	27	28
	3	29	30

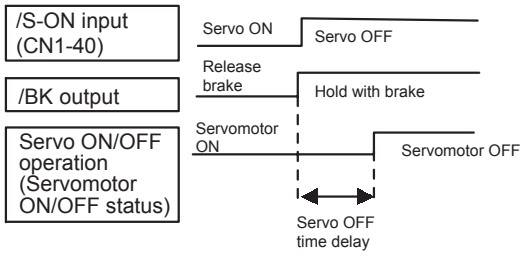
Note: Signals are output with OR logic when multiple signals are allocated to the same output circuit. Set other output signals to a value other than that allocated to the /BK signal in order to output the /BK signal alone. See *4.3.4 Output Circuit Signal Allocation*.

■ Brake ON Timing

If the equipment moves slightly due to gravity when the brake is applied, set the following parameter to adjust brake ON timing.

Pn506	Brake Reference Servo OFF Delay Time	Unit: 10ms	Setting Range: 0 to 50	Factory Setting: 0	Speed/Torque Control, Position Control

This parameter is used to set the output time from the brake control signal /BK until the servo OFF operation (servomotor output stop) when a servomotor with a brake is used.



With the standard setting, the servo is turned OFF when the /BK signal (brake operation) is output. The equipment may move slightly due to gravity depending on equipment configuration and brake characteristics. If this happens, use this parameter to delay servo OFF timing.

This setting sets the brake ON timing when the servomotor is stopped.

Use Pn507 and 508 for brake ON timing during operation.

IMPORTANT

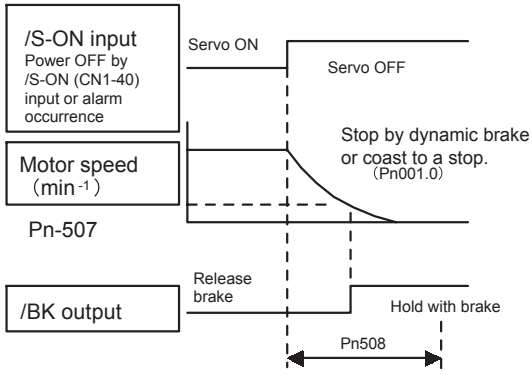
The servomotor will turn OFF immediately if an alarm occurs. The equipment may move due to gravity in the time it takes for the brake to operate.

■ Holding Brake Setting

Set the following parameters to adjust brake ON timing so the holding brake is applied when the servomotor stops.

Pn507	Brake Reference Output Speed Level	Unit: min^{-1}	Setting Range: 0 to 10000	Factory Setting: 100	Speed/Torque Control, Position Control
Pn508	Timing for Brake Reference Output during Motor Operation	Unit: 10ms	Setting Range: 10 to 100	Factory Setting: 50	Speed/Torque Control, Position Control

Set the brake timing used when the servo is turned OFF by input signal /S-ON (CN1-40) or when an alarm occurs during servomotor with brake operation.



Brake ON timing when the servomotor stops must be adjusted properly because servomotor brakes are designed as holding brakes. Adjust the parameter settings while observing equipment operation.

/BK Signal Output Conditions During Servomotor Operation

The circuit is open under either of the following conditions:

1	Motor speed drops below the setting at Pn507 after servo OFF.
2	The time set at Pn508 has elapsed since servo OFF.

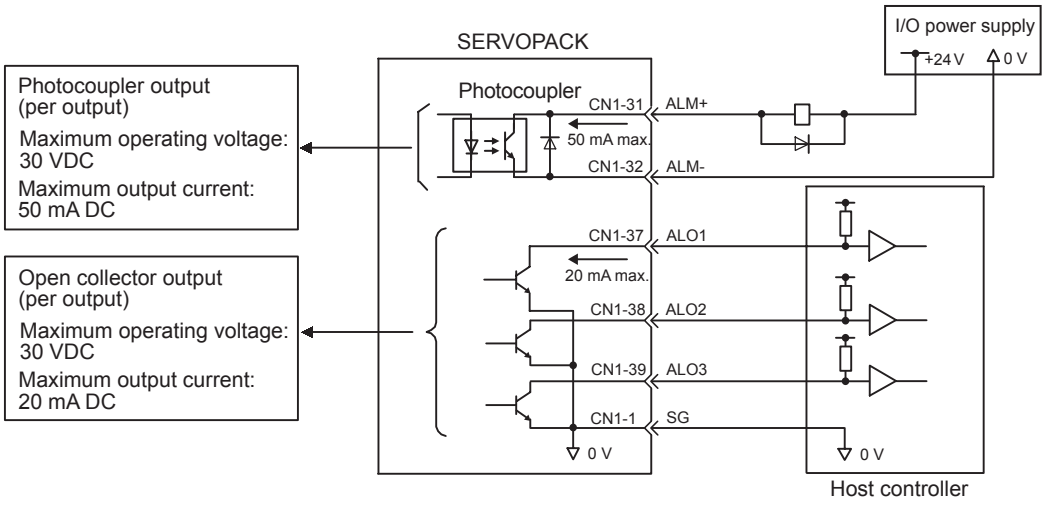
The actual setting will be the maximum speed even if Pn507 is set higher than the maximum speed.

4.5 Forming a Protective Sequence

This section describes the procedure for using I/O signals from the SERVOPACK to form a protective safety sequence.

4.5.1 Using Servo Alarm and Alarm Code Outputs

The basic procedure for connecting alarm output signals is described below.

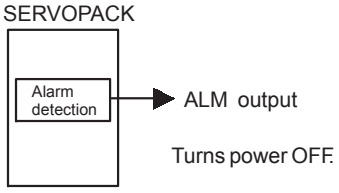


Provide an external input power supply; the SERVOPACK does not have an internal 24-V power supply.

The use of the photocoupler output signals is described below.

Output → ALM+ CN1-31	Servo Alarm Output	Speed/Torque Control, Position Control
Output → ALM- CN1-32	Signal Ground for Servo Alarm Output	Speed/Torque Control, Position Control

These alarms are output when a SERVOPACK alarm is detected.



Form an external circuit so this alarm output (ALM) turns the SERVOPACK OFF.

ON:	Circuit between CN1-31 and 32 is closed, and CN1-31 is at low level.	Normal state
OFF:	Circuit between CN1-31 and 32 is open, and CN1-31 is at high level.	Alarm status

Alarm codes ALO1, ALO2 and ALO3 are output to indicate each alarm type. The uses of open-collector output signals ALO1, ALO2 and ALO3 is described below.

Output → ALO1 CN1-37	Alarm Code Outputs	Speed/Torque Control, Position Control
Output → ALO2 CN1-38	Alarm Code Output	Speed/Torque Control, Position Control
Output → ALO3 CN1-39	Alarm Code Output	Speed/Torque Control, Position Control
Output → SG CN1-1	Signal Ground for Alarm Code Output	Speed/Torque Control, Position Control

These signals output alarm codes to indicate the type of alarm detected by the SERVOPACK.

Use these signals to display alarm codes at the host controller.

See *8.2.3 Alarm Display Table* for more details on the relationship between alarm display and alarm code output.

When a Servo alarm (ALM) occurs, eliminate the cause of the alarm and set the following /ALM-RST input signal to high level (ON) to reset the alarm.

→ Input /ALM-RST CN1-44	Alarm Reset	Speed/Torque Control, Position Control

The alarm reset signal is used to reset a Servo alarm.

Form an external circuit so the SERVOPACK turns OFF when an alarm occurs. Alarms are reset automatically when the control power supply is turned OFF.

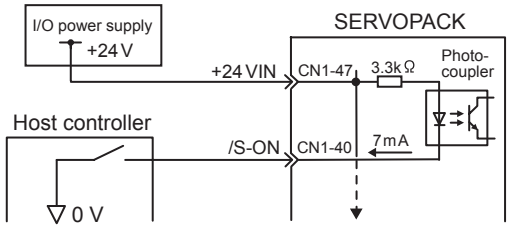
Alarms can also be reset using a Panel or Digital Operator.

IMPORTANT

1. Encoder alarms cannot always be reset by inputting the /ALM-RST signal. In that case, turn the control power supply OFF to reset the alarm.
2. When an alarm occurs, always eliminate the cause before resetting the alarm. See *8.2.1 Troubleshooting Problems with Alarm Displays* for more details on troubleshooting the system when an alarm occurs.

4.5.2 Using the Servo ON Input Signal

The basic use and wiring procedure for the Servo ON (/S-ON) input signal (sequence input signal) is described below. Use this signal to forcibly turn OFF the servomotor from the host controller.



→ Input /S-ON CN1-40	Servo ON	Speed/Torque Control, Position Control

This signal is used to turn the servomotor ON and OFF.

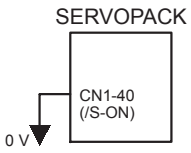
CN1-40 is ON (Low Level)	Turns the servomotor ON. This is the normal state (called the Servo ON state).	Servo ON	Servomotor is ON. The servomotor operates according to signal input.
CN1-40 is OFF (High Level)	Turns the servomotor OFF. The servomotor is OFF and cannot operate (called the Servo OFF state). Do not turn the servomotor OFF while it is operating except in an emergency.	Servo OFF	Servomotor is OFF. Servomotor cannot operate.

IMPORTANT

Do not use the Servo ON (/S-ON) signal but rather always use an input reference signal to start or stop the servomotor.

Set the following parameter to 7 if the /S-ON signal will not be used.

Pn50A.1	/S-ON Signal Mapping	Factory Setting: 0	Speed/Torque Control, Position Control



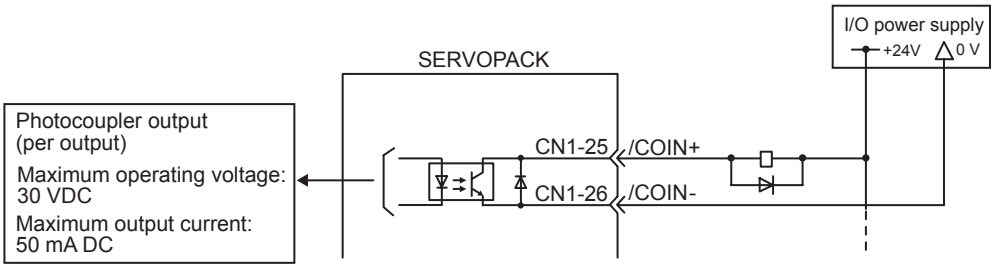
The external short-circuit wiring shown in the figure can be omitted if the Servo ON (/S-ON) input signal is not used.

Pn50A.1 Setting	Description
0	Enables the Servo ON (/S-ON) input signal. (The Servo is OFF when CN1-40 is open, and is ON when CN1-40 is at 0 V.)
7	Disables the Servo ON (/S-ON) input signal. (The Servo is always ON, and has the same effect as shorting CN1-40 to 0 V.)

Note: See *4.3.3 Input Circuit Signal Allocation* for other Pn50A.1 settings.

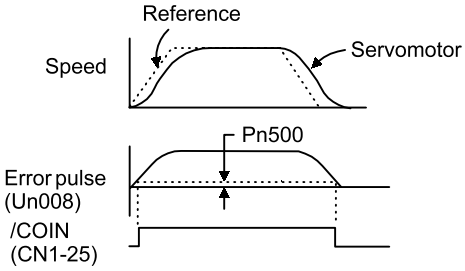
4.5.3 Using the Positioning Completed Output Signal

The basic use and wiring procedure for the positioning completed (/COIN) output signal (photocoupler output signal) is described below. The signal is output to indicate that servomotor operation is completed.



Output → /COIN CN1-25	Positioning Completed Output Signal	Position Control

This signal indicates that servomotor movement has been completed during position control. The host controller uses the signal as an interlock to confirm on the host controller that positioning is completed.



ON:	Circuit between CN1-25 and 26 is closed, and CN1-25 is at low level.	Positioning is completed. (Position error is below the setting.)
OFF:	Circuit between CN1-25 and 26 is open, and CN1-25 is at high level.	Positioning is not completed. (Position error is above the setting.)

Setting: Pn500 (positioning completed width)

The following parameter setting is used to change the CN1 connector terminal that outputs the /COIN signal.

Pn50E	Output Signal Selections 1	Factory Setting: 3211	Position Control

The parameter is factory set so the /COIN signal is output between CN1-25 and 26. See *4.3.4 Output Circuit Signal Allocation* for more details on parameter Pn50E.

The following parameter is used to set the number of error pulses and to adjust the output timing of the positioning completed signal.

Pn500	Positioning Completed Width	Unit: reference units	Setting Range: 0 to 250	Factory Setting: 7	Position Control

This parameter is used to set output timing for the positioning completed signal (/COIN) when the position reference pulse is input and servomotor operation is completed.

Set the number of error pulses in reference units (the number of input pulses defined using the electronic gear function).

Too large a value set at this parameter may output only a small error during low-speed operation that will cause the /COIN signal to be output continuously.

The positioning completed width setting has no effect on final positioning accuracy.

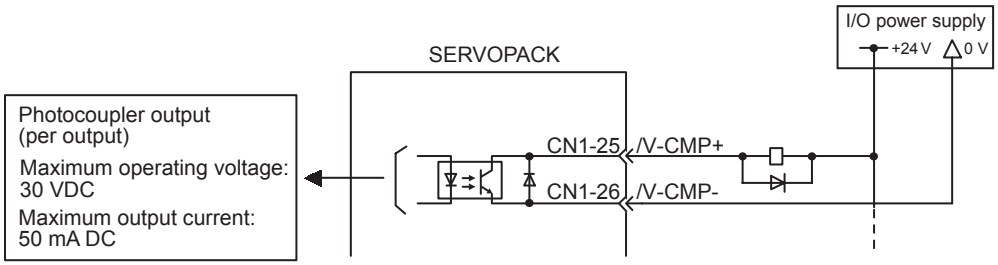


/COIN is a position control signal.

With the factory setting, this signal is used for the speed coincidence output /V-CMP for speed control, and it is always ON for torque control.

4.5.4 Speed Coincidence Output

The basic use and wiring procedures for the speed coincidence (/V-CMP) output signal used to indicate a match with the speed reference (photocoupler output signal) are described below. The host controller uses the signal as an interlock.

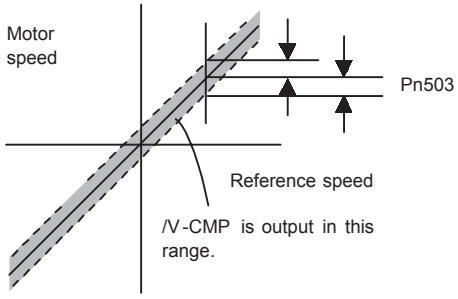


Output → /V-CMP CN1-25	Speed Coincidence Output	Speed Control

This signal is output when the actual motor speed during speed control is the same as the speed reference input.

ON:	Circuit between CN1-25 and 26 is closed, and CN1-25 is at low level.	Speed coincides. (Speed error is below the setting.)
OFF:	Circuit between CN1-25 and 26 is open, and CN1-25 is at high level.	Speed does not coincide. (Speed error is above the setting.)

Preset value: Pn503 (Speed Coincidence Signal Output Width)



The following parameter setting is used to change the CN1 connector terminal that outputs the /V-CMP signal.

Pn50E	Output Signal Selections 1	Factory Setting: 3211	Speed Control

The parameter is factory set so the /V-CMP signal is output between CN1-25 and 26. See *4.3.4 Output Circuit Signal Allocation* for more details on parameter Pn50E.

The following parameter is used to set conditions for speed coincidence output.

Pn503	Speed Coincidence Signal Output Width	Unit: min^{-1}	Setting Range: 0 to 100	Factory Setting: 10	Speed Control

This parameter is used to set conditions for speed coincidence signal /V-CMP output.

The /V-CMP signal is output when the difference between the speed reference and actual motor speed is below this setting.

◀ EXAMPLE ▶

The /V-CMP signal turns ON at 1900 to 2100 min^{-1} if the parameter is set to 100 and the reference speed is 2000 min^{-1}.

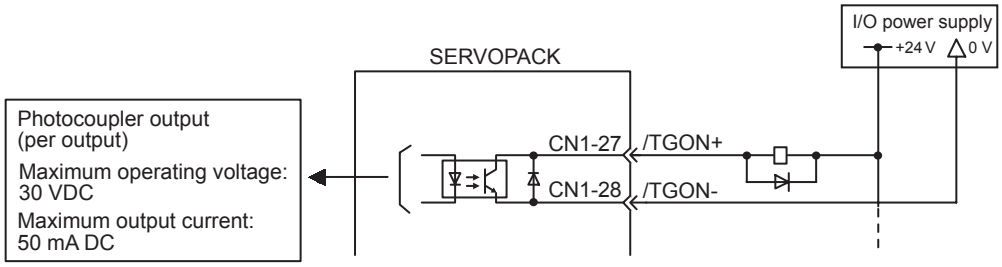
INFO

/V-CMP is a speed control signal.

With the factory setting, this signal is used as the positioning completed signal /COIN for position control, and it is always ON for torque control.

4.5.5 Using the Running Output Signal

The basic use and wiring procedures for the running (/TGON) output signal (photocoupler output signal) are described below. The signal is output to indicate that the servomotor is currently operating.



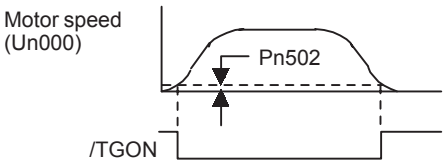
Output → /TGON CN1-27	Running Output Signal	Speed/Torque Control, Position Control

This signal is output to indicate that the servomotor is currently operating.

It is used as an external interlock.

ON:	Closed or low level	Servomotor is operating (Motor speed is above the setting.)
OFF:	Open or high level	Servomotor is not operating. (Motor speed is below the setting.)

Preset value: Pn502 (Running Output Level)



The following parameter setting is used to change the CN1 connector terminal that outputs the /TGON signal.

Pn50E	Output Signal Selections 1	Factory Setting: 3211	Speed/Torque Control, Position Control

The parameter is factory set so the /V-CMP signal is output between CN1-27 and -28. See *4.3.4 Output Circuit Signal Allocation* for more details on parameter Pn50E.

This parameter is used to set output conditions for the operation detection output signal /TGON.

Pn502	Rotation Detection Level	Unit: min^{-1}	Setting Range: 1 to 10000	Factory Setting: 20	Speed/Torque Control, Position Control

This parameter is used to set the speed at which the SERVOPACK determines servomotor operation and outputs a signal. The following signals are output when motor speed exceeds the preset level.

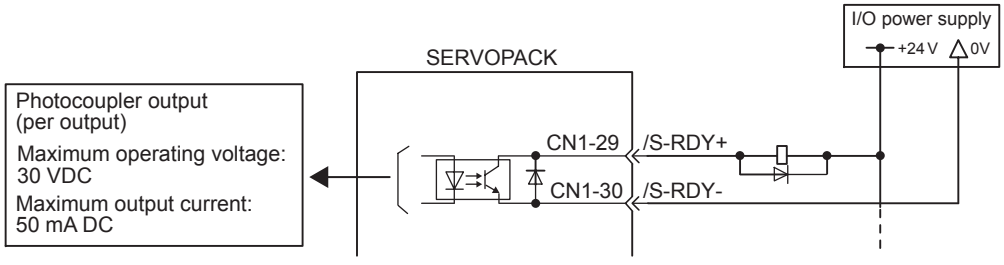
Signals output when servomotor operation is detected:

- /TGON
- Status Indication Mode
- Monitor Mode Un006

4.5.6 Using the Servo Ready Output Signal

The basic use and wiring procedures for the Servo Ready (/S-RDY) output signal (photocoupler output signal) are described below.

Servo Ready means there are no Servo alarms and the main circuit power supply is turned ON. An added condition with absolute encoder specifications is that the SEN signal is at high level and absolute data was output to the host controller.



Output → /S-RDY CN1-29	Servo Ready Output Signal	Speed/Torque Control, Position Control

This signal indicates the SERVOPACK received the Servo ON signal and completed all preparations.

ON:	Closed or low level	Servo is ready.
OFF:	Open or high level	Servo is not ready.

The following parameter setting is used to change the CN1 connector terminal that outputs the /S-RDY signal.

Pn50E	Output Signal Selections 1	Factory Setting: 3211	Speed/Torque Control, Position Control

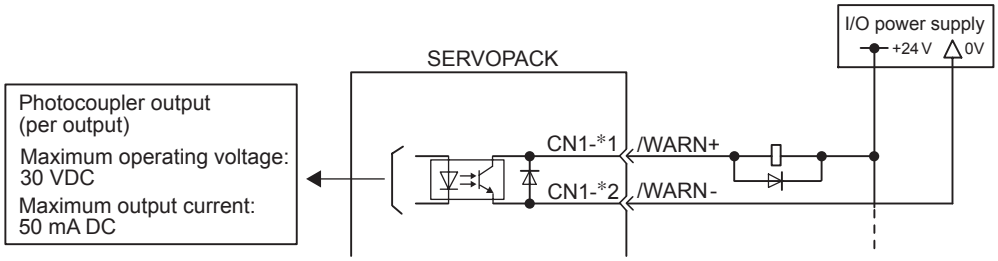
The parameter is factory set so the /V-CMP signal is output between CN1-29 and -30. See *4.3.4 Output Circuit Signal Allocation* for more details on parameter Pn50E.

4.5.7 Using the Warning Output Signal

The basic use and wiring procedure for the warning (/WARN) output signal (photocoupler output signal) are given below.

The signal consists of the following two output signals.

/WARN signals: Overload and regenerative overload



Note: Parameter Pn50F.3 is used to allocate output terminals for *1 and *2.

Output → /WARN	Warning Output Signal	Speed/Torque Control, Position Control

This output signal indicates an overload or regenerative overload warning.

OFF:	Open or high level	Normal operation.
ON:	Closed or low level	Error warning status

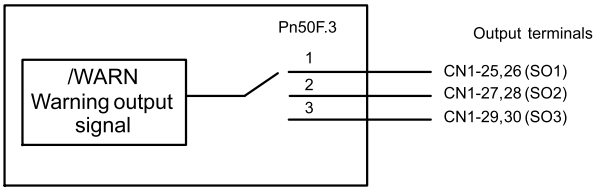
The following parameter setting is used to change the CN1 connector terminal that outputs the /WARN signal.

Pn50F	Output Signal Selections 2	Factory Setting: 0000	Speed/Torque Control, Position Control

Pn50F.3 is used to allocate the /WARN output signals above.

Parameter	Setting	Output Terminal (CN1-)	
		*1	*2
Pn50F.3	0	-	-
	1	25	26
	2	27	28
	3	29	30

Note: Multiple signals allocated to the same output circuit are output using OR logic. Set other output signals to a value other than that allocated to the /WARN signal in order to use the /WARN output signal alone. See *4.3.4 Output Circuit Signal Allocation*.



The following parameter is used to output warning details with an alarm code.

Pn001.3	Warning Code Output Selection	Factory Setting: 0	Speed/Torque Control, Position Control

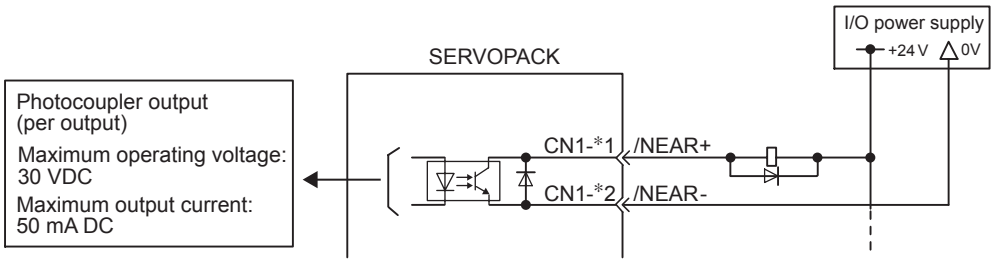
Pn001.3 Setting	Description
0	Outputs alarm codes alone for alarm codes ALO1, ALO2 and ALO3.
1	Outputs both alarm and warning codes for alarm codes ALO1, ALO2 and ALO3. Outputs an alarm code when an alarm occurs.

The following warning codes are output in 3 bits.

Warning Indication	Warning Code Output			Warning Description
	ALO1	ALO2	ALO3	
A.91	ON signal (low level)	OFF signal (high level)	OFF signal (high level)	Overload
A.92	OFF signal (high level)	ON signal (low level)	OFF signal (high level)	Regenerative overload

4.5.8 Using the Near Output Signal

The basic use and wiring procedures for the near (/NEAR) output signal (photocoupler output signal) are described below. The signal is a sequence signal that is generally output together with the positioning completed signal (/COIN), and it is used to indicate the servomotor is close to completing operation.



Note: *1 and *2 are the output terminals allocated with Pn510.0.

Output → /NEAR	Near Output Signal	Position Control

The SERVOPACK receives the near signal before the host controller checks the positioning completed signal and prepares the following sequence signal in order to reduce the number of operations required to complete servomotor operation during position control.

ON:	Closed or low level	The servomotor is close to completing operation. (Position error is below the near signal setting range.)
OFF:	Open or high level	The servomotor is not close to completing operation. (Position error is above the near signal setting range.)

Setting: Pn504 (near signal width)

To use the /NEAR signal, an output terminal must be allocated using the parameter below.

Pn510	Output Signal Selections 3	Factory Setting: 0000	Position Control

Pn510.0 is used to allocate the /NEAR output signals above.

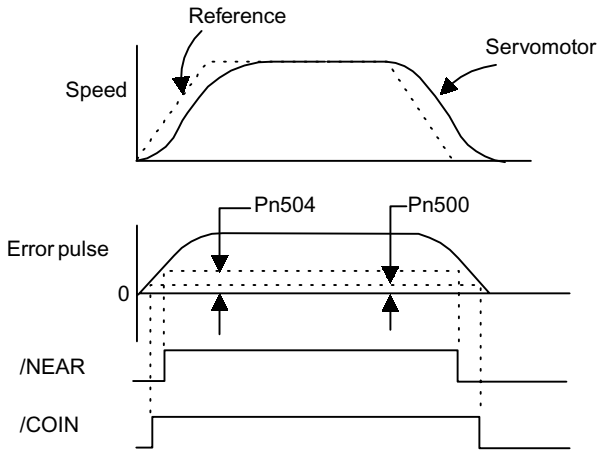
Parameter	Setting	Output Terminal (CN1-)	
		*1	*2
Pn510.0	0	-	-
	1	25	26
	2	27	28
	3	29	30

Note: Multiple signals allocated to the same output circuit are output using OR logic. Set other output signals to a value other than that allocated to the /NEAR signal in order to use the /NEAR output signal alone. See *4.3.4 Output Circuit Signal Allocation*.

The following parameter is used to set the timing for /NEAR signal output.

Pn504	NEAR Signal Width	Unit: reference units	Setting Range: 1 to 250	Factory Setting: 7	Position Control

Generally set the near signal width higher than the positioning completed width. Also see *4.5.3 Using the Positioning Completed Output Signal*.



4.5.9 Handling Power Loss

The following parameter is used to specify whether the servomotor holds or continues when a power loss occurs.

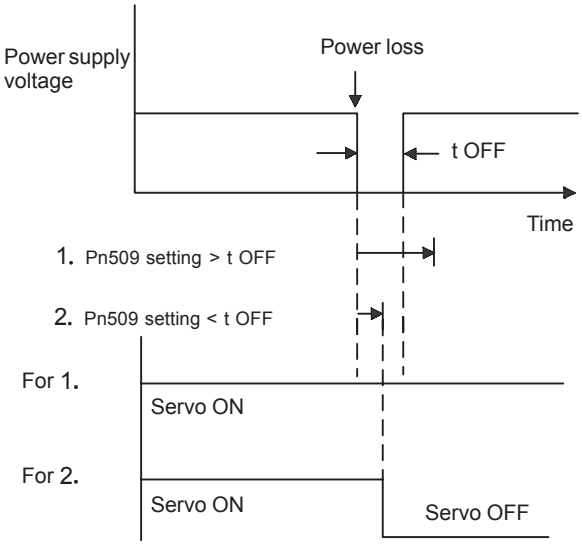
Pn509	Momentary Hold Time	Unit: ms	Setting Range: 20 to 1000	Factory Setting: 20	Speed/Torque Control, Position Control

The SERVOPACK turns the servomotor OFF if it detects an instantaneous voltage drop in the power supply. This factory setting of 20 ms means that servomotor operation will continue if power is lost for less than 20 ms.

In the following instances, however, a Servo alarm is generated or control is lost (equivalent to normal power OFF operation) regardless of the parameter setting.

- When an insufficient voltage alarm (A.41) occurs during power loss with a large servomotor load.
- When control is lost (equivalent to normal power OFF operation) with loss of the control power supply.

In power loss detection, the status of the main circuit power supply is detected and OFF status is ignored so servomotor operation will continue if the servomotor turns back ON within the time set at parameter Pn509.


Power supply voltage
Power loss
t OFF
Time
1. Pn509 setting > t OFF
2. Pn509 setting < t OFF
For 1.
Servo ON
For 2.
Servo ON
Servo OFF

4.6 External Regenerative Resistors

When installing an external regenerative resistor, set the regenerative resistor's capacity (W) at the following parameter.

Pn600	Regenerative Resistor Capacity	Unit: 10 W	Setting Range: 0 to SERVOPACK capacity	Factory Setting: 0	Speed/Torque Control, Position Control

The factory setting of "0" in the above table is the set value used when the SERVOPACK's built-in resistor is used or when a SERVOPACK without a built-in resistor is used.

When installing an external regenerative resistor, set the regenerative resistor's capacity (W).

◀ EXAMPLE ▶ When the external regenerative resistor's actual consumable capacity is 100 W, set the parameter to "10."

IMPORTANT

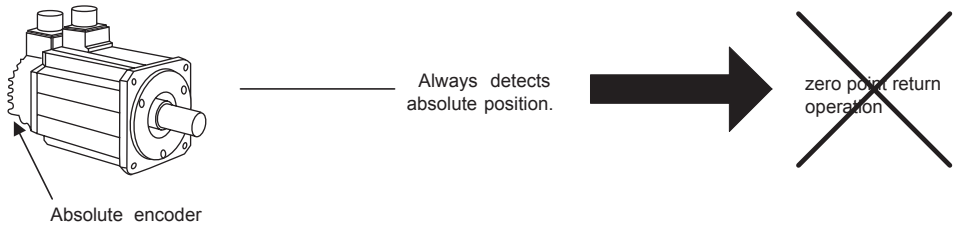
1. In general, when resistors for power are used at the rated load ratio, the resistor temperature increases to between 200°C and 300°C. The resistors must be used at or below the rated values. Check with the manufacturer for the resistor's load characteristics. Use resistors at no more than 20% of the rated load ratio with natural convection cooling, and no more than 50% of the rated load ratio with forced air cooling.
2. For safety's sake, it is recommended that resistors with thermoswitches be used.

4.7 Absolute Encoders

If a motor with an absolute encoder is used, a system to detect the absolute position can be made in the host controller. Consequently, operation can be performed without zero point return operation immediately after the power is turned ON.

Motor SGMBH-□□□2□···With 17-bit absolute encoder

SGMBH-□□□3□···With 20-bit absolute encoder (option)



⚠ WARNING

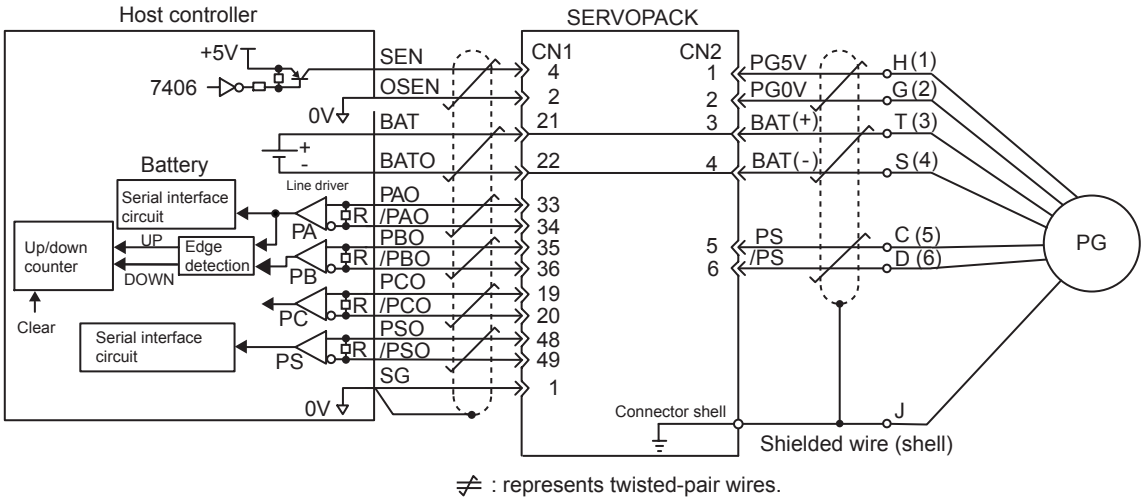
- The output range of multiturn data for Σ-II Series absolute detection system differs from that for conventional systems (15-bit encoder and 12-bit encoder). Specially when "Infinite length positioning system" of conventional type is to be configured with Σ-II Series, be sure to make the following system modification.

Absolute Encoder Type	Output Range of Multiturn Data	Motion When Exceeds the Limit
Conventional Types (12-bit and 15-bit)	-99999 to + 99999	• When exceeds the upper limit (+99999) in the positive direction, the multiturn data is 0. • When exceeds the lower limit (-99999) in the negative direction, the multiturn data is 0.
Σ-II Series (16-bit, 17-bit, and 20-bit)	-32768 to + 32767	• When exceeds the upper limit (+32767) in the positive direction, the multiturn data is -32768. • When exceeds the lower limit (-32768) in the negative direction, the multiturn data is +32767.*

* When the multiturn limit setting (Pn205) is changed, the motion differs.
Refer to *4.7.6 Multiturn Limit Setting*.

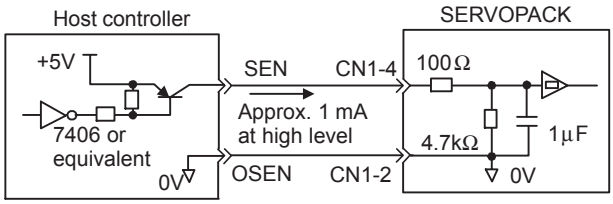
4.7.1 Interface Circuit

The following diagram shows the standard connections for an absolute encoder mounted to a servomotor.



Applicable line drivers: SN75175 or KM3486 by T/I.
Terminating resistance R: 220 to 470 Ω

■ SEN Signals

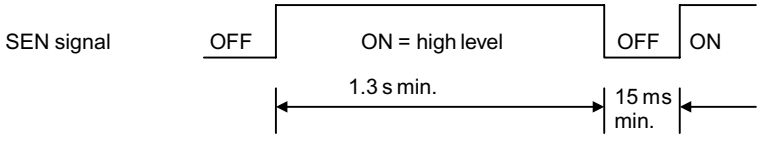


PNP is recommended for transistors.
Signal Levels
High level: 4.0 V min.; Low level: 0.8 V max.

- Let at least three seconds elapse after turning ON the power before raising the SEN signal to high level.
- When the SEN signal is changed from low level to high level, the multiturn data and initial incremental pulses are output.
- Until these operations are completed, the motor cannot be operated regardless of the status of the servo ON signal (/S-ON).

IMPORTANT

If for some reason it is necessary to turn OFF a SEN signal that is already ON, and then to turn it back ON again, maintain the high level for at least 1.3 seconds before turning it ON and OFF.



4.7.2 Selecting an Absolute Encoder

Select the absolute encoder usage with the following parameter.

Pn002.2	Absolute Encoder Usage	Factory Setting: 0	Speed/Torque Control, Position Control

"0" in the following table must be set to enable the absolute encoder.

Pn002.2 Setting	Contents
0	Use the absolute encoder as an absolute encoder.
1	Use the absolute encoder as an incremental encoder.

Note: This user definition goes into effect when the power is turned OFF after the change has been made.

4.7.3 Handling Batteries

In order for the absolute encoder to retain position data when the power is turned OFF, the data must be backed up by a battery.

■ Installing the Battery at the Host Device

Lithium battery, by Toshiba: ER6VC3, 3.6 V, 2000 mAh

■ Battery Provided for SERVOPACK

Lithium battery: JZSP-BA01 (includes battery and connector)

Battery: Toshiba, ER3 V, 3.6 V, 1000 mAh

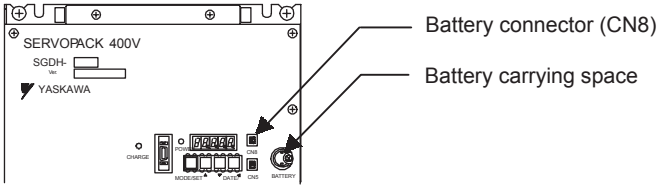


Fig. 4.1 SERVOPACKs with Capacities of 22 kW to 55 kW

⃠ PROHIBITED
• Install the battery at either the host controller or the SERVOPACK. It is dangerous to install batteries at both simultaneously, because that sets up a loop circuit between the batteries.

4.7.4 Absolute Encoder Setup

Perform the setup operation for the absolute encoder in the following circumstances:

- When starting the machine for the first time.
- When an encoder backup alarm is generated.
- When the SERVOPACK's power supply is turned OFF and the encoder's cable is removed.

The setup operation can be performed by using the Hand-held Digital Operator or the SERVOPACK's Panel Operator, or else personal computer monitor software can be employed.

The setup operation procedure shown here uses the Digital Operator. For more details, refer to *Chapter6 Using the Digital Operator*.

INFO

The absolute encoder setup operation is only possible when the servo is OFF. After the setup processing is finished, turn the power back ON again.

■ Setup Using the Hand-held Digital Operator

1. Press the DSPL/SET Key to select the auxiliary function mode.



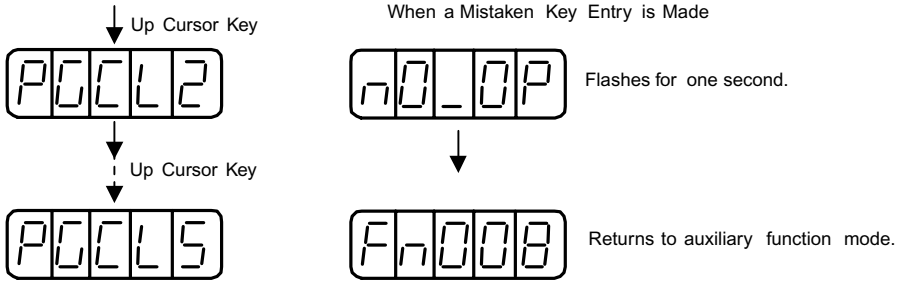
2. Select the parameter Fn008. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



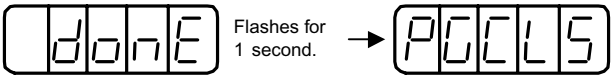
3. Press the DATA/ENTER Key. The following display will appear.



4. Pressing the Up Cursor Key will change the display as shown below. Continue pressing the Up Cursor Key until "PGCL5" is displayed. If an erroneous key entry is made, "nO_OP" will flash for one second and the display will return to the auxiliary function mode. In that case, go back to step 3 above and perform the operation again.



5. When "PGCL5" is displayed, press the DSPL/SET Key. The display will change as follows, and the absolute encoder's multiturn data will be cleared.



6. Press the DATA/ENTER Key to return the auxiliary function mode.



This completes the absolute encoder's setup operation. Turn the power OFF and then back ON again.

■ Setup Using the Built-in Panel Operator

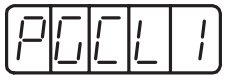
1. Press the MODE/SET Key to select the auxiliary function mode.



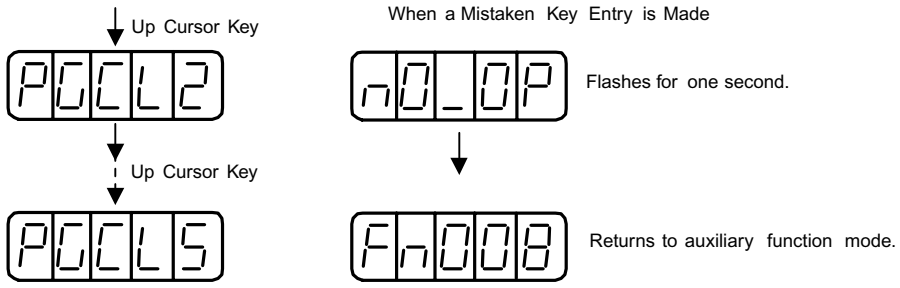
2. Press the Up or Down Cursor Key to select the parameter Fn008.



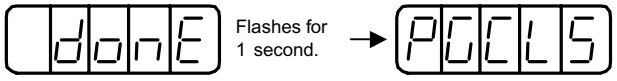
3. Press the DATA/SHIFT Key for at least one second. The following display will appear.



4. Pressing the Up Cursor Key will change the display as shown below. Continue pressing the Up Cursor Key until "PGCL5" is displayed. If an erroneous key entry is made, "nO_OP" will flash for one second and the display will return to the auxiliary function mode. In that case, go back to step 3 above and perform the operation again.



5. When "PGCL5" is displayed, press the MODE/SET Key. The display will change as follows, and the absolute encoder's multiturn data will be cleared.



6. Press the DATA/SHIFT Key for at least one second to return to the auxiliary function mode.



This completes the absolute encoder's setup operation. Turn the power OFF and then back ON again.

IMPORTANT

If the following absolute encoder alarms are displayed, the alarms must be cleared using the method described on the previous page for the setup operation. They cannot be cleared by the SERVOPACK's alarm reset (/ARM-RST) input signal.

- Encoder backup alarm (A.81)
- Encoder sum check alarm (A.82)

In addition, if a monitoring alarm is generated in the encoder, the alarm must be cleared by turning OFF the power.

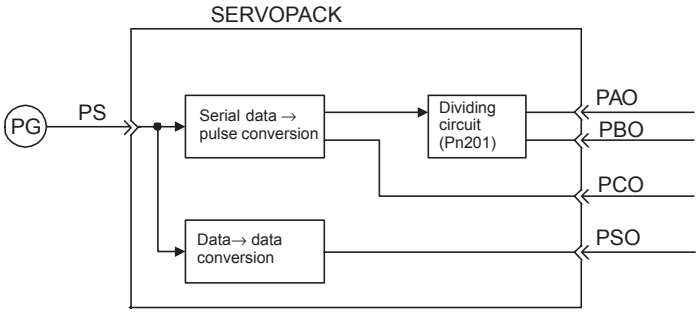
4.7.5 Absolute Encoder Reception Sequence

The sequence in which the SERVOPACK receives outputs from the absolute encoder and transmits them to the host device is shown below.

Be sure you understand this section when designing the host device.

■ Outline of Absolute Signals

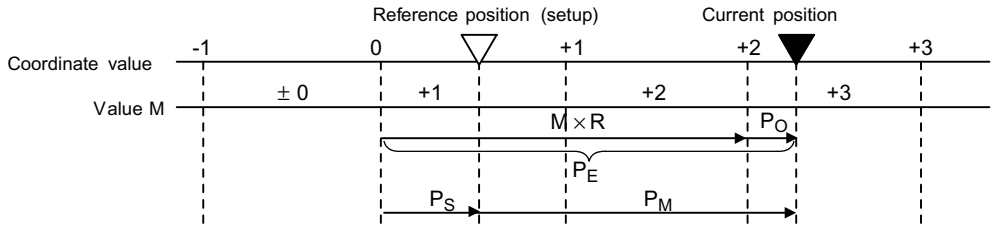
The absolute encoder's outputs are PAO, PBO, PCO, and PSO signals as shown below.



Signal Name	Status	Signal Contents
PAO	Initial state	Serial data Initial incremental pulse
	Normal state	Incremental pulse
PBO	Initial state	Initial incremental pulse
	Normal state	Incremental pulse
PCO	Always	Origin pulse
PSO	Always	Rotation count serial data

■ Contents of Absolute Data

- Serial data: Indicates how many turns the motor shaft has made from the reference position (position specified at setup).
- Initial incremental pulse: Outputs pulses at the same pulse rate as when the motor shaft rotates from the origin to the current position at approximately 2500 min^{-1} (for 16 bits when the dividing pulse is at the factory setting)



The final absolute data P_M can be found by using the following formula.

$P_E = M \times R + P_O$

$P_M = P_E - P_S$

(Use the following for reverse rotation mode (Pn000.0 = 1).

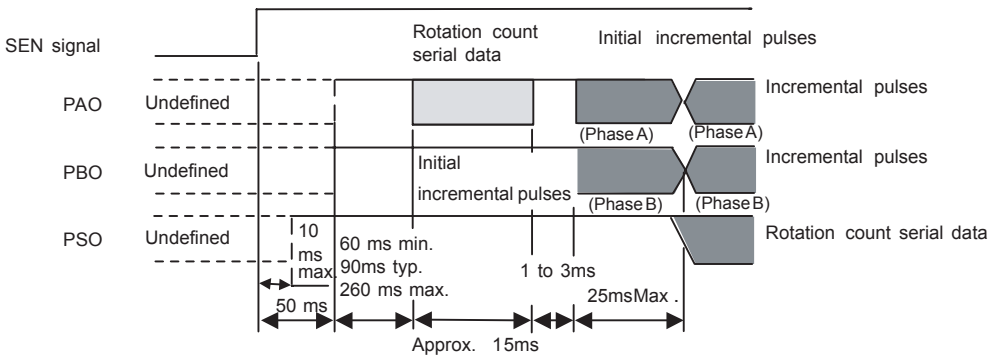
$P_E = -M \times R + P_O$

$P_M = P_E - R_S$

P_E	Current value read by encoder
M	Multiturn data (rotation count data)
P_O	Number of initial incremental pulses
P_S	Number of initial incremental pulses read at setup (This is saved and controlled by the host controller.)
P_M	Current value required for the user's system.
R	Number of pulses per encoder revolution (pulse count after dividing, value of Pn201)

■ Absolute Encoder Transmission Sequence

1. Set the SEN signal at high level.
2. After 100 ms, set the system to serial data reception-waiting-state. Clear the incremental pulse up/down counter to zero.
3. Receive eight bytes of serial data.
4. The system enters a normal incremental operation state approximately 50 ms after the last serial data is received.

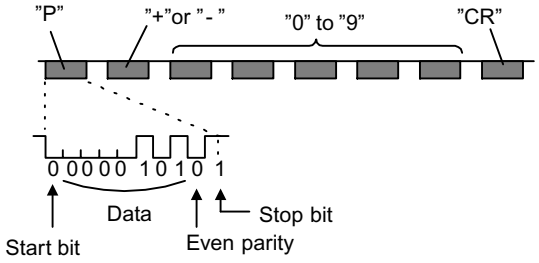


■ Detailed Signal Specifications

PAO Serial Data Specifications

The number of revolutions is output in five digits.

Data Transfer Method	Start-stop Synchronization (ASYNC)
Baud rate	9600 bps
Start bits	1 bit
Stop bits	1 bit
Parity	Even
Character code	ASCII 7-bit code
Data format	8 characters, as shown below.



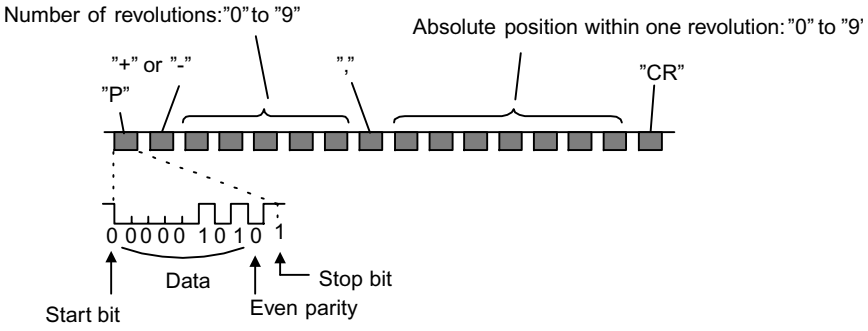
Note: 1. Data is "P+00000" (CR) or "P-00000" (CR) when the number of revolutions is zero.
2. The revolution range is "+32767" to "-32768." When this range is exceeded, the data changes from "+32767" to "-32768" or from "-32768" to "+32767. " When changing multiturn limit, the range changes. For details, see *4.7.6 Multiturn Limit Setting*.

PSO Serial Data Specifications

The number of revolutions and the absolute position within one revolution are always output in five and seven digits, respectively.

The data output cycle is approximately 40 ms.

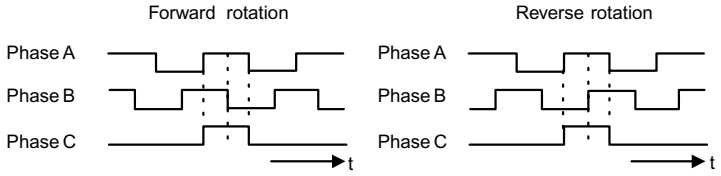
Data Transfer Method	Start-stop Synchronization (ASYNC)
Baud rate	9600 bps
Start bits	1 bit
Stop bits	1 bit
Parity	Even
Character code	ASCII 7-bit code
Data format	13 characters, as shown below.



Note: 1. The absolute position data within one revolution is the value before dividing.
2. Absolute position data increases during forward rotation. (Not valid in reverse rotation mode.)

Incremental Pulses and Origin Pulses

Just as with normal incremental pulses, initial incremental pulses which provide absolute data are first divided by the frequency divider inside the SERVOPACK and then output.



Setting the Pulse Dividing Ratio

Use the following parameter to set the pulse dividing ratio.

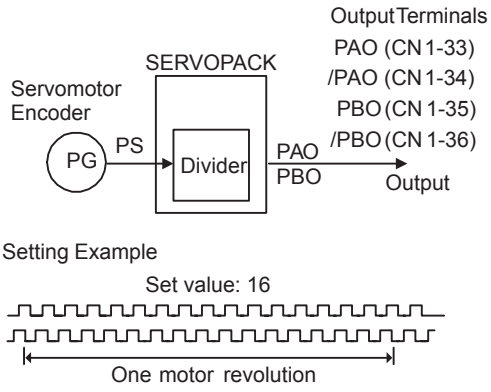
Pn201	PG Divider	Unit: P/R	Setting Range: 16 to 16384	Factory Setting: 16384	Speed/Torque Control, Position Control

This parameter sets the number of output pulses for PG output signals (PAO, /PAO, PBO, /PBO) sent externally.

Pulses from the motor encoder (PG) are divided by the number of pulses set here before being output.

The set value is the number of output pulses per revolution. Set this value according to the reference unit of the machine or controller to be used.

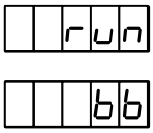
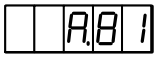
The setting range varies according to the encoder used.



■ Transferring Alarm Contents

When an absolute encoder is used, SEN signals can be utilized to transfer the alarm detection contents from PAO outputs to the host device as serial data.

Table 4.2 Alarm Contents Output Example

SEN Signal	"H" Error detection ▼ "L"	
Digital Operator Display	or 	 Absolute encoder backup alarm
PAO Serial Data	Incremental pulses	ALM81 CR

Refer to *8.2.3 Alarm Display Table* for a table of alarm contents.

4.7.6 Multiturn Limit Setting

When implementing absolute detection systems for machines that turn m times in response to n turns in the load shaft, such as disc tables, it is convenient to reset the multiturn data from the encoder to 0 every m turns. The Multiturn Limit[1] Setting allows the value m to be set for the encoder.

Select the absolute encoder usage with the following parameter.

Pn002.2	Absolute Encoder Usage	Factory Setting: 0	Speed/Torque Control, Position Control

"0" in the following table must be set to enable the absolute encoder.

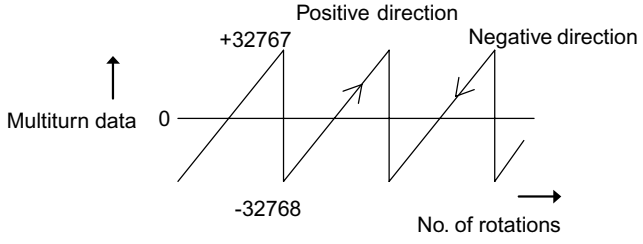
Pn002.2 Setting	Contents
0	Use the absolute encoder as an absolute encoder.
1	Use the absolute encoder as an incremental encoder.

The multiturn limit is set in the SERVOPACK using the following parameter.

Pn205	Multiturn Limit Setting	Unit: rev	Setting Range: 0 to 65535	Factory Setting: 65535	Speed/Torque Control, Position Control

If the Multiturn Limit Setting is set to 65535 (factory setting), the multiturn data will vary from -32768 to 32767. If any other value is set, the multiturn data will vary from 0 to the setting of Pn205.

- Variation of multiturn data when the multiturn limit value is 65535 (factory setting).

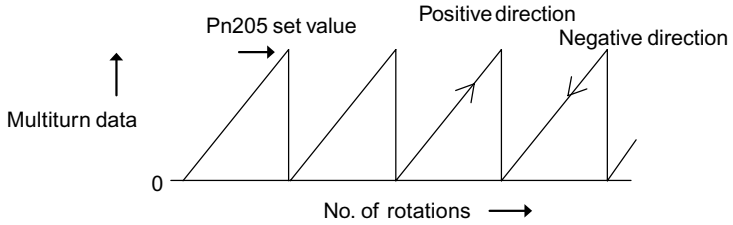


TERMS

[1] Multiturn limit

The multiturn limit is the upper limit of the multiturn data. If Pn002.2 = 0, the multiturn data will vary between 0 and the value set for Pn205 (Multiturn Limit Setting).

- Variation of multiturn data when the multiturn limit value is other than 65535 (factory setting).



If the servomotor rotates in the negative direction from 0, the multiturn data will change to the value set for Pn205. If the servomotor rotates in the positive direction from the value set in Pn205, the multiturn data will change to 0. Set Pn205 to m-1.

INFO Turn the power OFF and then back ON after changing the setting of parameter Pn002.2 or Pn205.

The multiturn limit value in the Encoder is factory set to 65535, the same as the SERVOPACK. If the multiturn limit value in the SERVOPACK is changed with Pn205 and then the SERVOPACK power is turned OFF and ON, the following alarm will occur.

Alarm Name: Multiturn Limit Disagreement

Alarm Display	Alarm Code Outputs			Meaning of Alarm
	ALO1	ALO2	ALO3	
A.CC	ON	OFF	ON	The multiturn limit value is different in the Encoder and SERVOPACK.

Note: OFF: Signals are high level. ON: Signals are low level.

When this alarm occurs, the multiturn limit in the Encoder must be changed. The auxiliary function mode of the Digital Operator is used to change this setting. It can also be set from a personal computer using the Monitor Software.

The procedure to set the multiturn limit in the Encoder using the Digital Operator is provided next. Refer also to *Chapter 6 Using the Digital Operator*.

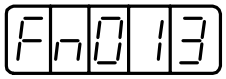
INFO The multiturn limit setting in the Encoder can be changed only when the Multiturn Limit Disagreement alarm has occurred. After changing the setting, turn the power supply OFF and then back ON.

■ Changing the Setting with the Hand-held Digital Operator

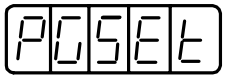
1. Press the DSPL/SET Key to select the auxiliary function mode.



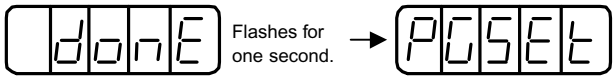
2. Select the parameter Fn013. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



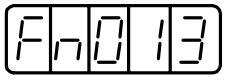
3. Press the DATA/ENTER Key. The following display will appear.



4. Press the DSPL/SET Key. The following display will appear and the multiturn limit setting in the absolute encoder will be changed.



5. Press the DATA/ENTER Key to return the auxiliary function mode.



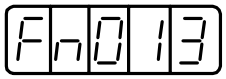
This completes the procedure to change the multiturn limit setting in the absolute encoder. Turn the power OFF and then back ON again.

■ Changing the Setting with the Built-in Panel Operator

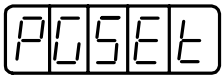
1. Press the MODE/SET Key to select the auxiliary function mode.



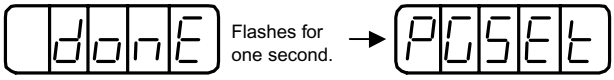
2. Press the Up or Down Cursor Key to select the parameter Fn013.



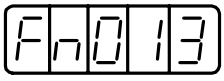
3. Press the DATA/SHIFT Key for at least one second. The following display will appear.



4. Press the MODE/SET Key. The following display will appear and the multiturn limit setting in the absolute encoder will be changed.



5. Press the DATA/SHIFT Key for at least one second to return to the auxiliary function mode.



This completes the procedure to change the multiturn limit setting in the absolute encoder. Turn the power OFF and then back ON again.

⚠ WARNING

- The multiturn limit value must be changed only for special applications.

  Changing it inappropriately or unintentionally can be dangerous.

- If the Multiturn Limit Disagreement alarm occurs, check the setting of parameter Pn205 in the SERVOPACK to be sure that it is correct.

  If Fn013 is executed when an incorrect value is set in Pn205, an incorrect value will be set in the Encoder. The alarm will disappear even if an incorrect value is set, but incorrect positions will be detected, resulting a dangerous situation where the machine will move to unexpected positions.

4.8 Special Wiring

This section describes special wiring methods including the one for noise control. In addition to *4.8.1 Wiring Precautions* and *4.8.2 Wiring for Noise Control*, refer to other sections as necessary.

4.8.1 Wiring Precautions

To ensure safe and stable operation, always observe the following wiring precautions.

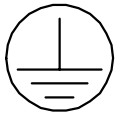
IMPORTANT

1. Always use the following cables for reference input and encoder wiring.

–	Cable Type	Yaskawa Drawing No.	Maximum Allowable Length
Reference Input	Twisted-pair wires	JZSP-CKI01	3 m (118 in)
Encoder	Multiconductor shielded twisted-pair wire	JZSP-CMP09	20 m (787 in)
		JZSP-CMP19	50 m (1969 in)

   - Trim off the excess portion of the cable to minimize the cable length.

2. For a ground wire, use as thick a cable as possible (2 mm^2 or thicker).

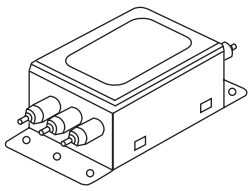


   - Ground resistance of 100 Ω max. is recommended.
   - Ground to one point only.
   - If the motor is insulated from the machine, ground the motor directly.

3. Do not bend or apply tension to cables.

   The conductor of a signal cable is very thin (0.2 to 0.3 mm (0.0079 to 0.012 in)), so handle the cables with care.

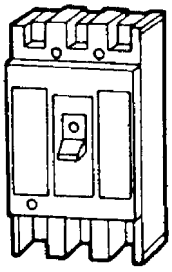
4. Use a noise filter to prevent noise interference. (For details, refer to *4.8.2 Wiring for Noise Control*.)
   - If the equipment is to be used near private houses or may receive noise interference, install a noise filter on the input side of the power supply line.
   - Since this SERVOPACK is designed as an industrial device, it provides no mechanism to prevent noise interference.



5. To prevent malfunction due to noise, take the following actions:
   - Position the input reference device and noise filter as close to the SERVOPACK as possible.
   - Always install a surge absorber circuit in the relay, solenoid and electromagnetic contactor coils.
   - The distance between a power line (such as a power supply line or motor cable) and a signal line must be at least 30 cm. Do not put the power and signal lines in the same duct or bundle them together.
   - Do not share the power supply with an electric welder or electrical discharge machine. When the SERVOPACK is placed near a high-frequency oscillator, install a noise filter on the input side of the power supply line.

   Note: 1. Since the SERVOPACK uses high-speed switching elements, signal lines may receive noise. To prevent this, always take the above actions.
   2. For details on grounding and noise filters, refer to *4.8.2 Wiring for Noise Control*.

6. Use a molded-case circuit breaker (QF) or fuse to protect the power supply line from high voltage.
   - This SERVOPACK connects directly to a commercial power supply without a transformer, so always use a QF or fuse to protect the servo system from accidental high voltage.
   - Refer to *7.5.10 Molded-case Circuit Breaker (MCCB)* to select an appropriate QF or fuse according to the SERVOPACK capacity.



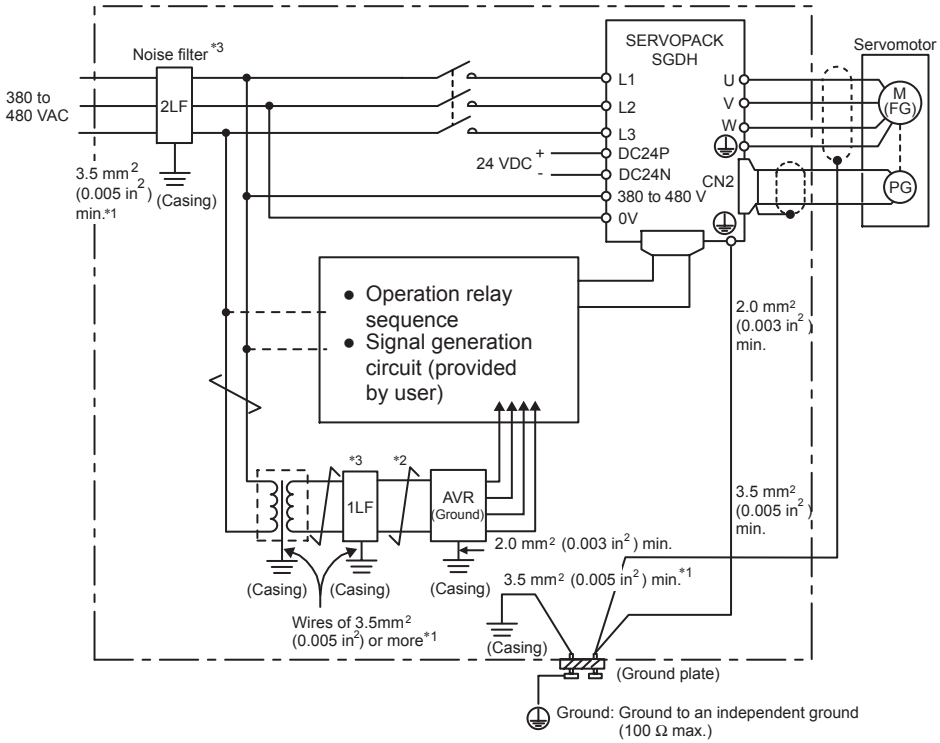
4.8.2 Wiring for Noise Control

■ Wiring Example

This SERVOPACK uses high-speed switching elements in the main circuit. It may receive "switching noise" from these high-speed switching elements if wiring or grounding around the SERVOPACK is not appropriate. To prevent this, always wire and ground the SERVOPACK correctly.

This SERVOPACK has a built-in microprocessor (CPU), so it is necessary to protect it from external noise as much as possible by installing a noise filter in the appropriate place.

The following is an example of wiring for noise control.



* 1. For ground wires connected to the casing, use a thick wire with a thickness of at least 3.5 mm^2 (0.005 in^2) (preferably, plain stitch cooper wire).

* 2. For wires indicated by ⇌ use twisted-pair wires whenever possible.

* 3. When using a noise filter, follow the precautions in ■ *Using Noise Filters* (*page 4-102*).

■ Correct Grounding

Grounding the Motor Frame

Always connect servomotor frame terminal FG to the SERVOPACK ground terminal ⏚ .

Also be sure to ground the ground terminal ⏚ .

If the servomotor is grounded via the machine, a switching noise current will flow from the SERVOPACK power unit through motor stray capacitance. The above grounding is required to prevent the adverse effects of switching noise.

Noise on the Reference Input Line

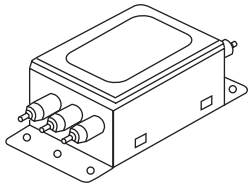
If the reference input line receives noise, ground the 0 V line (SG) of the reference input line. If the main circuit wiring for the motor is accommodated in a metal conduit, ground the conduit and its junction box.

For all grounding, ground at one point only.

■ Using Noise Filters

Use an inhibit type noise filter to prevent noise from the power supply line. Refer to *7.5.11 Noise Filter* for details on recommended noise filters for each SERVOPACK model.

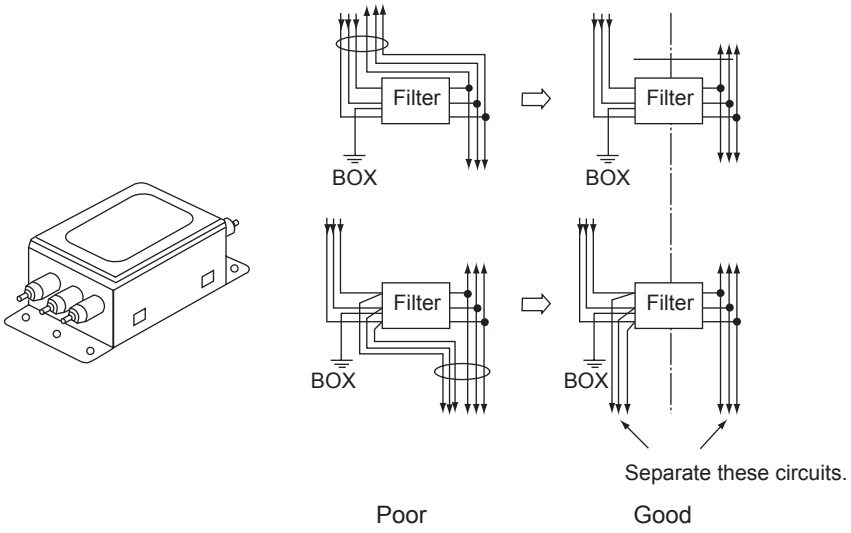
Install a noise filter on the power supply line for peripheral equipment as necessary.



Always observe the following installation and wiring instructions. Incorrect use of a noise filter halves its benefits.

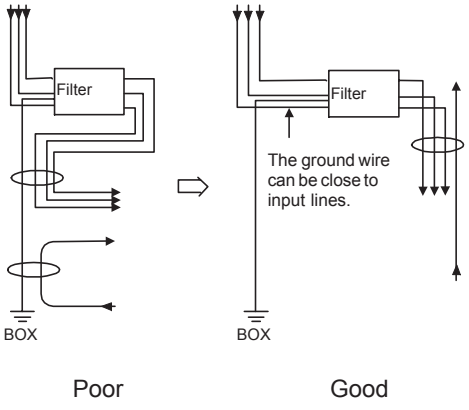
- Separate input lines from output lines.

  Do not put the input and output lines in the same duct or bundle them together.



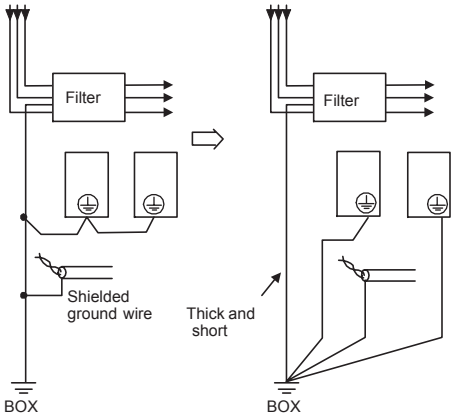
- Separate the noise filter ground wire from the output lines.

  Do not accommodate the noise filter ground wire, output lines and other signal lines in the same duct or bundle them together.



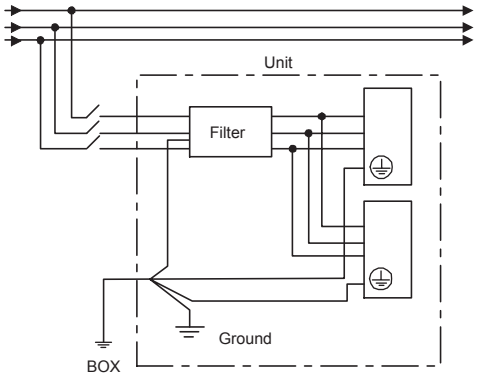
• Connect the noise filter ground wire directly to the ground plate.

Do not connect the noise filter ground wire to other ground wires.



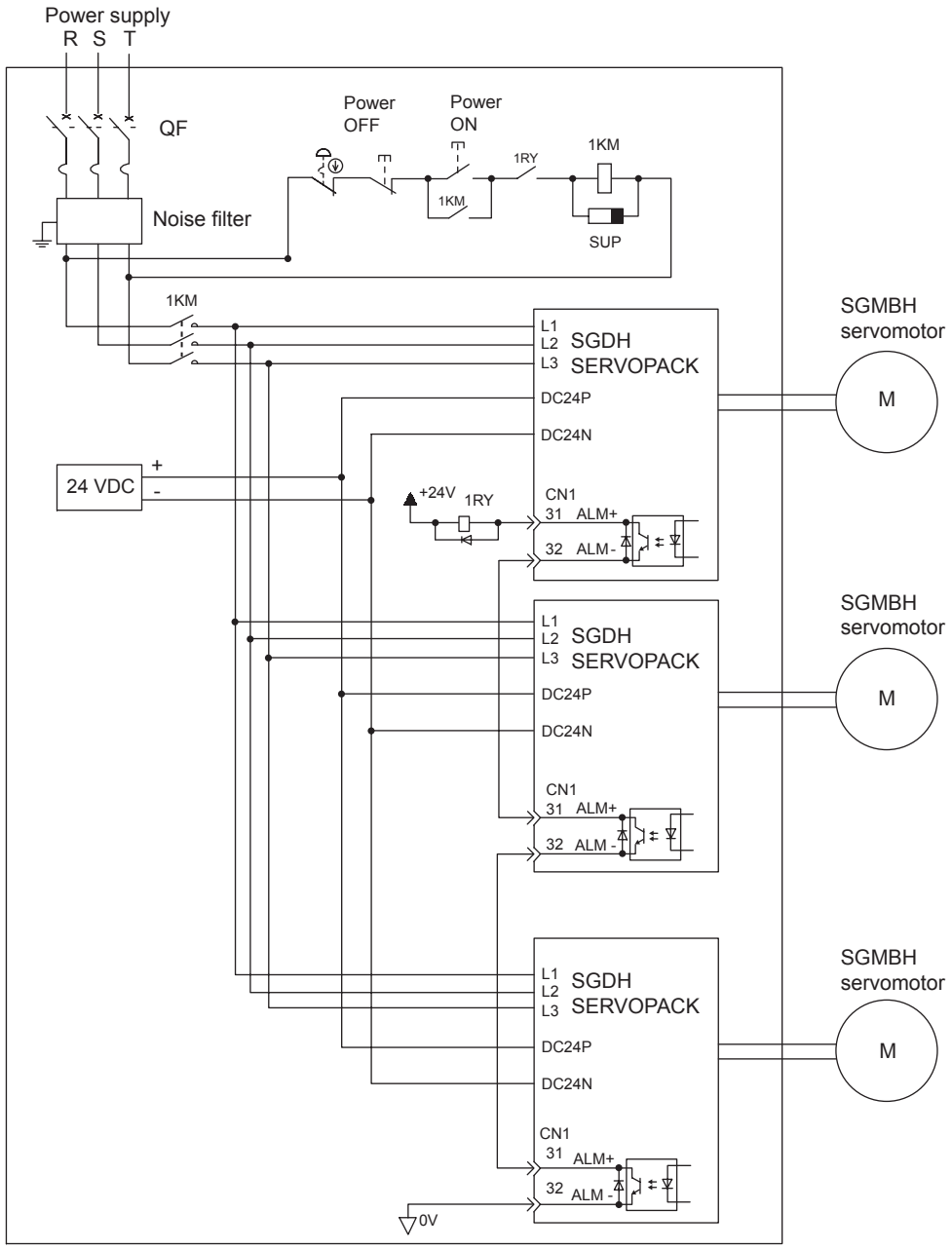
• When grounding a noise filter inside a Unit.

If a noise filter is located inside a Unit, connect the noise filter ground wire and the ground wires from other devices inside the Unit to the ground plate for the Unit first, then ground these wires.



4.8.3 Using More Than One Servodrive

The following diagram is an example of the wiring when more than one Servodrive is used.



Note: Wire the system so that the power supply's phase S is the ground.

Connect the alarm output (ALM) terminals for the three SERVOPACKs in series to enable alarm detection relay 1RY to operate.

The output transistor is turned OFF when the ALM output signal invokes the alarm state.

Multiple servos can share a single QF or noise filter. Always select a QF or noise filter that has enough capacity for the total power capacity (load conditions) of those servos. For details, refer to *7.5.10 Molded-case Circuit Breaker (MCCB)* and *7.5.11 Noise Filter*.

4.8.4 Extending Encoder Cables

Standard encoder cables have a maximum length of 20 m. If a longer cable is required, prepare an extension cable as described below. The maximum allowable cable length is 50 m. For 50-m encoder cables, only the cable lines and connectors are available. The cable must be prepared by the user.

For more details, refer to *7.5.7 Encoder Cables*.

Preparing 50-m (1968.50 in) Encoder Cables

- Cable Lines

Length	Cable Line Model Numbers
30 m (1181.10 in)	JZSP-CMP19-30
40 m (1574.80 in)	JZSP-CMP19-40
50 m (1968.50 in)	JZSP-CMP19-50

When specifying the cable length, just specify the model number:

JZSP-CMP19-□

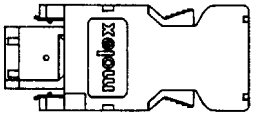
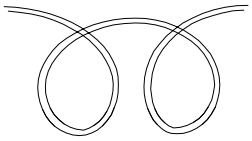
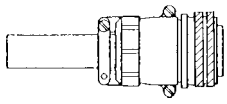
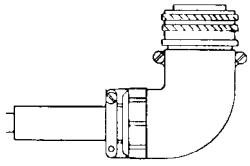
The □ in the model number designates the length of the cable (in meters).

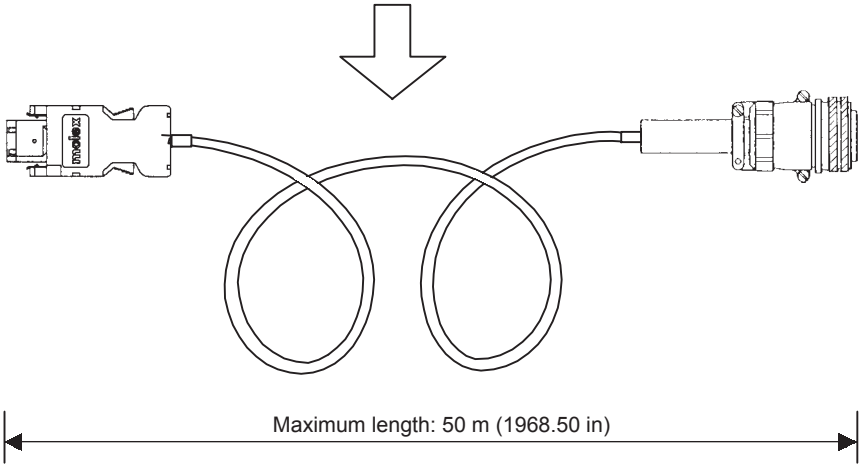
◀ EXAMPLE ▶ For example, to order 35-m cable, specify JZSP-CMP19-35 as the model number.

- Connectors or Connector Kits

Type		Model
SERVOPACK end	Encoder connector (CN2) socket	JZSP-CMP9-1
Servomotor end	Encoder connector plug and cable clamp for SGMBH servomotors	Plug L: MS3108B20-29S Straight: MS3106B20-29S Cable clamp: MS3057-12A

• Preparing Encoder Cables

• Encoder Connector at SERVOPACK	• Cable Line	• Encoder Connector at Servomotor	
 (JZSP-CMP9-1)	 (JZSP-CMP19-□)	 	For SGMBH servomotors



5

Servo Adjustment

This chapter describes the functions required for servo adjustment. Find the required information by selecting the section from the following table of contents.

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5.1.2 Smoothing ---------- 5-3
5.1.3 Adjusting Gain ---------- 5-4
5.1.4 Adjusting Offset ---------- 5-4
5.1.5 Setting the Torque Reference Filter Time Constant ---------- 5-5
5.1.6 Notch Filter ---------- 5-5
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5.2.3 Using Proportional Control ---------- 5-8
5.2.4 Setting Speed Bias ---------- 5-9
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5.1 Smooth Operation

This section provides technical information on the smooth operation of servomotors.

5.1.1 Using the Soft Start Function

The soft start function adjusts progressive speed reference input inside the SERVOPACK so that acceleration and deceleration can be as constant as possible.

To use this function, set the following parameters.

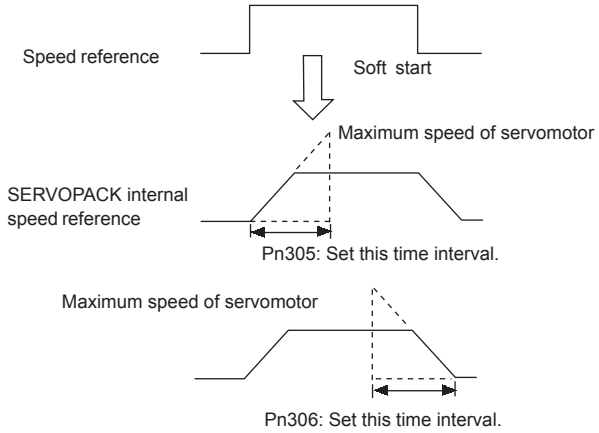
Pn305	Soft Start Acceleration Time	Unit: ms	Setting Range: 0 to 10000	Factory Setting: 0	Speed Control
Pn306	Soft Start Deceleration Time	Unit: ms	Setting Range: 0 to 10000	Factory Setting: 0	Speed Control

In the SERVOPACK, a speed reference is multiplied by the acceleration or deceleration value set in Pn305 or Pn306 to provide speed control.

The soft start function enables smooth speed control when inputting progressive speed references or when selecting internally-set speeds. Set both Pn305 and Pn306 to 0 for normal speed control.

Set these parameters as follows:

- Pn305: The time interval from the time the motor starts until the motor maximum speed is reached.
- Pn306: The time interval from the time the motor is operating at the motor maximum speed until it stops.



5.1.2 Smoothing

A filter can be applied in the SERVOPACK to a constant-frequency reference pulse. Use the following parameter to set the type of filter to be applied.

Pn207.0	Position Reference Filter Selection	Factory Setting: 0	Position Control

Either an acceleration/deceleration or average movement filter can be selected.

Pn207.0 Setting	Contents
0	Acceleration/deceleration filter
1	Average movement filter

The time constant and time for these filters are set in the following parameters.

Time Constant for Acceleration/Deceleration Filter

Pn204	Position Reference Acceleration/ Deceler-ation Time Constant	Unit: 0.01 ms	Setting Range: 0 to 6400	Factory Setting: 0	Position Control

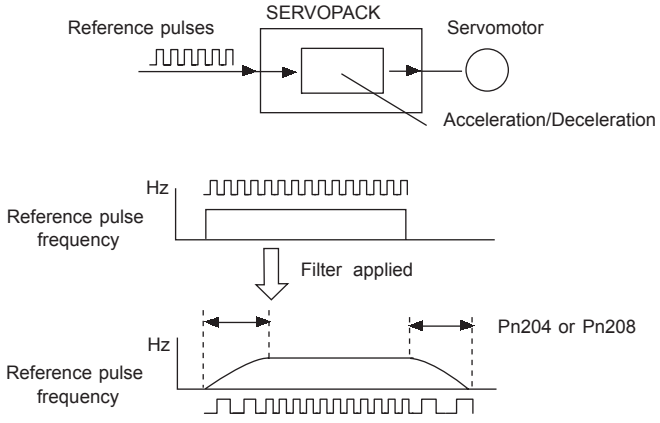
Averaging Time for Average Movement Filter

Pn208	Position Reference Movement Averaging Time	Unit: 0.01 ms	Setting Range: 0 to 6400	Factory Setting: 0	Position Control

This function provides smooth motor operating in the following cases:

- When the host device which outputs references cannot perform acceleration/deceleration processing.
- When the reference pulse frequency is too low.
- When the reference electronic gear ratio is too high (i.e., 10 × or more).

This function does not affect the travel distance (i.e., the number of pulses).



5.1.3 Adjusting Gain

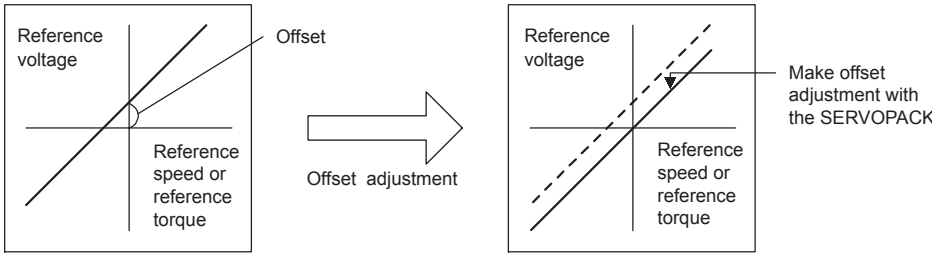
If speed loop gain or position loop gain exceeds the allowable limit for the servo system including the machine to be controlled, the system will tend to vibrate or become too sensitive. Smooth operation is not possible under such conditions, so reduce each loop gain value to an appropriate value.

Refer to *5.2.1 Setting Servo Gain* for details regarding servo gain adjustment.

5.1.4 Adjusting Offset

The servo system does not operate smoothly if reference voltage from the host controller or external equipment has a reference offset value in close proximity to 0 V. In this case, adjust the reference offset value to 0 V.

■ Reference Voltage Offset from Host Controller or External Circuitry



■ Reference Offset Adjustment

The following two methods are available to set the reference offset value to 0 V.

Reference offset automatic adjustment	The reference offset value is automatically set to 0 V.
Reference offset manual adjustment	The reference offset value can be adjusted manually.

IMPORTANT

If a position loop is formed in the host controller, be sure to make manual offset adjustment and do not make automatic reference offset adjustment.

Refer to the following sections in *Chapter 6 Using the Digital Operator* for reference offset adjustment in detail.

Reference offset automatic adjustment	*6.2.3 Automatic Adjustment of the Speed and Torque Reference Offset*
Reference offset manual adjustment	*6.2.4 Manual Adjustment of the Speed and Torque Reference Offset*

5.1.5 Setting the Torque Reference Filter Time Constant

If there is machine vibration which may be caused by the servodrive, try adjusting the filter time constant in Pn401. This may stop the vibration.

Pn401	Torque Reference Filter Time Constant	Unit: 0.01 ms	Setting Range: 0 to 65535	Factory Setting: 100	Speed/Torque Control, Position Control

The above constant is the filter time constant of the torque reference to be set in the SERVOPACK. The smaller the value, the faster the speed control response will be. There is, however, a certain limit depending on machine conditions.

5.1.6 Notch Filter

Vibration in the machine can sometimes be eliminated by using a notch filter for the frequency at which the vibration is occurring.

Pn408.0	Notch Filter Selection	Factory Setting: 0	Speed/Torque Control, Position Control

This parameter can be set to enable the notch filter.

Pn408.0 Setting	Contents
0	None
1	Notch filter used for torque reference.

The frequency at which the machine is vibrating is set in the following parameter.

Pn409	Notch Filter Frequency	Unit: Hz	Setting Range: 50 to 2000	Factory Setting: 2000	Speed/Torque Control, Position Control

5.2 High-speed Positioning

This section provides technical information on high-speed positioning.

5.2.1 Setting Servo Gain

Use the servo gain setting function in the following cases.

- To check each servo gain value that is automatically set after auto-tuning.
- To directly set each of the above servo gain values in another SERVOPACK.
- To further refine responsiveness after autotuning (either to increase responsiveness or to reduce it).

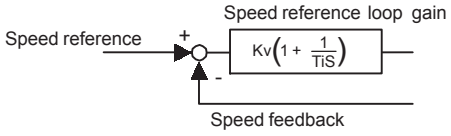
■ Setting Speed Loop Gain

Set the following speed-loop-related parameters as required.

Pn100	Speed Loop Gain (Kv)	Unit: Hz	Setting Range: 1 to 2000	Factory Setting: 40	Speed/Torque Control, Position Control
Pn101	Speed Loop Integral Time Constant (Ti)	Unit: 0.01 ms	Setting Range: 15 to 51200	Factory Setting: 2000	Speed/Torque Control, Position Control

The above constants are the SERVOPACK's speed loop gain and integral time constant respectively.

The higher the speed loop gain, or the smaller the speed loop integral time constant value, the faster the speed control response will be. There is, however, a certain limit depending on machine characteristics.



Speed loop gain Kv is adjusted in 1-Hz increments provided that the following parameter is set correctly.

Pn103	Inertia Ratio	Unit: %	Setting Range: 0 to 10000	Factory Setting: 0	Speed/Torque Control, Position Control

$$\text{Inertia ratio} = \frac{\text{Motor axis conversion load moment of inertia } (J_L)}{\text{Servomotor rotor moment of inertia } (J_M)} \times 100\ (\%)$$

The load moment of inertia of the SERVOPACK converted on the basis of the motor shaft is factory-set to the rotor moment of inertia of the servomotor. Therefore, obtain the inertia ratio from the above formula and set parameter Pn103 properly.

The above parameters are automatically set by the autotuning operation.

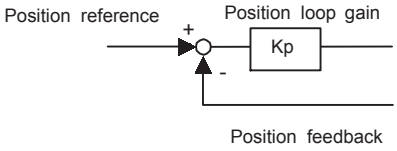
■ Setting Position Loop Gain

Set the following position loop-related parameter as required.

Pn102	Position Loop Gain (Kp)	Unit: 1/s	Setting Range: 1 to 2000	Factory Setting: 40	Speed Control, Position Control

The above constant is the position loop gain for the SERVOPACK.

The higher the position loop gain, the smaller the position control error will be. There is, however, a certain limit depending on machine characteristics.

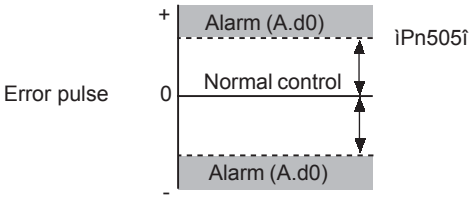


This gain setting is also valid for zero clamp operation.

The above parameter is automatically set by the autotuning operation.

Pn505	Overflow level	Unit: 256 reference units	Setting Range: 1 to 32767	Factory Setting: 1024	Position Control

Set in this parameter the error pulse level at which a position error pulse overflow alarm (A.d0) is detected.



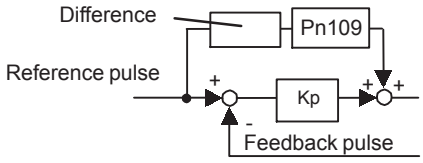
If the machine permits only a small position loop gain value to be set in Pn102, an overflow alarm may arise during high-speed operation. In this case, increase the value set in this parameter to suppress alarm detection.

5.2.2 Using Feed-forward Control

The time required for positioning can be shortened with feed-forward control[1] by setting the following parameter.

Pn109	Feed-forward	Unit: %	Setting Range: 0 to 100	Factory Setting: 0	Position Control

This parameter is set to apply feed-forward frequency compensation to position control inside the SERVOPACK. Use this parameter to shorten positioning time. Too high a value may cause the machine to vibrate. For ordinary machines, set 80% or less in this constant.

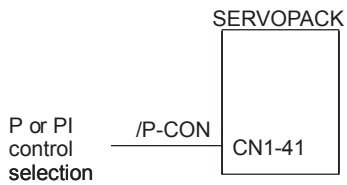


5.2.3 Using Proportional Control

If parameter Pn000.1 is set to 0 or 1 as shown below, input signal /P-CON serves as a PI/P control changeover switch.

- PI control: Proportional/integral control.
- P control: Proportional Control

Pn000.1	Control Method Selection	Factory Setting: 0	Speed/Position Control

Pn000.1 Setting	Control Mode		
0	Speed Control	Usual speed control or position control is selected. Input signal /P-CON (CN1-41) is used to select PI control or P control.	
1	Position Control	CN1-41 is open. → PI control CN1-41 is 0 V. → P control	

TERMS

[1] Feed-forward control

Feed-forward control is a type of control in which necessary control connections are made in advance before the control system is affected by external disturbance. Feed-forward control increases the effective servo gain, thus making it possible to improve the response performance of the system.

■ Methods for Using Proportional Control

Proportional control can be used in the following two ways.

- When operation is performed by sending speed references from the host controller to the SERVOPACK, the host controller can selectively use P control mode for particular conditions only. This method can suppress overshooting and shorten setting time. Refer to *5.2.5 Using Mode Switch* for particular conditions.
- If PI control mode is used when the speed reference has a reference offset, the motor may rotate at a very slow speed and fail to stop even if 0 is specified as a speed reference. In this case, use P control mode to stop the motor.

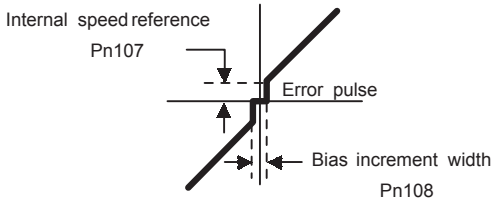
5.2.4 Setting Speed Bias

The setting time for positioning can be reduced by assigning bias to the speed reference block in the SERVOPACK. To assign bias, use the following parameters.

Pn107	Bias	Unit: min^{-1}	Setting Range: 0 to 450	Factory Setting: 0	Position Control
Pn108	Bias Addition Width	Unit: reference units	Setting Range: 0 to 250	Factory Setting: 7	Position Control

Set the parameters to shorten the time required for positioning according to the application.

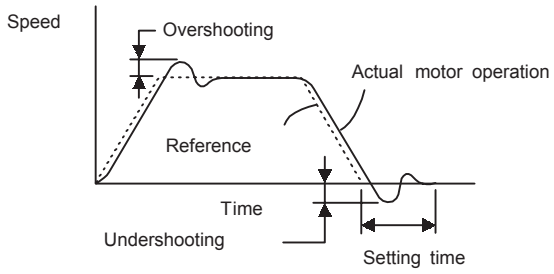
The bias increment width (Pn108) is expressed by an error pulse width that determine the timing of giving bias input (Pn107). The bias input is ON if the error pulse width exceeds the value set in Pn108.



5.2.5 Using Mode Switch

Use the mode switch function for the following purposes.

- To suppress overshooting during acceleration or deceleration (for speed control).
- To suppress undershooting during positioning and to shorten the setting time (for position control).



The mode switch function makes it possible to automatically switch over the SERVOPACK's internal speed control mode from PI to P control[1] mode and vice versa when specified conditions are satisfied.

IMPORTANT

1. The mode switch is used to fully utilize performance of a servodrive to achieve very high-speed positioning. The speed response waveform must be observed to adjust the mode switch.
2. For normal use, the speed loop gain and position loop gain set by autotuning provide sufficient speed/position control. Even if overshooting or undershooting occur, they can be suppressed by setting the acceleration/deceleration time constant for the host device, the soft start time constants (Pn305, Pn306), or position reference acceleration/deceleration constant (Pn204) for the SERVOPACK.

TERMS

[1] From PI control to P control

PI control means proportional/integral control and P control means proportional control. In short, switching "from PI control to P control" reduces effective servo gain, making the servo system more stable.

■ Selecting Mode Switch Setting

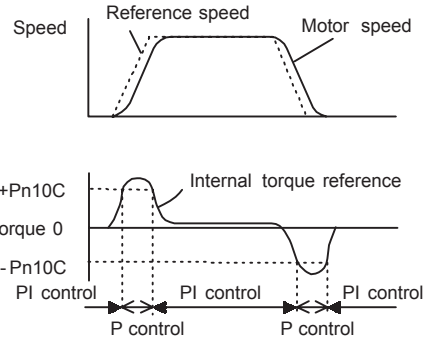
The SERVOPACK incorporates four mode switch settings (0 to 3). Select a mode switch with the following parameter (Pn10B.0).

Pn10B.0 Setting	Selecting Mode Switch Setting	Parameter to Set Detective Point	Set Unit
0	Uses torque reference as the detection point. (Standard setting)	Pn10C	Percentage of rated torque: %
1	Uses speed reference input as the detection point.	Pn10D	Motor speed: min^{-1}
2	Uses acceleration as the detection point.	Pn10E	Motor acceleration:10 min^{-1}/s
3	Uses error pulse input as the detection point.	Pn10F	Reference units
4	Mode switch function is not used.	-	-

Torque Reference Input Used as Detection Point (Standard Setting)

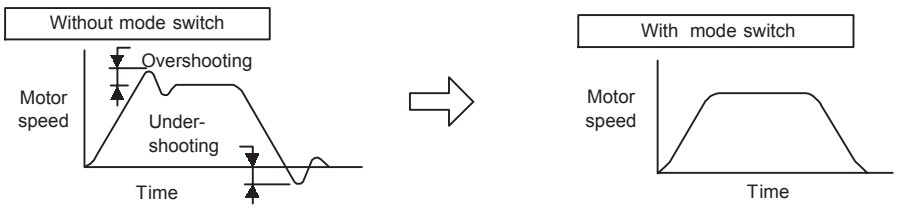
With this setting, if the value of torque reference input exceeds the torque set in parameter Pn10C, the speed loop switches to P control.

The SERVOPACK is factory-set to this standard mode. (Pn10C = 200)



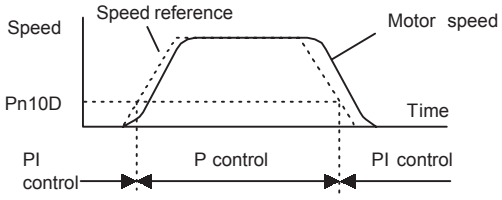
◀ EXAMPLE ▶ Operating Example

If the system is always in PI control without using the mode switch function, the speed of the motor may overshoot or undershoot due to torque saturation at the time of the acceleration or deceleration of the motor. The mode switch function suppresses torque saturation and eliminates the overshooting or undershooting of the speed of the motor.



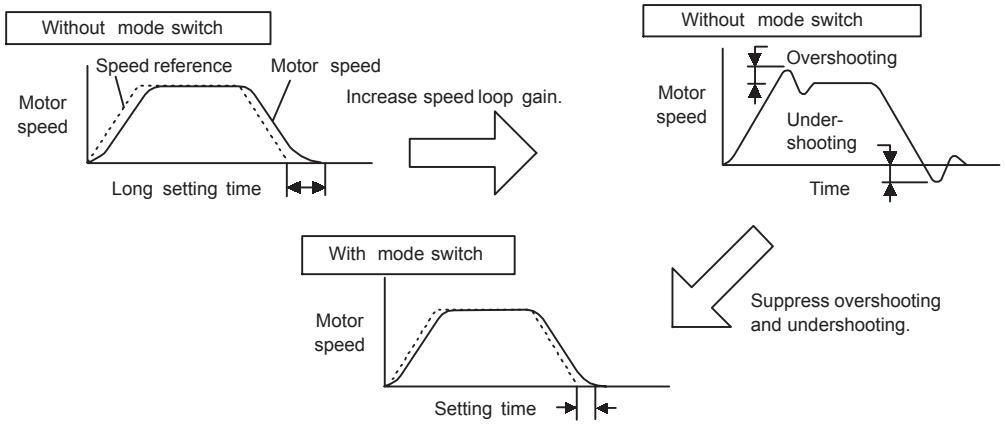
Speed Reference Used as Detection Point

With this setting, if a speed reference exceeds the value set in parameter Pn10D, the speed loop switches to P control.



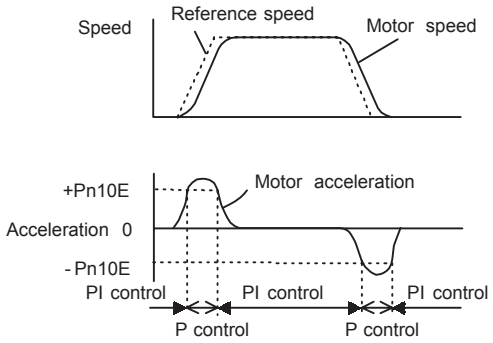
◀ EXAMPLE ▶ Operating Example

In this example, the mode switch is used to reduce setting time. Generally, speed loop gain must be increased to reduce setting time. Using the mode switch suppresses the occurrence of overshooting and undershooting when speed loop gain is increased.



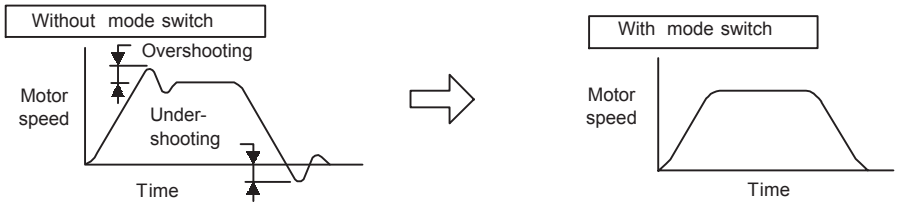
Acceleration Used as Detection Point

If motor acceleration exceeds the value set in parameter Pn10E, the speed loop switches to P control.



◀ EXAMPLE ▶ Operating Example

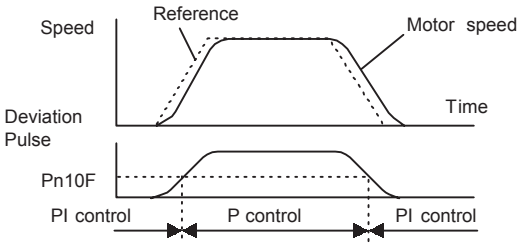
If the system is always in PI control without using the mode switch function, the speed of the motor may overshoot or undershoot due to torque saturation at the time of the acceleration or deceleration of the motor. The mode switch function suppresses torque saturation and eliminates the overshooting or undershooting of the speed of the motor.



Error Pulse Used as Detection Point

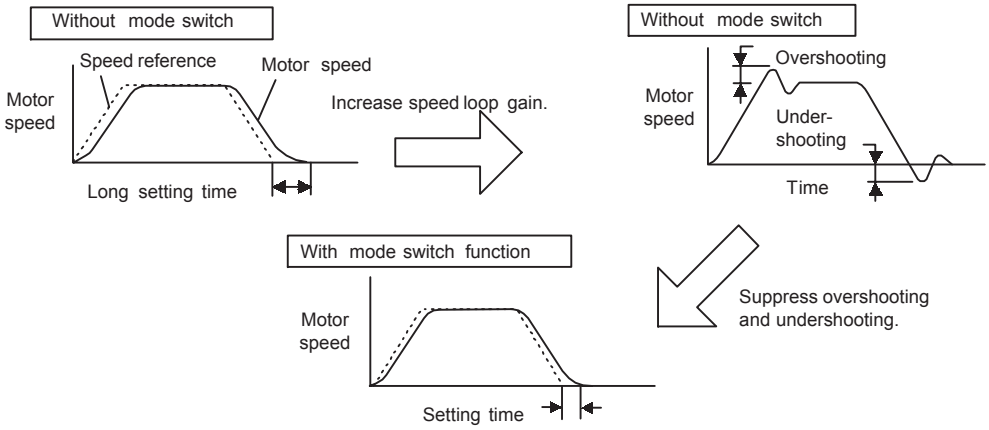
This setting is enabled for position control operation only.

If an error pulse exceeds the value set in parameter Pn10F, the speed loop switches to P control.



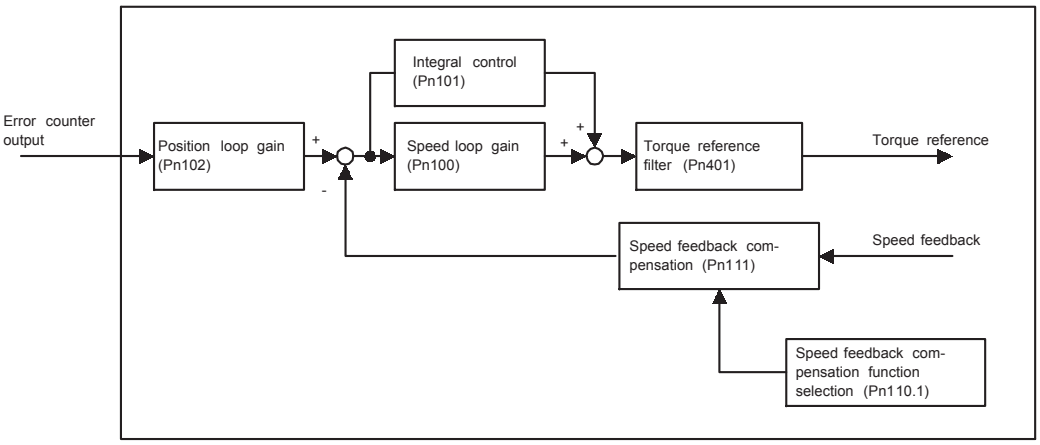
◀ EXAMPLE ▶ Operating Example

In this example, the mode switch is used to reduce setting time. Generally, speed loop gain must be increased to reduce setting time. Using the mode switch suppresses the occurrence of overshooting and undershooting when speed loop gain is increased.



5.2.6 Speed Feedback Compensation

Use this function for shortening the setting time of the system in positioning operation.



INFO

This function is available provided that the inertia ratio set in Pn103 is correct.Therefore, perform online autotuning to obtain and save the results as the parameters. Refer to *5.3 Autotuning* for details. Alternatively, directly set the inertia ratio.

■ Adjustment Procedure

When adding the value of speed feedback compensation, be sure to follow the procedure described below and make servo gain adjustments while watching the analog monitor to observe the position error and torque reference. Refer to *5.5 Analog Monitor* for details.

1. Set parameter Pn110 to “0002” so that the online autotuning function will be disabled. Refer to *5.3.4 Parameters Related to Online Autotuning* and *Appendix A List of Parameters* for details regarding Pn110.
2. First, make normal servo gain adjustments with no feedback compensation. In this case, gradually increase the speed loop gain in Pn100 while reducing the speed loop integral time constant Pn101, and finally, set the sped loop gain Pn100 to the same value as that of the position loop gain in Pn102.

The relationship between the speed loop gain and integral time constant is as follows:

Take the value obtained from the following formula as a reference value for setting the speed loop integral time constant in Pn101.

$$\text{Speed loop integral time constant} = \frac{4}{2\pi \times \text{Speed loop gain}} \text{ [sec]}$$

Unit of speed loop gain :[Hz]

Check the unit when setting the speed loop integral time constant in Pn101. Pn101 can be set in 0.01 ms increments.

The unit of speed loop gain (i.e., Hz) and that of position loop gain (i.e., 1/s) are different to each other. Set these gains to the same value, however.

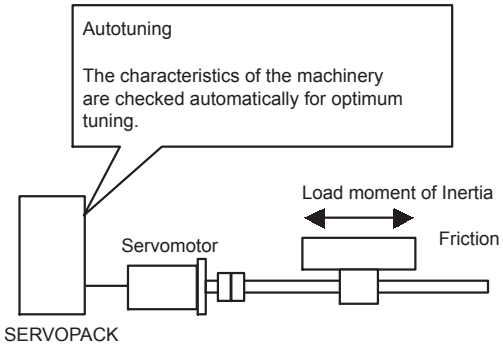
3. Repeat step 2. to increase the speed loop gain while watching the position error of the analog monitor to observe the setting time and the torque reference of the analog monitor to observe any occurrence of vibration. If there is any oscillating noise or noticeable vibration, gradually increase the time constant of the torque reference filter in Pn401.
4. Gradually increase only the position loop gain. When it has been increased about as far as possible, then decrease the speed feedback compensation in Pn111 from 100% to 90%. Then repeat steps 2. and 3.
5. Decrease the speed feedback compensation to a value lower than 90%. Then repeat steps 2. through 4. to shorten the setting time. If the speed feedback compensation is too low, however, the response waveform will vibrate.
6. Find the condition in which the shortest setting time is obtainable within the range where the position error or torque reference waveform observed through the analog monitor is not vibrating or unstable.
7. The servo gain adjustment is completed when no further shortening of the positioning time is possible.

IMPORTANT

Speed feedback compensation usually makes it possible to increase the speed loop gain and position loop gain.The machinery may vibrate excessively if the compensation value greatly changes or Pn110.1 is set to “1” (i.e., no speed feedback compensation enabled) after increasing the speed loop gain or position loop gain. The machinery may malfunction.

5.3 Autotuning

If positioning is taking a long time, the speed loop gain or position loop gain of the servo system may not be set properly. If the gain settings are wrong, set them properly in accordance with the configuration and rigidity of the machinery.



The SERVOPACK incorporates an online autotuning function, which checks the characteristics of the machinery automatically and makes the necessary servo gain adjustments. The function is easy to use and makes it possible for even beginners to perform servo gain tuning and set all servo gains as parameters.

The following parameters can be set automatically by using the online autotuning function.

Parameter	Contents
Pn100	Speed loop gain
Pn101	Speed loop integral time constant
Pn102	Position loop gain
Pn401	Torque reference filter time constant

5.3.1 Online Autotuning

Online autotuning is a control function which enables the Servoamp to check changes in the load moment of inertia during operation in order to maintain the target value for speed loop gain or position loop gain.

Online autotuning may not work well in the following cases.

- When the cycle for load moment of inertia change is 200 ms or shorter (when the load changes rapidly).
- When the application has slow acceleration or deceleration using the soft start function, and the speed error of the servomotor being driven is small.
- When adjusting the servomotor manually and operating at low gain (a machine rigidity of 1 or less).

Disable the online autotuning function if tuning is not possible. (See *5.4.3 Making Manual Adjustments*.)

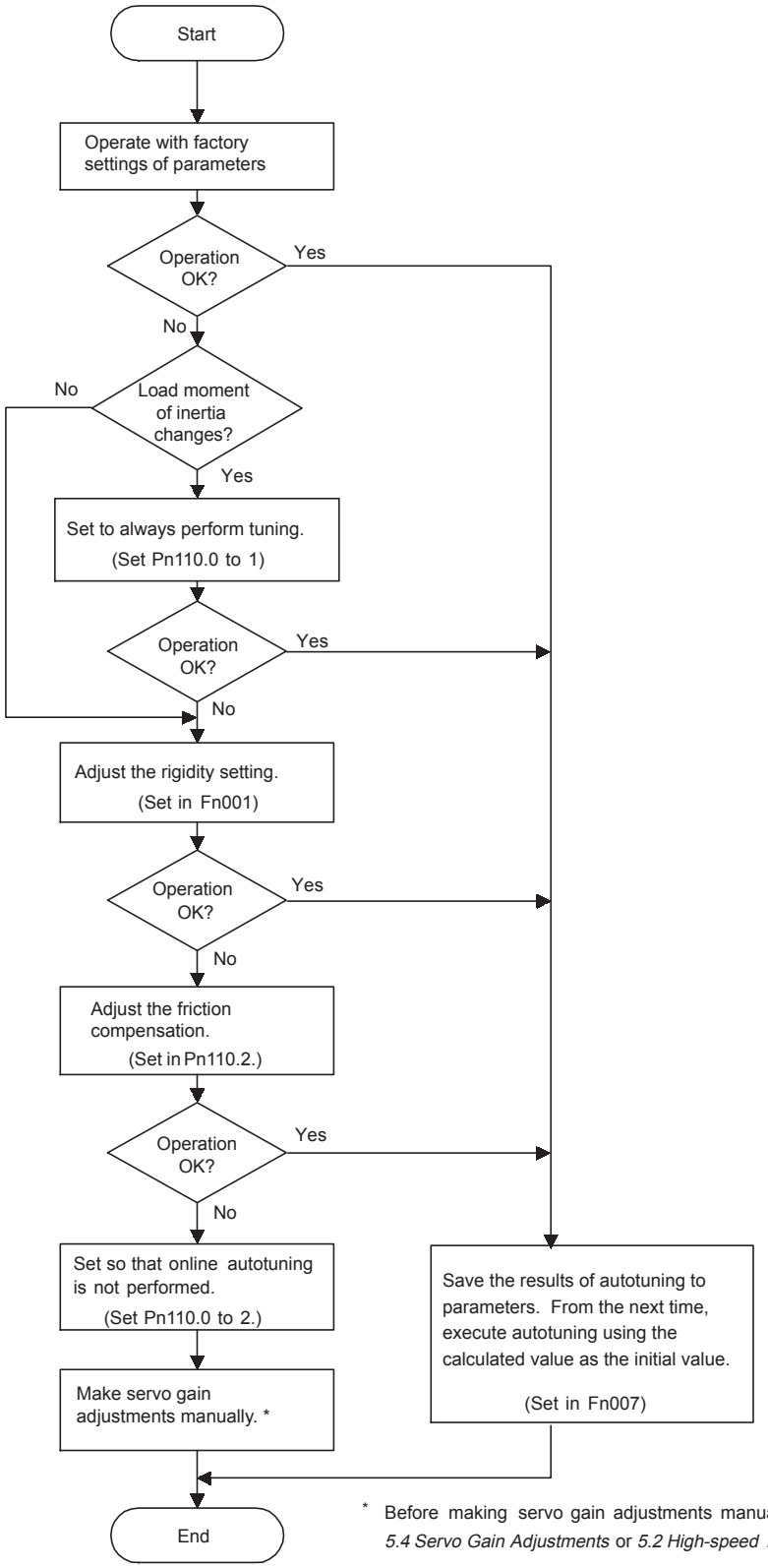
IMPORTANT

Do not use online autotuning in the following cases.

- When driving using Torque Control Mode.
- When using IP control for the speed loop.
- When using the torque feed-forward function.
- When switching gain using /G-SEL.

■ Setting Parameters for Online Autotuning

The following flowchart shows the procedure for setting the parameters for online autotuning.



* Before making servo gain adjustments manually, refer to *5.4 Servo Gain Adjustments* or *5.2 High-speed Positioning*.

5.3.2 Machine Rigidity Settings for Online Autotuning

For the machine rigidity settings at the time of online autotuning, select the target values for speed loop gain and position loop gain of the servo system. Any of the following ten levels of rigidity can be selected.

Rigidity Setting Fn001	Position Loop Gain [S^{-1}] Pn102	Speed Loop Gain [Hz] Pn100	Speed Loop Integral Time Constant [0.01ms] Pn101	Torque Reference Filter Time Constant [0.01ms] Pn401
1	15	15	6000	250
2	20	20	4500	200
3	30	30	3000	130
4	40	40	2000	100
5	60	60	1500	70
6	85	85	1000	50
7	120	120	800	30
8	160	160	600	20
9	200	200	500	15
10	250	250	400	10

Note: The Rigidity value is factory-set to 4.

As the rigidity value is increased, the servo system loop gain increases and the time required for positioning is shortened. If the rigidity is excessively high, however, it may cause the machinery to vibrate. In that case, decrease the set value.

The rigidity value setting automatically changes the parameters in the above table.



If parameters Pn102, Pn100, Pn101, and Pn401 are set manually with the online autotuning function enabled, tuning is performed with the manually set values as target values.

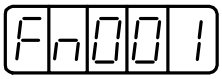
■ Changing the Rigidity Setting

Use parameter Fn001 in the auxiliary function mode to change the rigidity setting.

The procedure for changing the setting is as follows:

Using the Hand-held Digital Operator

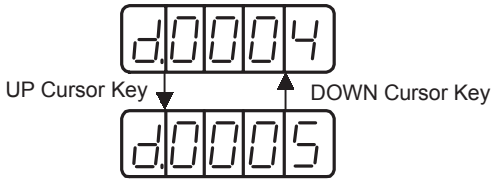
1. Press the DSPL/SET Key and select Fn001 in the auxiliary function mode.



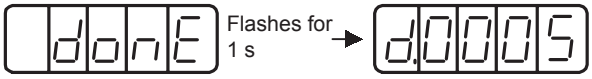
2. Press the DATA/ENTER Key. The following display will appear.



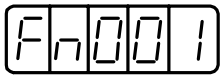
3. Press the Up or Down Cursor Key to select the rigidity setting.



4. Press the DSPL/SET Key. The following display will flash for 1 second and then the rigidity setting will be changed.



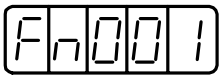
5. Press the DATA/ENTER Key to return to the auxiliary function mode.



This completes the procedure for changing the rigidity setting.

Using the Built-in Panel Operator

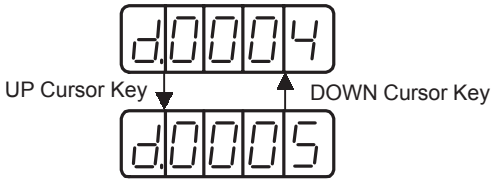
1. Press the MODE/SET Key to select Fn001 in the auxiliary function mode.



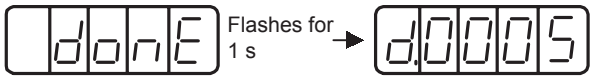
2. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



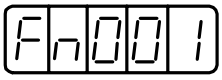
3. Press the Up or Down Cursor Key to select the rigidity setting.



4. Press the MODE/SET Key. The following display will flash for 1 second and then the rigidity setting will be changed.



5. Press the DATA/SHIFT Key for at least one second to return to the auxiliary function mode.



This completes the procedure for changing the rigidity setting.

5.3.3 Saving Results of Online Autotuning

Online autotuning always processes the latest load moment of inertia to renew data so that the speed loop gain will reach the target value that has been set. When the SERVOPACK is turned OFF, all the processed data is lost. Therefore, when the SERVOPACK is turned ON again, online autotuning is performed by processing the factory-set values in the SERVOPACK.

To save the results of online autotuning and use them as the initial values set in the SERVOPACK when the SERVOPACK is turned ON again, it is necessary to set parameter Fn007 in the auxiliary function mode. In this case, the inertia value set in parameter Pn103 can be changed.

On the basis of the rotor moment of inertia of the servomotor, the inertia ratio is expressed in percentage terms by the load moment of inertia. The value set in Pn103 is used to calculate the load moment of inertia at the time of online autotuning.

Pn103	Inertia Ratio	Unit: %	Setting Range: 0 to 10000	Factory Setting: 0	Speed/Torque Control, Position Control

$$\text{Inertia ratio} = \frac{\text{Motor axis conversion load moment of inertia } (J_L)}{\text{Servomotor rotor moment of inertia } (J_M)} \times 100\ (\%)$$

The inertia ratio is factory-set to 0%.

IMPORTANT

Before making servo gain adjustments manually, be sure to set the inertia ratio in Pn103 .If the inertia ratio is incorrect, the speed loop gain (in 1-Hz increments) set in Pn100 will be wrong.

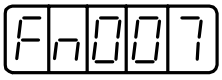
For details on setting Pn103, refer to *6.1.6 Operation in Parameter Setting Mode*.

■ Procedure for Saving Results of Online Autotuning

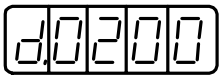
The procedure for saving the results of online autotuning is as follows:

Using the Hand-held Digital Operator

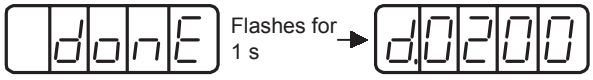
1. Press the DSPL/SET Key to select Fn007 in the auxiliary function mode.



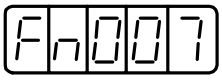
2. Press the DATA/ENTER Key. If the inertia ratio is 200%, for example, the following data will be displayed.



3. Press the DSPL/SET Key. The following display will flash for 1 second and then the inertia ratio will be saved.



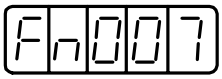
4. Press the DATA/ENTER Key to return to the auxiliary function mode.



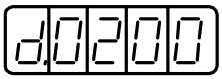
This completes the procedure for saving the results of online autotuning. When the SERVOPACK is turned ON again, the inertia ratio set in Pn103 will be used as the default value.

Using the Built-in Panel Operator

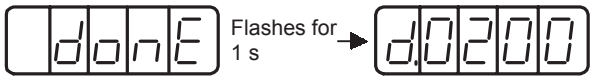
1. Press the MODE/SET Key and select Fn007 in the auxiliary function mode.



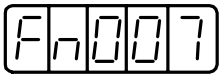
2. Press the DATA/SHIFT Key for a minimum of one second. If the inertia ratio is 200%, for example, the following data will be displayed.



3. Press the MODE/SET Key. The following display will flash for 1 second and then the inertia ratio will be saved.



4. Press the DATA/SHIFT Key for at least one second to return to the auxiliary function mode.



This completes the procedure for saving the results of online autotuning. When the SERVOPACK is turned ON again, the inertia ratio set in Pn103 will be used as the default value.

5.3.4 Parameters Related to Online Autotuning

This section provides information on a variety of parameters related to online autotuning.

■ Online Autotuning Method

The following parameter is used for setting the autotuning conditions.

Pn110.0	Online Autotuning Method	Factory Setting: 0	Speed Control, Position Control

Pn110.0 Setting	Contents
0	Autotuning is performed only when the system runs for the first time after the power is turned ON. After the load moment of inertia is calculated, the calculated data is not refreshed.
1	Autotuning is continuously performed (moment of inertia value calculation).
2	The online autotuning function is not used.

This parameter is factory-set to "0." If the load moment of inertia change is minimal or if the application makes few changes, there is no need to continue calculating the moment of inertia while the system is in operation. Instead, continue to use the value that was calculated when the system was first started up.

Set this parameter to "1" if the load moment of inertia always fluctuates due to the load conditions. Then the response characteristics can be kept stable by continuously refreshing the moment of inertia calculation data and reflecting them in the servo gain.

If the load moment of inertia fluctuation results within 200 ms, the moment of inertia calculation data may not be refreshed properly. If that happens, set Pn110.0 to "0" or "2."

Set Pn110.0 to "2" if autotuning is not available or if the online autotuning function is not used because the load moment of intertia is already known and the SERVOPACK is manually adjusted by setting the inertia ratio data in Pn103.

■ Speed Feedback Compensation Selection

Use the following parameter to enable or disable speed feedback compensation. Refer to *5.2.6 Speed Feedback Compensation*.

This parameter can be left as it is if online autotuning is performed. If this parameter is set manually, however, the setting is reflected to the operational setting made during online autotuning.

Pn110.1	Speed Feedback Compensation Selection	Factory Setting: 1	Speed Control, Position Control

Pn110.1 Setting	Contents
0	Enabled
1	Disabled

■ Friction Compensation Selection

Use the following parameter to enable or disable friction compensation to determine whether or not the friction of the servo system is to be taken into consideration for the calculation of load moment of inertia.

If this compensation function is enabled, select small or large friction compensation according to the extent of friction in order to ensure highly precise load moment of inertia calculation.

Pn110.2	Friction Compensation Selection	Factory Setting: 0	Speed Control, Position Control

Pn110.2 Setting	Contents
0	Friction compensation: Disabled
1	Friction compensation: Small
2	Friction compensation: Large



1. Do not set friction compensation for loads with low friction (10% rated torque/speed or less).
2. When the load moment of inertia is greater than the motor moment of inertia by more than 30 times, autotuning will be performed as if the load moment of inertia was only 30 times the motor moment of inertia.

5.4 Servo Gain Adjustments

This section describes information on the basic rules of gain adjustments in the SERVOPACK, adjustment methods in a variety of cases, and reference set values.

5.4.1 Servo Gain Parameters

The following parameters must be set properly for servo gain adjustments.

- Pn100: Speed loop gain
- Pn101: Speed loop integral time constant
- Pn102: Position loop gain
- Pn401: Torque reference filter time constant

If the SERVOPACK is used in the speed control mode with the analog voltage reference, the position loop is controlled by the host device. Therefore, position loop gain is adjusted through the host device.

If the host is not available for adjustments of position loop gain, set the speed reference input gain in parameter Pn300. If the set value is improper, the servomotor may not run at top speed.

5.4.2 Basic Rules of Gain Adjustment

The servo system consists of three feedback loops (i.e., position loop, speed loop, and current loop). The innermost loop must have the highest response speed and the middle loop must have higher response speed than the outermost. If this principle is not followed, it will result in vibration or poor responsiveness.

The SERVOPACK is designed to ensure that the current loop has good response performance. The user need only adjust position loop and speed loop gain.

The servo system block diagram consists of the position, speed, and current loops, as shown below.

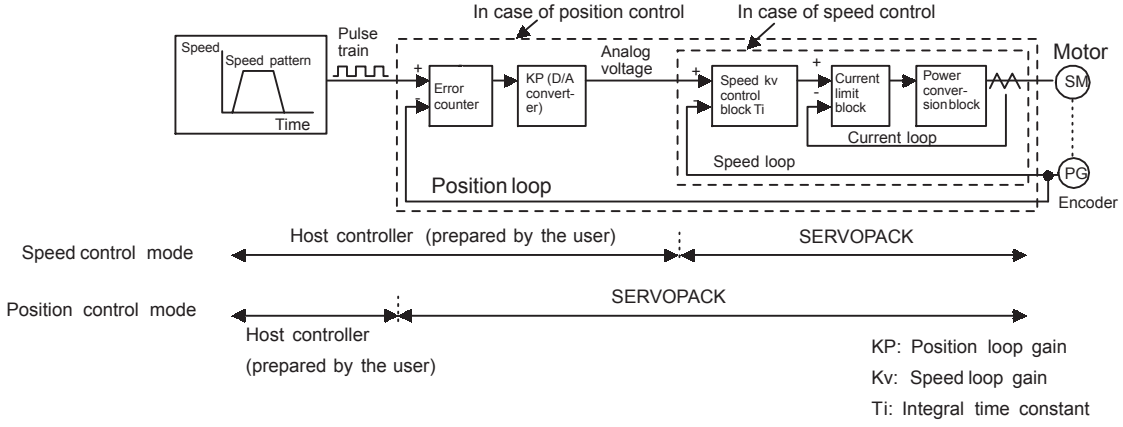


Fig. 5.1 Servo System Block Diagram

Generally speaking, the responsiveness of the position loop cannot be higher than that of the speed loop. Therefore, to increase the position loop gain, you must first increase the speed loop gain. If only the position loop gain is increased, oscillation will result in the speed reference and positioning time will increase, not decrease.

Position loop gain can be increased only to the point where oscillation begins in the mechanical system.

- If the position loop response is faster than the speed loop response, speed reference output from the position loop cannot follow the position loop response due to the slow speed loop response. Therefore, smooth linear acceleration or deceleration will not be possible and the position loop will keep accumulating errors, thus increasing the amount of speed reference output.

  As a result, the motor speed will be excessive and the position loop will try decreasing the amount of speed reference output. The speed loop responsiveness will be poor, however, and the motor will not be able to catch up with the speed reference. As a result, the speed reference will oscillate as shown in the following graph.

  If this happens, reduce the position loop gain or increase the speed loop gain to prevent the speed reference from oscillating.

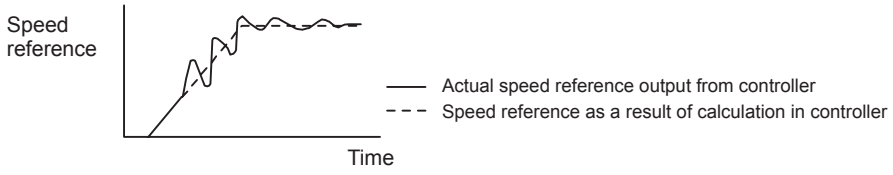


Fig. 5.2 Speed Reference with Position Loop Gain and Speed Loop Responsiveness Not Well-balanced

- The position loop gain must not exceed the natural frequency of the mechanical system. For example, if the mechanical system is an articulated robot, the rigidity of the machinery mechanism is very low because the mechanism incorporates a wave reduction gear and the natural frequency of the mechanical system is 10 to 20 Hz. In this case, the position loop gain can be set to 10 to 20 (1/s).

  If the mechanical system is a chip mounting machine, IC bonding machine, or high-precision machining tool, the natural frequency of the system is 70 Hz or more. Therefore, the position loop gain can be set to 70 (1/s) or higher.

- When high responsiveness is required, it is not only important to ensure the responsiveness of the servo system that is employed (the controller, SERVOPACK, motor, and encoder), but it is also necessary to ensure that the mechanical system have high rigidity.

5.4.3 Making Manual Adjustments

The autotuning function uses a gain adjustment algorithm with a comparatively large safety margin by considering a variety of mechanical systems to which the SERVOPACK is applied. Therefore, the SERVOPACK may not satisfy the response characteristics of some applications. The autotuning function is not available to machines with low rigidity or high fluctuation.

In such cases, observe the mechanical systems and make manual adjustments of parameters.

■ Speed Control

Required Parameters

The following parameters are used.

- Speed Loop Gain (Pn100)

  This parameter is used for determining the response speed of the speed loop. The response speed increases if the constant is set to a large value provided that the mechanical system does not vibrate. The value of speed loop gain is the same as the set value of Pn100 if the inertia ratio set in Pn103 is correct.

  Speed loop gain Kv = Set value of Pn100 (Hz)

  Set Pn103 to the following value.

$$\text{Pn103 set value} = \frac{\text{Motor axis conversion load moment of inertia } (J_L)}{\text{Servomotor rotor moment of inertia } (J_M)} \times 100\ (\%)$$



In the case of manual adjustments of parameters, the user must set the value of parameter Pn103. The inertia ratio can be obtained if the servo gain constant is written with parameter Fn007 after autotuning has been performed. For details regarding Fn007, refer to *5.3 Autotuning*.

- Speed Loop Integral Time Constant (Pn101)

  The speed loop has an integral element so that the speed loop can respond to minute inputs. This integral element delays the operation of the servo system, so a longer positioning setting time is required with slower response speed as the value of the time constant increases.

  If the load moment of inertia is large or the mechanical system is likely to vibrate, make sure that the speed loop integral time constant is large enough; otherwise the mechanical system will vibrate. The following formula is the standard.

$$Ti \geq 2.3 \times \frac{1}{2\pi \times Kv}$$

  Ti: Integral time constant [s]

  Kv: Speed loop gain (calculated from the above) [Hz]

- Torque Reference Filter Time Constant (Pn401)

  If the mechanical system uses ball screws, torsion resonance may result, in which case the oscillation noise will be a high-pitched tone. The oscillation may be stopped by increasing the time constant of the torque reference filter. Like the integral time constant, this filter causes a delay in the operation of the servo system. Therefore, this constant must not be set to an excessively large value.

- Speed Reference Input Gain (Pn300)

  Changing the speed reference input gain set in Pn300 is equivalent to changing the position loop gain. In other words, an increase in the speed reference input gain set in Pn300 is equivalent to a decrease in the position loop gain and vice versa. Use this parameter in the following cases.

  - When the host controller does not have a function for adjusting the position loop gain.

    (The host incorporates a D/A converter to change the number of bits but cannot make fine adjustments of position loop gain.)

  - When it is necessary to clamp the full range of the speed reference output of the host device to a specified rotation speed.

  In normal operation, the factory-set value can be used as it is.



If the SERVOPACK is used for speed control, the position loop gain set in Pn102 is enabled in zero-clamp mode only. In normal control operation, change the position loop gain through the host or change the speed reference input gain in Pn300 in the SERVOPACK. The position loop gain remains the same if the setting in Pn102 is changed.

Adjustment Procedure

1. Set the position loop gain to a comparatively low value in the host device. Then increase the speed loop gain set in Pn100 to within a range where there is no noise or oscillation resulting.

   If the position loop gain cannot be changed through the host device, increase the speed reference input gain set in Pn300 to a larger value.

2. Decrease the speed loop gain a little from the value set in step 1. Then increase the position loop gain through the host controller to within a range where there is no noise or oscillation resulting.

   As in step 1., decrease the set value of Pn300 if the position loop gain cannot be changed through the host device.

3. Set the speed loop integral time constant in Pn101 while observing the positioning setting time and the vibration of the mechanical system. If the constant is too large, positioning setting time will be long.

4. Set the torque reference filter to a small value in Pn401 if the mechanical system does not have shaft torsion resonance. If the mechanical system generates oscillation noise in a high-pitched tone, shaft torsion resonance may be occurring. In that case, set Pn401 to

a larger value.

5. Finally, progressively make fine adjustments to parameters such as the position loop gain, speed loop gain, and integral time constant to find the optimal points.

■ Position Control

Required Parameters

The following parameters are used.

- Speed Loop Gain (Pn100)

  This parameter is used for determining the response speed of the speed loop. The response speed increases if the constant is set to a large value provided that the mechanical system does not vibrate. The value of speed loop gain is the same as the set value of Pn100 if the inertia ratio set in Pn103 is correct.

  Speed loop gain Kv = Set value of Pn100 (Hz)

  Set Pn103 to the following value.

$$\text{Pn103 set value} = \frac{\text{Motor axis conversion load moment of inertia } (J_L)}{\text{Servomotor rotor moment of inertia } (J_M)} \times 100\ (\%)$$



In the case of manual adjustments of parameters, the user must set the value of parameter Pn103. The inertia ratio can be obtained if the servo gain constant is written with parameter Fn007 after autotuning has been performed. For details regarding Fn007, refer to *5.3 Autotuning*.

- Speed Loop Integral Time Constant (Pn101)

  The speed loop has an integral element so that the speed loop can respond to minute inputs. This integral element delays the operation of the servo system, so a longer positioning setting time is required with slower response speed as the value of the time constant increases.

  If the load moment of inertia is large or the mechanical system is likely to vibrate, make sure that the speed loop integral time constant is large enough; otherwise the mechanical system will vibrate. The following formula is the standard.

$$Ti \geq 2.3 \times \frac{1}{2\pi \times Kv}$$

  Ti: Integral time constant [s]

  Kv: Speed loop gain (calculated from the above) [Hz]

- Torque Reference Filter Time Constant (Pn401)

  If the mechanical system uses ball screws, torsion resonance may result, in which case the oscillation noise will be a high-pitched tone. The oscillation may be stopped by increasing the time constant of the torque reference filter. Like the integral time constant, this filter causes a delay in the operation of the servo system. Therefore, this constant must not be set to an excessively large value.

- Position Loop Gain (Pn102)

  The responsiveness of the servo system is determined by the position loop gain. The response speed increases if the position loop gain is set to a high value, so the time required for positioning will be shortened. In order to set the position loop gain to a high value, the rigidity and natural frequency of the mechanical system must be high.

  The responsiveness of the whole servo system may become unstable if only the position loop gain is increased, because the speed reference as output from the position loop is likely to become unstable. Increase the speed loop gain while observing the response.

Adjustment Procedure

1. Set the position loop gain to a comparatively low value. Then increase the speed loop gain set in Pn100 to within a range where there is no noise or oscillation resulting.
2. Decrease the speed loop gain a little from the value set in step 1. Then increase the position loop gain to within a range where there is no overshooting or oscillation resulting.
3. Set the speed loop integral time constant in Pn101 while observing the positioning setting time and the vibration of the mechanical system. If the constant is too large, positioning setting time will be long.
4. Set the torque reference filter to a small value in Pn401 if the mechanical system does not have shaft torsion resonance. If the mechanical system generates oscillation noise in a high-pitched tone, shaft torsion resonance may be resulting. In that case, set Pn401 to a larger value.
5. Finally, progressively make fine adjustments to parameters such as the position loop gain, speed loop gain, and integral time constant to find the optimal points.

■ Function to Improve Response Characteristics

The mode switch, feed-forward, and bias functions can improve the response characteristics of the servo system only if they are used properly. If they are used improperly, they will worsen the response characteristics. Refer to the following instructions and make adjustments to these functions while observing the change in the actual response characteristics.

Mode Switch

Use the mode switch function in order to improve the saturation characteristics of the servo system if there is torque reference saturation at the time of acceleration or deceleration of the servomotor. If an appropriate value is set with this function, the speed loop in PI (proportional and integral) control is switched over to P (proportional) control when the operation speed exceeds the set value.

Feed-forward Functions

The responsiveness is increased by using one of the feed-forward functions. A feed-forward function is not so effective, however, if the position loop gain is set to a high enough value. Adjust the feed-forward set value of Pn109 as described below.

1. Adjust the speed loop and position loop according to the method described on *page 5-32*.
2. Gradually increase the set value of Pn109 so that the positioning completion signal (/COIN) will be output quickly.

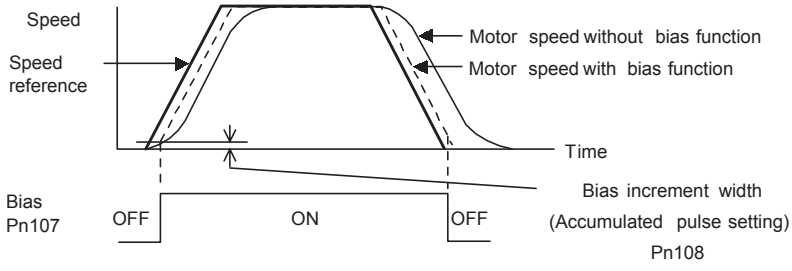
   Make sure that the positioning completion signal (/COIN) is not broken (i.e., turned ON and OFF repeatedly within a short period) and that speed overshooting does not result. These are likely to occur if the feed-forward value is too high.

   It is possible to add a primary delay filter (to be set in Pn10A) to the feed-forward function. The primary delay filter may prevent the positioning completion signal from breaking and the system speed from overshooting.

Bias Function

This function adds the bias set in Pn107 to the output (i.e., speed reference) of the error counter if the number of accumulated pulses of the error counter exceeds the bias increment width set in Pn108 and stops adding the bias if the output is within the bias increment width. As a result, the number of accumulated pulses of the error counter decreases and the time required for positioning can be shortened.

If the bias set value of Pn107 is too large, the motor rotation will be unstable. The optimum bias value varies with the load, gain, and bias increment width. Make bias adjustments while observing the response. When not using this function, set Pn107 to 0.



5.4.4 Gain Setting Reference Values

This section describes information on servo gain values as reference for making gain adjustments.

Refer to the following for standards for gain adjustments according to the rigidity of the mechanical system. Refer to these values and use the previously mentioned methods to make gain adjustments. These values are for reference only and do not mean that the mechanical system has good response characteristics or is free from oscillation in the specified ranges.

Observe the response by monitoring the response waveform and make the optimum gain adjustments. If the rigidity of the machinery is high, further gain increments exceeding the described ranges are possible.

■ Machines with High Rigidity

These machines are directly connected to ball screws.

Example: Chip mounting machine, bonding machine, high-precision machine tool

Position Loop Gain (Pn102) [1/s]	Speed Loop Gain (Pn100) [Hz]	Speed Loop Integral Time Constant (Pn101) [ms]
50 to 70	50 to 70	5 to 20

■ Machines with Medium Rigidity

These machines are driven by ball screws through speed reducers or long-length machines directly driven by screws.

Examples: General machining tool, transverse robot, and conveyor

Position Loop Gain (Pn102) [1/s]	Speed Loop Gain (Pn100) [Hz]	Speed Loop Integral Time Constant (Pn101) [ms]
30 to 50	30 to 50	10 to 40

■ Machines with Low Rigidity

These machines are driven by timing belts or chains or machines with wave reduction gears.

Example: Conveyor and articulated robot

Position Loop Gain (Pn102) [1/s]	Speed Loop Gain (Pn100) [Hz]	Speed Loop Integral Time Constant (Pn101) [ms]
10 to 20	10 to 20	50 to 120

IMPORTANT

If the inertia ratio is a little larger than 10 times its rated value, start gain adjustments with the position and speed loop gains slightly below the above corresponding ranges and the speed loop integral constant slightly exceeding the above corresponding range. If the inertia ratio is much larger, start the gain adjustments with the position and speed loop gains set to the smallest values and the speed loop integral constant to the largest value in the above corresponding ranges.

In speed control operation, the position loop gain is set through the host device. If that is not possible, adjust the position loop gain with the speed reference input gain in Pn300 in the SERVOPACK. In speed control operation, the position loop gain set in Pn102 is enabled in zero-clamp mode only. Position loop gain K_P is obtainable from the following.

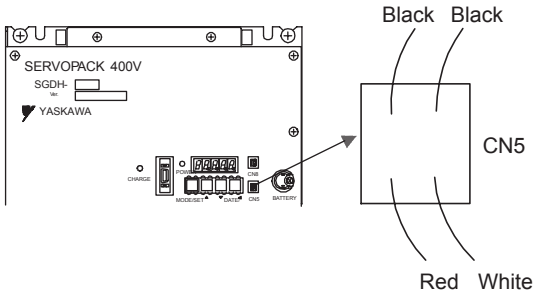
$$Kp \geq \frac{Vs}{\varepsilon}$$

- Kp (1/S): Position Loop Gain
- Vs (PPS): Constant Speed Reference
- ε (Pulse): Constant error: The number of accumulated pulses of the error counter at the above constant speed.

5.5 Analog Monitor

The analog monitor can observe a variety of signals through analog voltages.

Analog monitor signals must be observed through the CN5 connector using DE9404559 dedicated cable.



Cable Color	Signal Name	Description
White	Analog monitor 1	Torque reference: 1 V/100% rated torque
Red	Analog monitor 2	Motor speed: 1 V/1000 min^{-1}
Black (two wires)	GND (0 V)	-

Analog monitor signals can be selected with parameters Pn003.0 and Pn003.1.

Pn003.0	Analog Monitor 1	Factory Setting: 2	Speed/Torque Control, Position Control
Pn003.1	Analog Monitor 2	Factory Setting: 0	Speed/Torque Control, Position Control

The following monitor signals can be observed.

Setting in Pn003.0 and Pn003.1	Contents	
	Monitor signal	Observation gain
0	Motor speed	1 V/1000 min^{-1}
1	Speed reference	1 V/1000 min^{-1}
2	Torque reference	1 V/100% rated torque
3	Position error	0.05 V/1 reference unit
4	Position error	0.05 V/100 reference units
5	Reference pulse speed frequency (converted to min^{-1})	1 V/1000 min^{-1}
6	Motor speed	1 V/250 min^{-1}
7	Motor speed	1 V/125 min^{-1}
8 to E	Reserved monitor signal	-

Note: In the case of torque control or speed control, the monitor signal of position error monitor signal is indefinite.



The output voltage of the analog monitor is ±8 V max. The output voltage will be reversed if ±8 V is exceeded.

6

Using the Digital Operator

This chapter describes the basic operation of the Digital Operator and the features it offers. All constant settings and motor operations can be executed by simple, convenient operations. Operate the Digital Operator as you read through this chapter.

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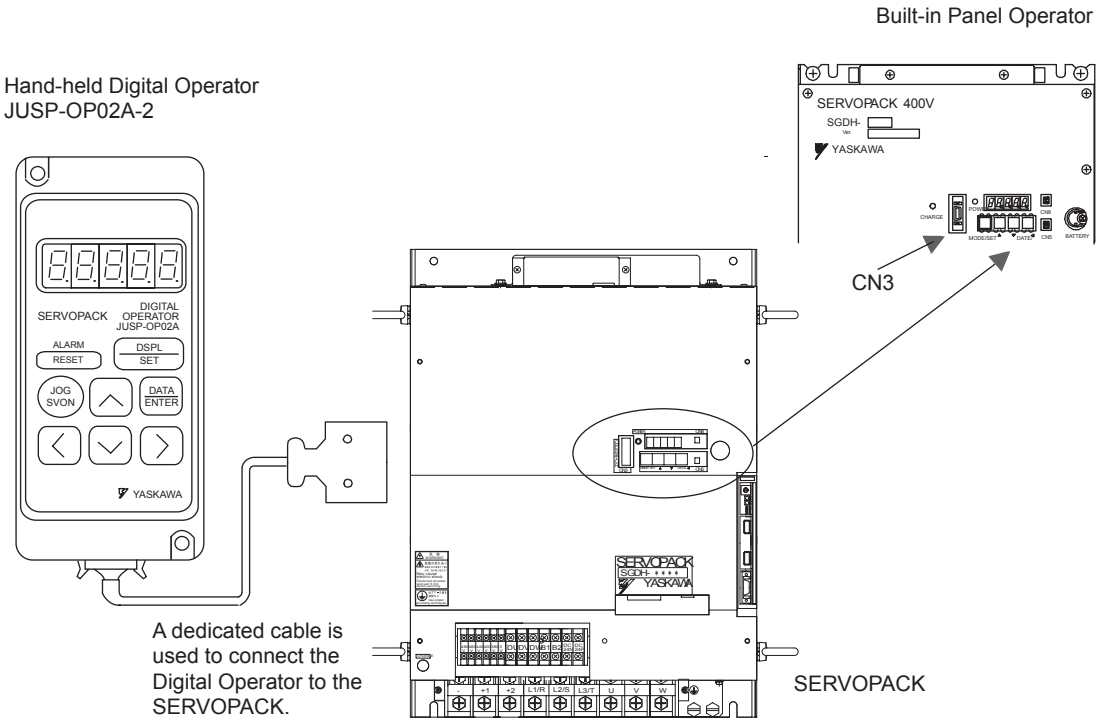
6.1 Basic Operation

This section provides information on the basic operation of the Digital Operator for setting operating conditions.

6.1.1 Connecting the Digital Operator

There are two types of Digital Operator. One is a built-in operator incorporating a panel indicator and switches located on the front panel of the SERVOPACK. This type of Digital Operator is also called a Panel Operator. The other one is a Hand-held Operator (i.e., the JUSP-OP02A-2 Digital Operator), which can be connected to the SERVOPACK through connector CN3 of the SERVOPACK.

Refer to the following illustrations to connect the Hand-held Digital Operator to the SERVOPACK. There is no need to turn OFF the SERVOPACK to connect this Hand-held Operator to the SERVOPACK.



IMPORTANT

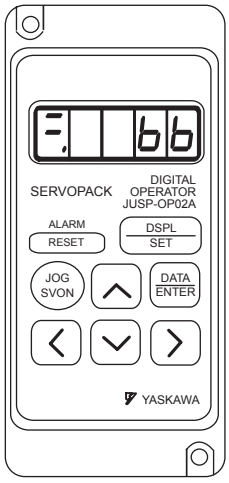
If the Hand-held Digital Operator is connected to the SERVOPACK, the built-in Panel Operator does not display anything.

6.1.2 Functions

The Digital Operator can be used parameter settings, operating references, and status displays.

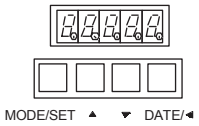
This section provides information on the keys and their functions available from the initial displays.

Hand-held Digital Operator



Key	Name		Function
ALARM RESET	RESET Key		Press this key to reset the servo alarm.
DSPL SET	DSPL/SET Key		• Press this key to select the status display mode, auxiliary function mode, parameter setting mode, or monitor mode. • This key is used for data selection in parameter setting mode.
DATA ENTER	DATA/ENTER Key		Press this key to set each parameter or display the set value of each parameter.
∧	Value Change/JOG Key	Up Cursor Key	Press this key to increase the set value. This key is used as a forward start key in JOG operation.
∨		Down Cursor Key	Press this key to decrease the set value. This key is used as a reverse start key in JOG operation.
>	Digit Select Key	Right Cursor Key	• Press this key to select the digit to be changed. The selected digit flashes. • Press the Right Cursor Key to shift to the next digit on the right. • Press the Left Cursor Key to shift to the next digit on the left.
<		Left Cursor Key	
JOG SVON	SVON Key		Press this key to perform the JOG operation with the Digital Operator.

Built-in
Panel Operator



Key	Name	Function
▲	Up Cursor Key	• Press this key to set parameters or display the set values of parameters. • Press the Up Cursor Key to increase the set value. • Press the Down Cursor Key to decrease the set value. • Press the Up and Down Cursor Keys together to reset a servo alarm.
▼	Down Cursor Key	
MODE/SET	MODE/SET Key	Press this key to select the status display mode, auxiliary function mode, parameter setting mode, or monitor mode.
DATA/◄	DATA/SHIFT Key	• Press this key to set each parameter or display the set value of each parameter. • This key is used for selecting the editing (flashing) digit or data setting.

6.1.3 Resetting Servo Alarms

Servo alarms can be reset using the Digital Operator.

■ Using the Hand-held Digital Operator

Press the RESET Key in status display mode.

■ Using the Built-in Panel Operator

Press the Up and Down Cursor Keys together in status display mode.

The alarm can be reset with CN1-44, or /ALM-RST signal input. Refer to *4.5.1 Using Servo Alarm and Alarm Code Outputs*.

The servo alarm need not be reset if the control power supply is turned OFF.

IMPORTANT

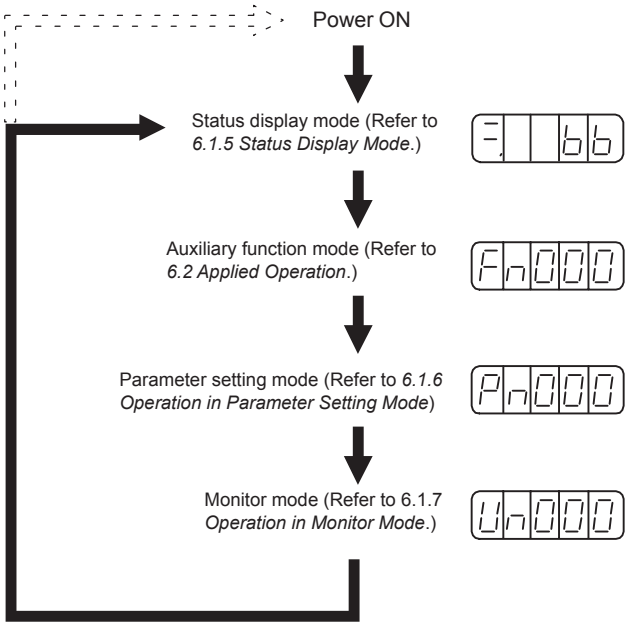
If an alarm is ON, reset the alarm after eliminating the cause of the alarm. Refer to *8.2 Troubleshooting*.

6.1.4 Basic Mode Selection

The basic mode selection of the Digital Operator is used for indicating the status of the SERVOPACK in operation and setting a variety of parameters and operation references.

The status display, auxiliary function, parameter setting, and monitor modes are the basic modes. As shown below, the mode is selected in the following order by pressing the key.

Hand-held Digital Operator	Panel Operator
Press the DSPL/SET Key. The basic mode changes.	Press the MODE/SET Key. The basic mode changes.



6

6.1.5 Status Display Mode

In status display mode, bit data and codes are displayed to indicate the status of the SERVOPACK.

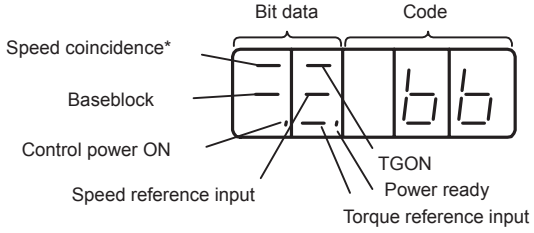
■ Selecting Status Display Mode

The Digital Operator goes into status display mode when the Digital Operation is turned ON.

■ Items Indicated in Status Display Mode

The displayed contents in the status display mode are different for the speed and torque control mode and the position control mode.

Speed and Torque Control Mode



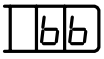
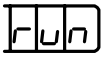
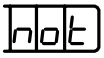
* This indicator is always lit when the SERVOPACK is in torque control mode.

The following tables list bit data items, codes, and their meanings.

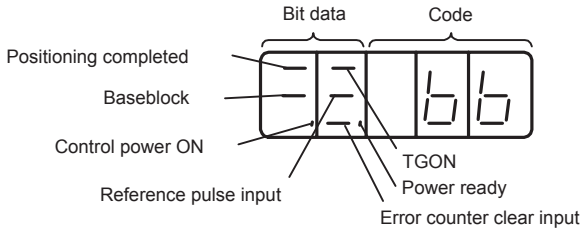
Table 6.1 Bit Data and Meanings in Speed and Torque Control Mode

Bit Data	Meaning
Control Power ON	Lit when SERVOPACK control power is ON.
Baseblock	Lit for baseblock. Not lit when servo is ON.
Speed Coincidence	Lit when the difference between the motor speed and reference speed is the same as or less than the value set. Preset value: Set in Pn503 (10 min^{-1} is standard setting)
/TGON	Lit if motor speed exceeds preset value. Not lit if motor speed is below preset value. Preset value: Set in Pn502 (20 min^{-1} is standard setting)
Speed Reference Input	Lit if input speed reference exceeds preset value. Not lit if input speed reference is below preset value. Preset value: Set in Pn502 (20 min^{-1} is standard setting)
Torque Reference Input	Lit if input torque reference exceeds preset value. Not lit if input torque reference is below preset value. Preset value: 10% rated torque is standard setting.
Power Ready	Lit when main power supply circuit is normal. Not lit when power is OFF.

Table 6.2 Codes and Meanings in Speed and Torque Control Mode

Code	Meaning
	Baseblock Servo OFF (motor power OFF)
	Run Servo ON (motor power ON)
	Forward Run Prohibited CN1-42 (P-OT) is OFF. Refer to *4.1.2 Setting the Overtravel Limit Function*.
	Reverse Run Prohibited CN1-43 (N-OT) is OFF. Refer to *4.1.2 Setting the Overtravel Limit Function*.
  :	Alarm Status Displays the alarm number. Refer to *8.2 Troubleshooting*.

Position Control Mode



The following tables list bit data items, codes, and their meanings.

Table 6.3 Bit Data and Meanings in Position Control Mode

Bit Data	Meaning
Control Power ON	Lit when SERVOPACK control power is ON.
Baseblock	Lit for baseblock. Not lit when servo is ON.
Positioning Completed	Lit if error between position reference and actual motor position is below preset value. Not lit if error between position reference and actual motor position exceeds preset value. Preset value: Set in Pn500 (7 pulses are standard setting)
/TGON	Lit if motor speed exceeds preset value. Not lit if motor speed is below preset value. Preset value: Set in Pn502 (20 min^{-1} is standard setting)
Reference Pulse Input	Lit if reference pulse is input. Not lit if no reference pulse is input.
Error Counter Clear Input	Lit when error counter clear signal is input. Not lit when error counter clear signal is not input.
Power Ready	Lit when main power supply circuit is normal. Not lit when power is OFF.

Table 6.4 Codes and Meanings in Position Control Mode

Code	Meaning
bb	Baseblock Servo OFF (motor power OFF)
run	Run Servo ON (motor power ON)
Pot	Forward Run Prohibited CN1-42 (P-OT) is OFF. Refer to *4.1.2 Setting the Overtravel Limit Function*.
not	Reverse Run Prohibited CN1-43 (N-OT) is OFF. Refer to *4.1.2 Setting the Overtravel Limit Function*.
A.02	Alarm Status Displays the alarm number. Refer to *8.2 Troubleshooting*.
A.03 :	

6.1.6 Operation in Parameter Setting Mode

Functions can be selected or adjusted by setting parameters. There are two types of parameters. One type requires value setting and the other requires function selection. These two types use different setting methods.

With value setting, a parameter is set to a value within the specified range of the parameter. With function selection, the functions allocated to each digit of the seven-segment LED panel indicator (five digits) can be selected. Refer to *Appendix A List of Parameters*.

■ Changing Parameter Settings

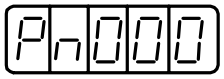
The parameter settings can be used for changing parameter data. Check the permitted range of the parameters in *Appendix A List of Parameters*, before changing the data.

The example below shows how to change parameter Pn507 from 100 to 85.



Using the Hand-held Digital Operator

1. Press DSPL/SET Key to select the parameter setting mode.

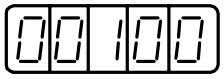


2. Select the parameter number to be set. (Pn507 is selected in this example.)

   Press the Left or Right Cursor Key to select the digit. The selected digit will flash.

   Press the Up or Down Cursor Key to change the value.

3. Press the DATA/ENTER Key to display the current data for the parameter selected at step 2.



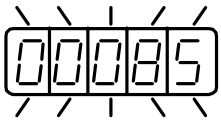
4. Change to the required data.

   Press the Left or Right Cursor Key to select the digit. The selected digit will flash.

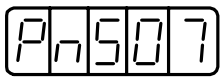
   Press the Up or Down Cursor Key to change the value.

   Continue pressing the key until “00085” is displayed.

5. Press the DATA/ENTER Key to store the data. The display will flash.

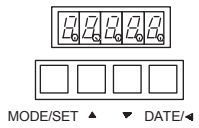


6. Press the DATA/ENTER Key once more to return to the parameter number display.



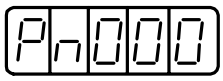
   This has changed the setting of the parameter Pn507 from 100 to 85.

Repeat steps 2. to 6. as often as required.

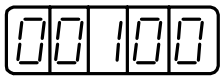


Using the Panel Operator

1. Press the MODE/SET Key to select the parameter setting mode.

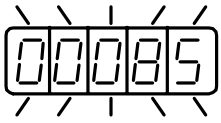


2. Press the Up or Down Cursor Key to select the parameter number to set. (Pn507 is selected in this example.)
3. Press the DATA/SHIFT Key for a minimum of one second to display the current data for the parameter selected at step2.

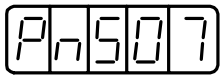


4. Press the Up or Down Cursor Key to change to the desired value of "00085."

   As you keep pressing the Up or Down Cursor Key, and the display changes faster.
5. Press the DATA/SHIFT Key for a minimum of one second to save the data. The display will flash.



6. Press the DATA/SHIFT Key once more for a minimum of one second to return to the parameter number display.



This has changed the setting of the parameter Pn507 from 100 to 85.

Repeat steps 2. to 6. as often as required.

IMPORTANT

Press the DATA/SHIFT Key for a maximum of one second to shift to a higher (left) digit.

INFO

Parameter numbers that are not defined are skipped during Operator operations.

■ Function Selection Parameters

Types of Function Selection Parameters

The following table shows the parameters used for selecting SERVOPACK functions.

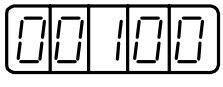
Category	Parameter No.	Name	Factory Setting	Remarks
Function Selection Constants	Pn000	Function Selection Basic Switches	0000	(See 1.)
	Pn001	Function Selection Application Switches 1	0000	(See 1.)
	Pn002	Function Selection Application Switches 2	0000	(See 1.)
	Pn003	Function Selection Application Switches 3	0002	
Gain-related Constants	Pn10B	Gain-related Application Switches	0000	(See 2.)
	Pn110	Online Autotuning Switches	0010	(See 2.)
Position Control-related Constant	Pn200	Position Control Reference Selection Switches	0000	(See 1.)
Sequence-related Constants	Pn50A	Input Signal Selections 1	2100	(See 1.)
	Pn50B	Input Signal Selections 2	6543	(See 1.)
	Pn50C	Input Signal Selections 3	8888	(See 1.)
	Pn50D	Input Signal Selections 4	8888	(See 1.)
	Pn50E	Output Signal Selections 1	3211	(See 1.)
	Pn50F	Output Signal Selections 2	0000	(See 1.)
	Pn510	Output Signal Selections 3	0000	(See 1.)

6

IMPORTANT

1. After changing these parameters, turn OFF the main circuit and control power supplies and then turn them ON again to enable the new settings.
2. Pn10B.1 and Pn110.0 require the power to be reset as mentioned above.

Parameter settings are displayed in two patterns as shown below.

Parameters for function selection		Hexadecimal display for each digit
Parameters for constant settings		Decimal display in five digits

Since each digit in the function selection parameters has a significant meaning, the value can only be changed for each individual digit. Each digit displays a value within its own setting range.

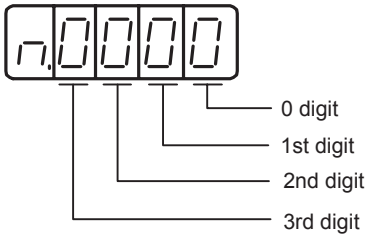
Definition of Display for Function Selection Parameters

Each digit of the function selection parameters has a unique meaning.

For example, the rightmost digit of parameter Pn000 is expressed as “Pn000.0”.

IMPORTANT

Each digit of the function selection parameters is defined as shown below. The parameter display example shows how parameters are displayed in digits for set values.



How to Display Parameters

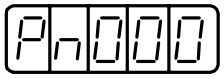
Pn000.0	:	Indicates the value for the 0 digit of parameter Pn000
Pn000.1	:	Indicates the value for the 1st digit of parameter Pn000
Pn000.2	:	Indicates the value for the 2nd digit of parameter Pn000
Pn000.3	:	Indicates the value for the 3rd digit of parameter Pn000

■ Changing Function Selection Parameter Settings



Using the Hand-held Digital Operator

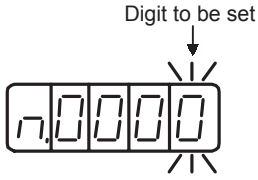
1. Press DSPL/SET Key to select the parameter setting mode.



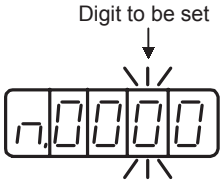
2. Select the parameter number to be set.

   Press the Left or Right Cursor Key to select the digit. The selected digit will flash. Press the Up or Down Key to change the value. (Pn000 is selected in this example.)

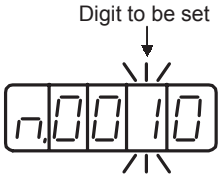
3. Press the DATA/ENTER Key to display the current data of the parameter selected in the above step 2.



4. Press the Left or Right Cursor Key to select the digit.

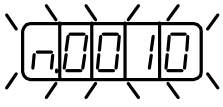


5. Press the Up or Down Cursor Key to select the value defined as a function setting for the selected digit.

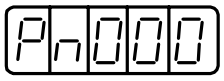


   Repeat the above steps 4. and 5. for changing the data as required.

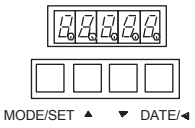
6. Press the DATA/ENTER Key to save the data. The display will flash.



7. Press the DATA/ENTER Key once more to return to the parameter number display.

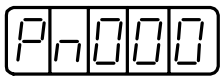


   This has changed the 1st digit of parameter Pn000 to “1.”

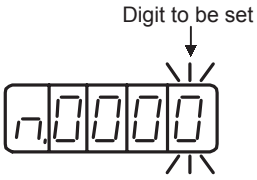


Using the Panel Operator

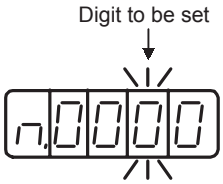
1. Press the MODE/SET Key to select the parameter setting mode.



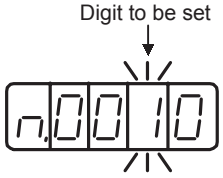
2. Press the Up or Down Cursor Key to select the parameter number to set. (Pn000 is selected in this example.)
3. Press the DATA/SHIFT Key for a minimum of one second to display the current data for the selected parameter.



4. Press the DATA/SHIFT Key to select the digit to be set.

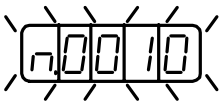


5. Press the Up or Down Cursor Key to select the value defined as a function setting for the selected digit.

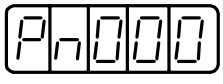


Repeat the above steps 4. and 5. for changing the data as required.

6. Press the DATA/SHIFT Key for a minimum of one second to save the data. The display will flash.



7. Press the DATA/SHIFT Key once more for a minimum of one second to return to the parameter number display.



This has changed the 1st digit of parameter Pn000 to “1.”

6.1.7 Operation in Monitor Mode

The monitor mode can be used for monitoring the reference values, I/O signal status, and SERVOPACK internal status.

The monitor mode can be set during motor operation.

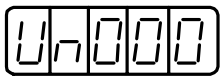
■ Using the Monitor Mode

The example below shows how to display 1500, the contents of monitor number Un000 when the servomotor rotates at 1500 min^{-1}.

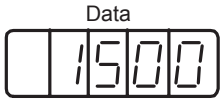


With the Hand-held Digital Operator

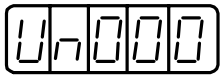
1. Press the DSPL/SET Key to select the monitor mode.



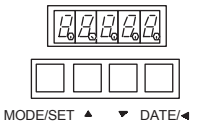
2. Press the Up or Down Cursor Key to select the monitor number to be displayed.
3. Press the DATA/ENTER Key to display the data for the monitor number selected in the above step 2.



4. Press the DATA/ENTER Key once more to return to the monitor number display.



This completes the example procedure for displaying 1500, the contents of monitor number Un000.

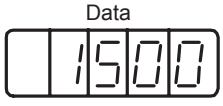


Using the Panel Operator

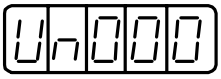
1. Press the MODE/SET Key to select the monitor mode.



2. Press the Up or Down Cursor Key to select the monitor number to be displayed.
3. Press the DATA/SHIFT Key for a minimum of one second to display the data for the monitor number selected in the above step2.



4. Press the DATA/SHIFT Key once more for a minimum of one second to return to the monitor number display.



This completes the example procedure for displaying 1500, the contents of monitor number Un000.

■ Contents of Monitor Mode Display

The following table shows contents of the monitor mode display.

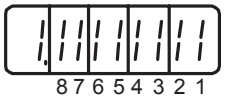
Monitor Number	Monitor Display	Unit	Remarks
Un000	Actual motor speed	min^{-1}	
Un001	Input speed reference	min^{-1}	*3
Un002	Internal torque reference	%	Value for rated torque
Un003	Rotation angle 1	pulses	Number of pulses from the origin
Un004	Rotation angle 2	deg	Angle (electrical angle) from the origin
Un005	Input signal monitor	-	*1
Un006	Output signal monitor	-	*1
Un007	Input reference pulse speed	min^{-1}	*4
Un008	Error counter value	reference units	Positional error*4
Un009	Accumulated load rate	%	Value for the rated torque as 100%. Displays effective torque in 10-s cycle.
Un00A	Regenerative load rate	%	Value for the processable regenerative power as 100%. Displays regenerative consumption power in 10-s cycle.
Un00B	Power consumed by DB resistance	%	Value for the processable power when dynamic brake is applied as 100%. Displays DB power consumption in 10-s cycle.
Un00C	Input reference pulse counter	-	In hexadecimal*2, *4
Un00D	Feedback pulse counter	-	In hexadecimal

* 1. Refer to *Sequence I/O Signal Monitor Display* on the next page.
* 2. Refer to *Reference Pulse/Feedback Pulse Counter Monitor Display*.
* 3. Displayed only in speed control mode.
* 4. Displayed only in position control mode.

■ Sequence I/O Signal Monitor Display

The following section describes the monitor display for sequence I/O signals.

Input Signal Monitor Display



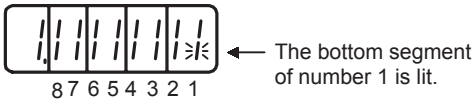
LED Number	Input Terminal Name	Factory Setting
1	SI0 (CN1-40)	/S-ON
2	SI1 (CN1-41)	/P-CON
3	SI2 (CN1-42)	P-OT
4	SI3 (CN1-43)	N-OT
5	SI4 (CN1-44)	/ALM -RST
6	SI5 (CN1-45)	/P-CL
7	SI6 (CN1-46)	/N-CL
8	(CN1-4)	SEN

Note: Refer to *4.3.3 Input Circuit Signal Allocation* for details on input terminals.

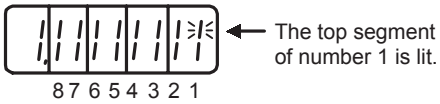
Input signals are allocated as shown above and displayed on the panel display of the SERVOPACK or the Digital Operator. They are indicated by ON/OFF display of seven-segment LEDs in top and bottom rows. These segments turn ON depending on the input signals (ON for “L” level and OFF for “H” level).

◀ EXAMPLE ▶

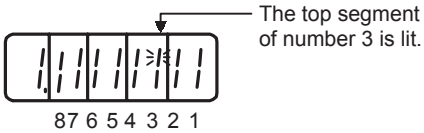
- When /S-ON signal is ON (Servo ON at “L” signal)



- When /S-ON signal is OFF



- When P-OT signal operates (Operates at “H” signal)



Output Signal Monitor Display



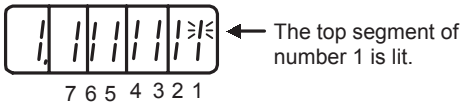
LED Number	Output Terminal Name	Factory Setting
1	(CN1-31, -32)	ALM
2	SO1 (CN1-25, -26)	/COIN or /V-CMP
3	SO2 (CN1-27, -28)	/TGON
4	SO3 (CN1-29, -30)	/S-RDY
5	(CN1-37)	AL01
6	(CN1-38)	AL02
7	(CN1-39)	AL03

Note: Refer to *4.3.4 Output Circuit Signal Allocation* for details on output terminals.

Output signals are allocated as shown above and displayed on the panel display of the SERVOPACK or the Digital Operator. They are indicated by ON/OFF display of seven-segment LEDs in top and bottom rows. These segments turn ON depending on the output signals (ON for “L” level and OFF for “H” level).

◀ EXAMPLE ▶

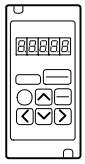
- When ALM signal operates (alarm at “H”)



■ Reference Pulse/Feedback Pulse Counter Monitor Display

The monitor display of reference pulse counter and feedback pulse counter is expressed in 32-bit hexadecimal.

The display procedure is as follows:



Using the Hand-held Digital Operator

1. Press the DSPL/SET Key to select the monitor mode.
2. Press the Up or Down Cursor Key to select "Un00C" or "Un00D."
3. Press the DATA/ENTER Key to display the data for the monitor number selected in the above step 2.

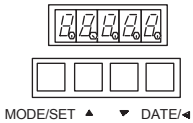


4. Press the Up or Down Cursor Key to alternately display the leftmost 16-bit data and rightmost 16-bit data.



Leftmost 16-bit Data　　Rightmost 16-bit Data

5. Press both the Up and Down Cursor Keys simultaneously to clear the 32-bit counter data.
6. Press the DATA/ENTER Key once more to return to the monitor number display.



Using the Panel Operator

1. Press the MODE/SET Key to select the monitor mode.
2. Press the Up or Down Cursor Key to select "Un00C" or "Un00D."
3. Press the DATA/SHIFT Key for a minimum of one second to display the data for the monitor number selected in the above step 2.



4. Press the Up or Down Cursor Key to alternately display the leftmost 16-bit data and rightmost 16-bit data.



Leftmost 16-bit Data　　Rightmost 16-bit Data

5. Press both the Up and Down Cursor Keys simultaneously to clear the 32-bit counter data.
6. Press the DATA/SHIFT Key once more for a minimum of one second to return to the monitor number display.

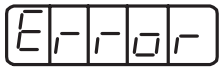
6.2 Applied Operation

This section describes how to apply the basic operations using the Digital Operator to run and adjust the motor. Read the basic operations described in *6.1 Basic Operation* before proceeding to this section.

Parameters for applied operation can be set in the auxiliary function mode. The following table shows the parameters in the auxiliary function mode.

Parameter No.	Function	Remarks
Fn000	Alarm traceback data display	
Fn001	Rigidity setting during online autotuning	(See note.)
Fn002	JOG mode operation	
Fn003	Zero-point search mode	
Fn004	(Reserved constant)	
Fn005	Parameter settings initialization	(See note.)
Fn006	Alarm traceback data clear	(See note.)
Fn007	Writing inertia ratio data obtained from online autotuning to EEPROM	(See note.)
Fn008	Absolute encoder multiturn reset and encoder alarm reset	(See note.)
Fn009	Automatic tuning of analog (speed, torque) reference offset	(See note.)
Fn00A	Manual adjustment of speed reference offset	(See note.)
Fn00B	Manual adjustment of torque reference offset	(See note.)
Fn00C	Manual zero-adjustment of analog monitor output	(See note.)
Fn00D	Manual gain-adjustment of analog monitor output	(See note.)
Fn00E	Automatic offset-adjustment of motor current detection signal	(See note.)
Fn00F	Manual offset-adjustment of motor current detection signal	(See note.)
Fn010	Password setting (protects from parameter changes)	
Fn011	Motor models display	
Fn012	SERVOPACK software version display	
Fn013	Multiturn limit value setting change when a Multiturn Limit Disagreement alarm occurs	(See note.)
Fn014	Clear of option unit detection results	

Note: These parameters and those indicated as Pn□□□ are displayed as shown below if their passwords are set (Fn010). These parameters cannot be changed.



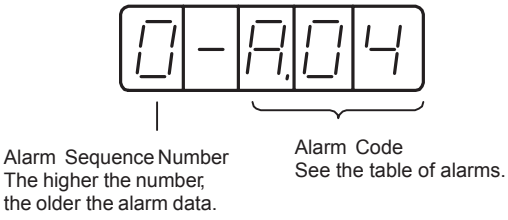
Flashing for one second

6.2.1 Operation in Alarm Traceback Mode

The alarm traceback mode can display up to ten alarms that have occurred, thus making it possible to check what kind of alarms have been generated.

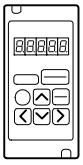
The alarm traceback data is not cleared on alarm reset. The alarm traceback data is not cleared when the SERVOPACK power is turned OFF. This does not adversely affect operation.

The data can be cleared using the special "clear alarm traceback mode." Refer to *6.2.5 Clearing Alarm Traceback Data*.



■ Checking Alarms

Follow the procedure below to determine which alarms have been generated.



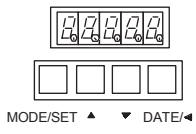
Using the Hand-held Digital Operator

1. Press the DSPL/SET Key to select the "Displaying alarm traceback data (Fn000)" in the auxiliary function mode.



2. Press the DATA/ENTER Key and the alarm traceback data will be displayed.
3. Press the Up or Down Cursor Key to scroll the alarm sequence numbers up or down and display information on previous alarms.

The higher the left-hand digit (alarm sequence number), the older the alarm data.



Using the Panel Operator

1. Press the MODE/SET Key to select the "Displaying alarm traceback data (Fn000)" in the auxiliary function mode.



2. Press the DATA/SHIFT Key for a minimum of one second to display the alarm traceback data.
3. Press the Up or Down Cursor Key to scroll the alarm sequence numbers up or down.

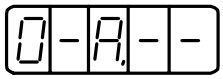
The higher the left-hand digit (alarm sequence number), the older the alarm data.

For descriptions of each alarm code, refer to *8.2 Troubleshooting*.

The following are Operator-related alarms which are not recorded in the traceback data.

CPF00	Digital Operator transmission error 1
CPF01	Digital Operator transmission error 2

The display will be as shown below while no alarm is detected.



INFO Alarm traceback data will not be updated when the same alarm occurs repetitively.

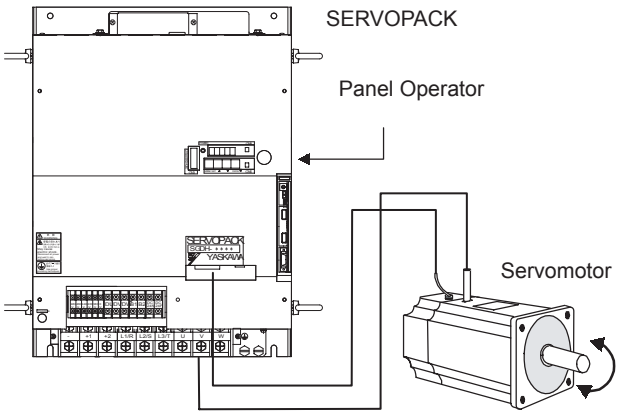
6.2.2 Controlling Operation Through the Digital Operator

⚠ CAUTION

- Forward run prohibited (P-OT) and reverse run prohibited (N-OT) signals are not effective during jog operations using parameter Fn002.

Controlling operation through the Digital Operator allows the SERVOPACK to run the motor. This allows rapid checking of motor's rotation direction and speed setting during machine set-up and testing, without the trouble of connecting a host controller.

For motor speed setting procedure, refer to *6.1.6 Operation in Parameter Setting Mode* and *4.3.2 JOG Speed*.



INFO

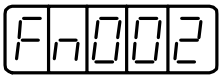
The following conditions must be satisfied to perform JOG mode operation.

1. If the Servo-ON input signal (/S-ON) is ON, turn it OFF.
2. Release the Servo-ON signal mask if parameter Pn50A.1 is set to 7 and the Servo has been set to always be ON.

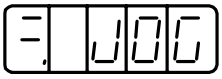
Operation procedure using the Digital Operator is described on the following pages.

Using the Hand-held Digital Operator

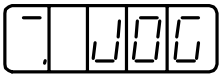
1. Press the DSPL/SET Key to select Fn002 in the auxiliary function mode.



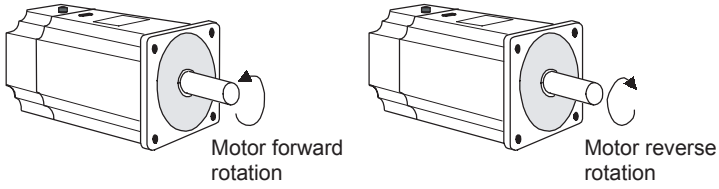
2. Press the DATA/ENTER Key to select the Digital Operator operation mode. Operation is now possible using the Digital Operator.



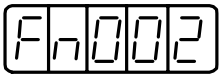
3. Press the SVON Key to set to the servo ON state (with motor power turned ON).



4. Press the Up Cursor Key or Down Cursor Key to operate the motor. The motor keeps operating while the key is pressed.

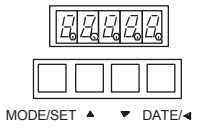


5. Press the DSPL/SET Key and the display will revert to Fn002. This sets to the servo OFF state (with motor power turned OFF). Alternatively, press the SVON Key to set to the servo OFF state.



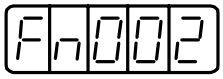
This disables operation under Digital Operator control.

6

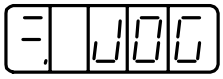


Using the Panel Operator

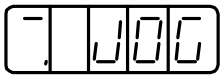
1. Press the MODE/SET Key to select Fn002 in the auxiliary function mode.



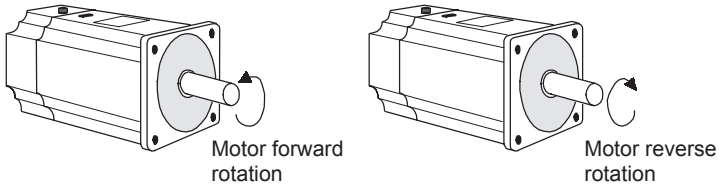
2. Press the DATA/SHIFT Key for a minimum of one second to select the Panel Operator operation mode. Operation is now possible using the Panel Operator.



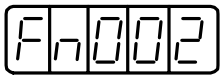
3. Press the MODE/SET Key to set to the servo ON state (with motor power turned ON).



4. Press the Up Cursor Key or Down Cursor Key to operate the motor. The motor keeps operating while the key is pressed.



5. Press the MODE/SET Key to set to the servo OFF state (with motor power turned OFF). Alternatively, press the DATA/SHIFT Key for a minimum of one second to set to the servo OFF state.
6. Press the DATA/SHIFT Key for a minimum of one second and the display will revert to Fn002 in the auxiliary function mode.



This ends operation under Panel Operator control.

The motor speed for operation under control using Digital Operator or Panel Operator can be changed with a parameter:

Parameter: Pn304, Unit: min^{-1}, Standard setting: 500



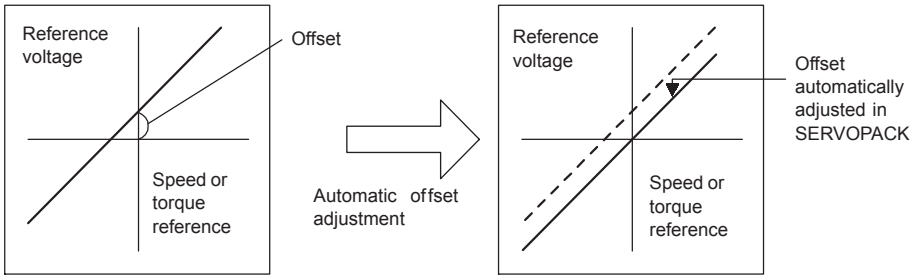
The rotation direction of the servomotor depends on the setting of parameter Pn000.0 “Rotation Direction.” The above example shows a case where Pn000.0 is set to “0” as a factory setting.

6.2.3 Automatic Adjustment of the Speed and Torque Reference Offset

When speed and torque control are used, the motor may rotate slowly even when 0 V is specified as the analog reference voltage. This occurs when the host controller or external circuit has a small offset (measured in mV) in the reference voltage.

The reference offset automatic adjustment mode automatically measures the offset and adjusts the reference voltage. It adjusts both the speed and torque references.

The following diagram illustrates automatic adjustment of an offset in the reference voltage by the SERVOPACK.



After completion of offset automatic adjustment, the amount of offset is stored in the SERVOPACK.

The amount of offset can be checked in the speed reference offset manual adjustment mode. Refer to *6.2.4 Manual Adjustment of the Speed and Torque Reference Offset*.

The reference offset automatic adjustment mode cannot be used for setting the error pulses to zero for a stopped SERVOPACK when a position loop is formed with a host controller.

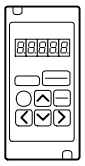
In such cases, use the reference offset manual adjustment mode. Refer to *6.2.4 Manual Adjustment of the Speed and Torque Reference Offset*.

The zero-clamp speed control function is available to force the motor to stop while the zero speed reference is given. Refer to *4.4.3 Using the Zero Clamp Function*.

IMPORTANT

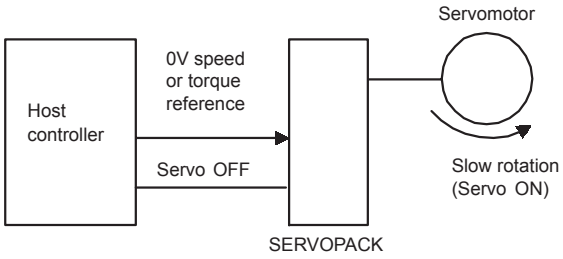
Automatic adjustment of the speed/torque reference offset must be performed under the servo OFF state.

Follow the procedure below to automatically adjust the speed/torque reference offset.

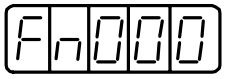


Using the Hand-held Digital Operator

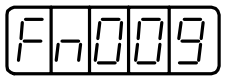
1. Input the (intended) 0 V reference voltage from the host controller or external circuit.



2. Press the DSPL/SET Key to select the auxiliary function mode.



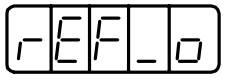
3. Select the parameter Fn009.



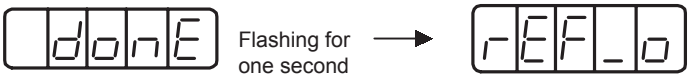
   Press the Left or Right Cursor Key to select the digit.

   Press the Up or Down Cursor Key to change the number.

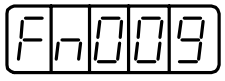
4. Press the DATA/ENTER Key. The following display will appear.



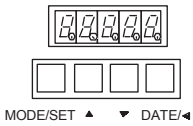
5. Press the DSPL/SET Key, and the following display will flash for one second. The reference offset will be automatically adjusted.



6. Press the DATA/ENTER Key to return to the auxiliary function mode display.

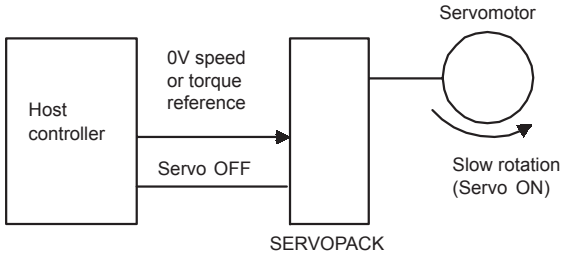


This completes the speed/torque reference offset automatic adjustment.

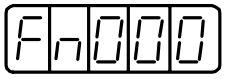


Using the Panel Operator

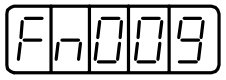
1. Input the (intended) 0 V reference voltage from the host controller or external circuit.



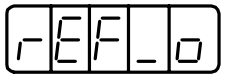
2. Press the MODE/SET Key to select the auxiliary function mode.



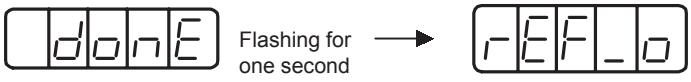
3. Press the Up or Down Cursor Key to select the parameter Fn009.



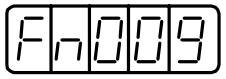
4. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



5. Press the MODE/SET Key and the following display will flash for one second. The reference offset will be automatically adjusted.



6. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the speed/torque reference offset automatic adjustment.

6.2.4 Manual Adjustment of the Speed and Torque Reference Offset

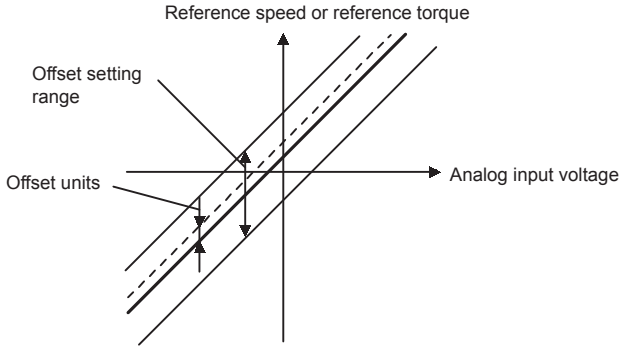
Speed/torque reference offset manual adjustment is very convenient in the following situations:

- If a loop is formed with the host controller and the error is zeroed when servo lock is stopped.
- To deliberately set the offset to some value.

This mode can also be used to check the data set in the reference offset automatic adjustment mode.

In principle, this mode operates in the same way as the reference offset automatic adjustment mode, except that the amount of offset is directly input during the adjustment. The offset amount can be set in the speed reference or torque reference.

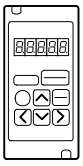
The offset setting range and setting units are as follows:



Offset Setting Range	Offset Setting Range
Speed Reference: -9999 to +9999	Speed Reference: 0.058 mV/LSB
Torque Reference: -128 to +127	Torque Reference: 14.7 mV/LSB

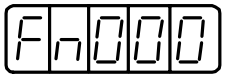
■ Speed Reference Offset Manual Adjustment

Follow the procedure below to manually adjust the speed reference offset.



Using the Hand-held Digital Operator

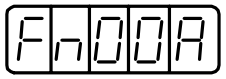
1. Press the DSPL/SET Key to select the auxiliary function mode.



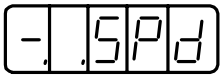
2. Select the parameter Fn00A.

   Press the Left or Right Cursor Key to select the digit.

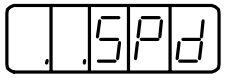
   Press the Up or Down Cursor Key to change the number.



3. Press the DATA/ENTER Key, and the display will be as shown below. The manual adjustment mode for the speed reference offset will be entered.



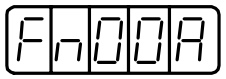
4. Turn ON the Servo ON (/S-ON) signal. The display will be as shown below.



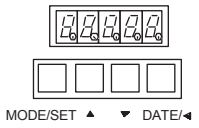
5. Press the Left or Right Cursor Key, to display the speed reference offset amount.



6. Press the Up or Down Cursor Key to adjust the amount of offset (adjustment of the speed reference offset).
7. Press the Left or Right Cursor Key to return to the display in the above step 4.
8. Press the DATA/ENTER Key to return to the auxiliary function mode display.

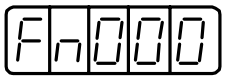


This completes the speed reference offset manual adjustment.

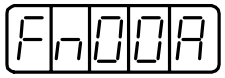


Using the Panel Operator

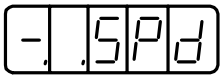
1. Press the MODE/SET Key to select the auxiliary function mode.



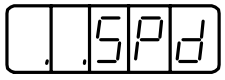
2. Press the Up or Down Cursor Key to select the parameter Fn00A.



3. Press the DATA/SHIFT Key for a minimum of one second. The display will be as shown below. The manual adjustment mode for the speed reference offset will be entered.



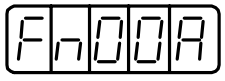
4. Turn ON the Servo ON (/S-ON) signal. The display will be as shown below.



5. Press the DATA/SHIFT Key for less than one second to display the speed reference offset amount.



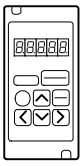
6. Press the Up or Down Cursor Key to adjust the amount of offset (adjustment of the speed reference offset).
7. Press the DATA/SHIFT Key for a minimum of one second to return to the display in the above step 4.
8. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the speed reference offset manual adjustment.

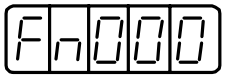
■ Torque Reference Offset Manual Adjustment

Follow the procedure below to manually adjust the torque reference offset.



Using the Hand-held Digital Operator

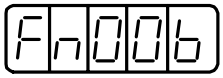
1. Press the DSPL/SET Key to select the auxiliary function mode.



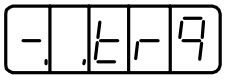
2. Select the parameter Fn00B.

   Press the Left or Right Cursor Key to select the digit.

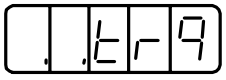
   Press the Up or Down Cursor Key to change the number.



3. Press the DATA/ENTER Key, and the display will be as shown below. The manual adjustment mode for the torque reference offset will be entered.



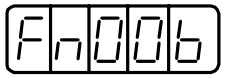
4. Turn ON the Servo ON (/S-ON) signal. The display will be as shown below.



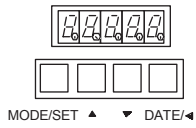
5. Press the Left or Right Cursor Key to display the torque reference offset amount.



6. Press the Up or Down Cursor Key to adjust the offset amount (adjustment of torque reference offset).
7. Press the Left or Right Cursor Key to return to the display in the above step 4.
8. Press the DATA/ENTER Key to return to the auxiliary function mode display.

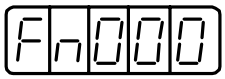


This completes the torque reference offset manual adjustment.

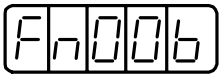


Using the Panel Operator

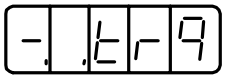
1. Press the MODE/SET Key to select the auxiliary function mode.



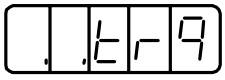
2. Press the Up or Down Cursor Key to select the parameter Fn00B.



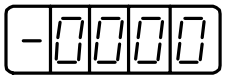
3. Press the DATA/SHIFT Key for a minimum of one second. The display will be as shown below. The manual adjustment mode for the torque reference offset will be entered.



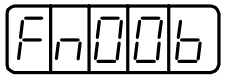
4. Turn ON the Servo ON (/S-ON) signal. The display will be as shown below.



5. Press the DATA/SHIFT Key for less than one second, to display the torque reference offset amount.



6. Press the Up or Down Cursor Key to adjust the offset amount. (Adjustment of torque reference offset).
7. Press the DATA/SHIFT Key for a minimum of one second to return to the display in the above step 4.
8. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.

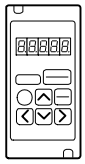


This completes the torque reference offset manual adjustment.

6.2.5 Clearing Alarm Traceback Data

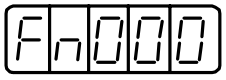
This procedure clears the alarm history, which stores the alarms generated in the SERVOPACK. Each alarm in the alarm history is set to A.- -, which is not an alarm code. Refer to *6.2.1 Operation in Alarm Traceback Mode*.

Follow the procedure below to clear the alarm traceback data.



Using the Hand-held Digital Operator

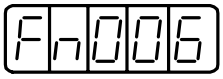
1. Press the DSPL/SET Key to select the auxiliary function mode.

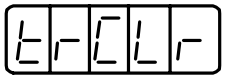
2. Select the parameter Fn006.

   Press the Left or Right Cursor Key to select the digit.

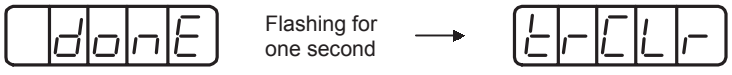
   Press the Up or Down Cursor Key to change the number.

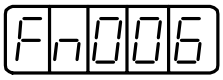
3. Press the DATA/ENTER Key. The following display will appear.

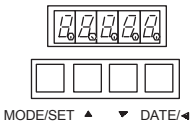
4. Press the DSPL/SET Key to clear the alarm traceback data. The following display will flash for one second, and, after the alarm traceback data is cleared, the display will return to the one in the above step 3.

5. Press the DATA/ENTER Key to return to the parameter number display.

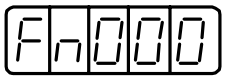
   

This completes the alarm traceback data clearing procedure.

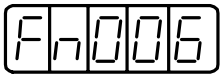


Using the Panel Operator

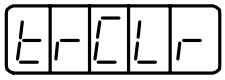
1. Press the MODE/SET Key to select the auxiliary function mode.



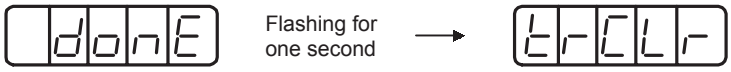
2. Press the Up or Down Cursor Key to select the parameter Fn006.



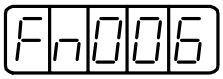
3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



4. Press the MODE/SET Key to clear the alarm tracebcak data. The following display will flash for one second, and, after the alarm traceback data is cleared, the display will return to the one in the above step 3.



5. Press the DATA/SHIFT Key for a minimum of one second to return to the parameter number display.

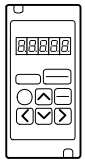


This completes the alarm traceback data clearing procedure.

6.2.6 Checking the Motor Model

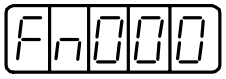
Set the parameter Fn011 to select the motor model check mode. This mode is used for the motor maintenance, and can also be used to check the specification codes of SERVOPACKs made with special specifications.

Follow the procedure below to check the motor model.

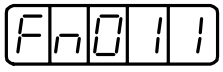


Using the Hand-held Digital Operator

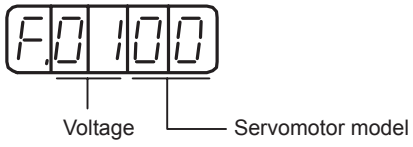
1. Press the DSPL/SET Key to select the auxiliary function mode.



2. Select the parameter Fn011. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



3. Press the DATA/ENTER Key to display the servomotor model and voltage code.



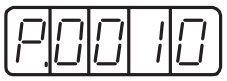
Voltage

Code	Voltage
00	100 VAC or 140 VDC
01	200 VAC or 280 VDC
02	400 VAC or 560 VDC

Servomotor Model

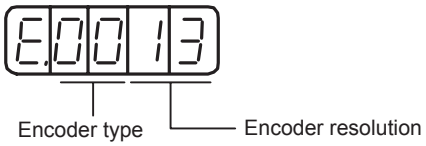
Code	Servomotor Model
00	SGMAH
01	SGMPH
02	SGMSH
03	SGMGH-□A (1500 min^{-1})
04	SGMGH-□B (1000 min^{-1})
05	SGMDH
06	SGMUH
0B	SGMBH

4. Press the DSPL/SET Key to display servomotor capacity.



Capacity: Displayed value × 10 (W)
In this example, the capacity is 100 W.

5. Press the DSPL/SET Key to display the encoder type and resolution code.



Encoder Type

Code	Type
00	Incremental encoder
01	Absolute encoder

Encoder Resolution

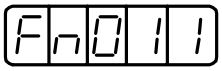
Code	Resolution
13	13 bits
16	16 bits
17	17 bits
20	20 bits

6. Press the DSPL/SET Key to display the SERVOPACK's specification code (Y Specification code).

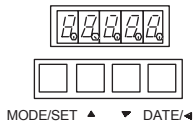


This example shows specification code "Y10" (Indicated in decimal).

7. Press the DATA/ENTER Key to return to the auxiliary function mode display. Pressing the DATA/ENTER Key after the above display 3. to 5. will also return to the auxiliary function mode display.

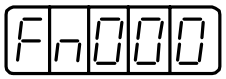


This completes the checking motor type procedure.

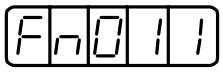


Using the Panel Operator

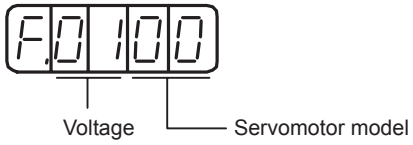
1. Press the MODE/SET Key to select the auxiliary function mode.



2. Press the Up or Down Cursor Key to select the parameter Fn011.



3. Press the DATA/SHIFT Key for a minimum of one second to display the servomotor model and voltage code.



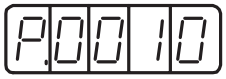
Voltage

Code	Voltage
00	100 VAC or 140 VDC
01	200 VAC or 280 VDC
02	400 VAC or 560 VDC

Servomotor Model

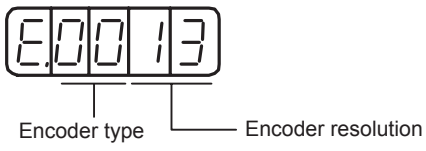
Code	Servomotor Model
00	SGMAH
01	SGMPH
02	SGMSH
03	SGMGH-□A (1500 min^{-1})
04	SGMGH-□B (1000 min^{-1})
05	SGMDH
06	SGMUH
0B	SGMBH

4. Press the MODE/SET Key to display servomotor capacity.



Capacity: Displayed value × 10 (W)
In this example, the capacity is 100 W.

5. Press the MODE/SET Key to display the encoder type and resolution code.



Encoder Type

Code	Type
00	Incremental encoder
01	Absolute encoder

Encoder Resolution

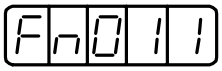
Code	Resolution
13	13 bits
16	16 bits
17	17 bits
20	20 bits

6. Press the MODE/SET Key to display the SERVOPACK's specification code (Y Specification code).



This example shows specification code "Y10"
(Indicated in decimal).

7. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display. Pressing the DATA/SHIFT Key after the above display 3. to 5. will also return to the auxiliary function mode display.



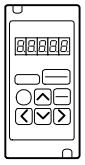
This completes the checking motor type procedure.

6.2.7 Checking the Software Version

This mode is used for the motor maintenance.

Set Fn012 to select the software-version check mode.

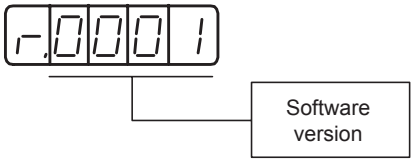
Follow the procedure below to check the software version.



Using the Hand-held Digital Operator

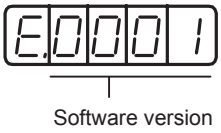
1. Select the parameter Fn012.
2. Press the DATA/ENTER Key and the SERVOPACK's Software version will be displayed.

Software Version Display

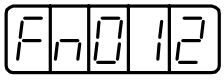


3. Press the DSPL/SET Key and the software version of the encoder mounted on the motor will be displayed.

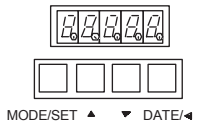
Software Version Display



4. Press the DATA/ENTER Key to return to the parameter number display.



This completes the checking software version procedure.



Using the Panel Operator

1. Select the parameter Fn012.
2. Press the DATA/SHIFT Key for a minimum of one second to display the SERVO-PACK's Software version.
3. Press the MODE/SET Key to display the encoder software version.
4. Press the DATA/SHIFT Key for a minimum of one second to return to the parameter number display.

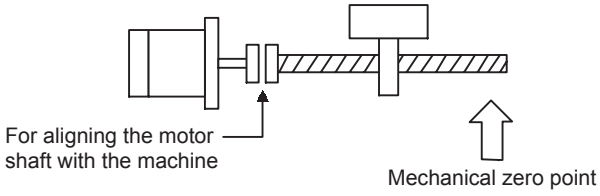
6.2.8 Zero-point Search Mode

⚠ CAUTION

- Forward run prohibited (P-OT) and reverse run prohibited (N-OT) signals are not effective during zero-point search mode operations using parameter Fn003.

The zero-point search mode is designed to position the zero-point pulse position of the encoder and to clamp at the position. This mode is used when the motor shaft needs to be aligned to the machine. Execute the zero-point search without connecting the couplings.

The speed for executing the zero-point search is 60 min^{-1}.

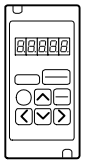


INFO

The following conditions must be met to perform the zero-point search operation.

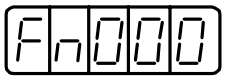
1. If the Servo-ON input signal (/S-ON) is ON, turn it OFF.
2. Release the Servo-ON signal mask if parameter Pn50A.1 is set to 7 and the Servo has been set to always be ON.

Follow the procedure below to execute the zero-point search.

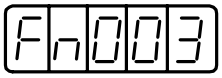


Using the Hand-held Digital Operator

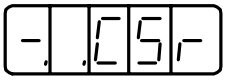
1. Press the DSPL/SET Key to select the auxiliary function mode.



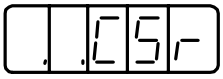
2. Select the parameter Fn003. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



3. Press the DATA/ENTER Key. The following display will appear.



4. Press the SVON Key and the display is as shown below. Now it is ready for executing the zero-point search mode.

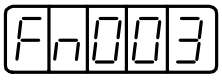


5. Hold down the Up or Down Cursor Key to execute the zero-point search.

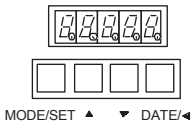
   When the parameter is set to Pn000.0 = 0 (default), pressing the Up Cursor Key will rotate the motor in the forward direction. Pressing the Down Cursor Key will rotate the motor in the reverse direction. When the parameter is set to Pn000.0 = 1, the rotation of the motor is reversed.



6. Press the DATA/ENTER Key to return to the auxiliary function mode display.

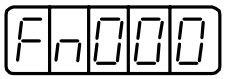


This completes the zero-point search execution.

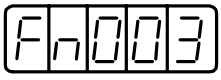


Using the Panel Operator

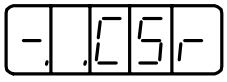
1. Press the MODE/SET Key to select the auxiliary function mode.



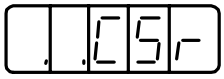
2. Press the Up or Down Cursor Key to select the parameter Fn003.



3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



4. Press the MODE/SET Key and the display is as shown below. Now it is ready for executing the zero-point search mode.

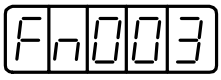


5. Hold down the Up or Down Cursor Key to execute the zero-point search.

   When the parameter is set to Pn000.0 = 0 (default), pressing the Up Cursor Key will rotate the motor in the forward direction. Pressing the Down Cursor Key will rotate the motor in the reverse direction. When the parameter is set to Pn000.0 = 1, the rotation of the motor is reversed.



6. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the zero-point search execution.

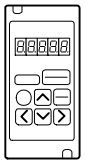
6.2.9 Initializing Parameter Settings

This function is used when returning to the standard settings (factory settings) after changing parameter settings.

IMPORTANT

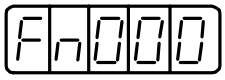
Initialize the parameter settings with the servo OFF.

Follow the procedure below to initialize parameter settings.

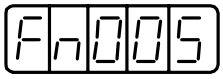


Using the Hand-held Digital Operator

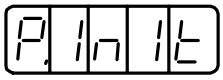
1. Press the DSPL/SET Key to select the auxiliary function mode.



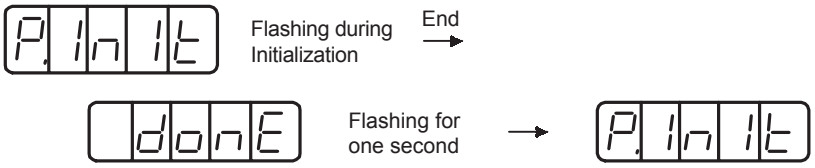
2. Select the parameter Fn005. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



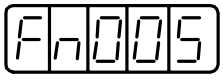
3. Press the DATA/ENTER Key. The following display will appear.



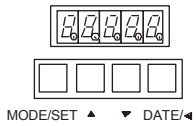
4. Press the DSPL/SET Key and the display will change as shown below. The parameter will be initialized.



5. Press the DATA/ENTER Key to return to the auxiliary function mode display.

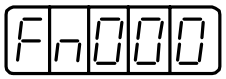


This completes the initialization of parameter settings.

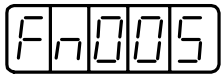


Using the Panel Operator

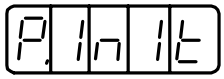
1. Press the MODE/SET Key to select the auxiliary function mode.



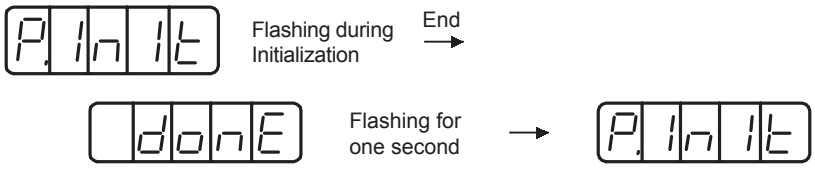
2. Press the Up or Down Cursor Key to select the parameter Fn005.



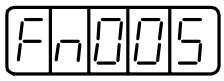
3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



4. Press the MODE/SET Key and the display will change as shown below. The parameter will be initialized.



5. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the initialization of parameter settings.

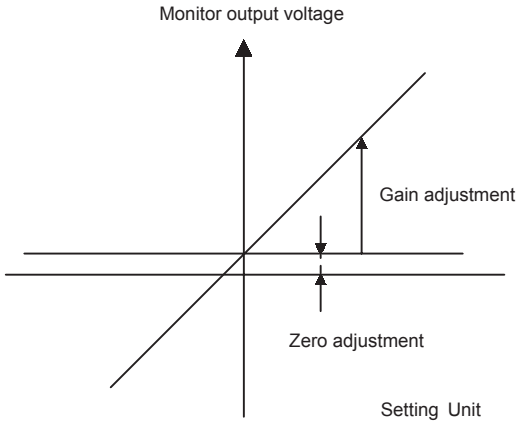


Parameters will not be initialized by pressing the DSPL/SET or MODE/SET Key with the servo ON. Turn the power OFF and then back ON after initialization.

6.2.10 Manual Zero Adjustment and Gain Adjustment of Analog Monitor Output

Motor speed, torque reference, and position error can be monitored through the analog monitor output. Refer to *5.5 Analog Monitor*.

Use the manual zero adjustment function to compensate for the output voltage drift or the zero point drift caused by noise entering the monitor system. The gain adjustment function can be changed to match the sensitivity of the measuring system.

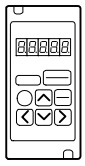


INFO

The output voltage of the analog monitor is ±8 V max. The output voltage will be reversed if ±8 V is exceeded.

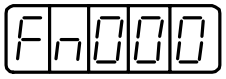
■ Manual Zero Adjustment of Analog Monitor Output

Follow the procedure below to execute the manual zero adjustment of analog monitor output.

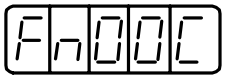


Using the Hand-held Digital Operator

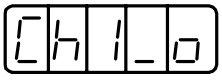
1. Press the DSPL/SET Key to select the auxiliary function mode.



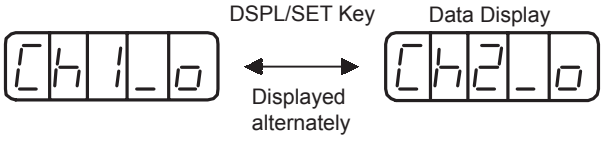
2. Select the parameter Fn00C. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



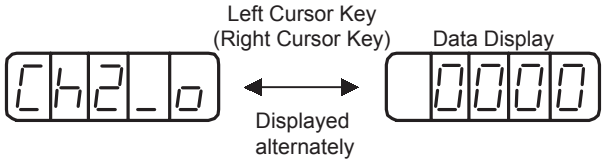
3. Press the DATA/ENTER Key. The following display will appear.



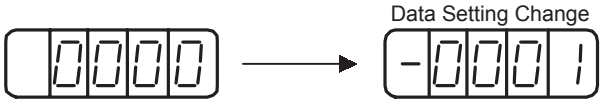
4. Press the DSPL/SET Key, and the monitor output for the two channels will be displayed alternately as shown below.



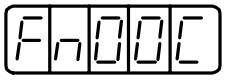
5. Press the Left or Right Cursor Key to display the analog monitor output data. Pressing the Left or Right Cursor Key again will return to the display shown in the above step 3. or 4.



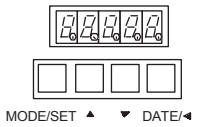
6. Press the Up or Down Cursor Key to perform zero adjustment of the analog monitor output.



7. When zero adjustment has been completed for the two channels, press the DATA/ ENTER Key to return to the auxiliary function mode display.

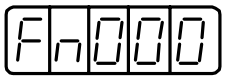


This completes the manual zero adjustment of the analog monitor output.

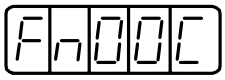


Using the Panel Operator

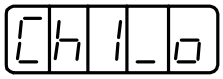
1. Press the MODE/SET Key to select the auxiliary function mode.



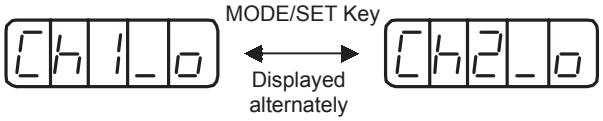
2. Press the Up or Down Cursor Key to select the parameter Fn00C.



3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



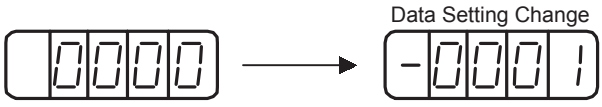
4. Press the MODE/SET Key, and the monitor output for the two channels will be displayed alternately as shown below.



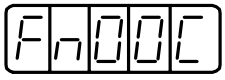
5. Press the DATA/SHIFT Key for less than one second, and the analog monitor gain constant will be displayed. Pressing the DATA/SHIFT Key again for less than one second will return to the display shown in the above step 3. or 4.



6. Press the Up or Down Cursor Key to perform zero adjustment of the analog monitor output.



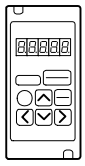
7. When zero adjustment has been completed for the two channels, press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the manual zero adjustment of the analog monitor output.

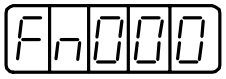
■ Manual Gain Adjustment of Analog Monitor Output

Follow the procedure below to execute the manual gain adjustment of analog monitor output.

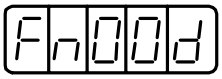


Using the Hand-held Digital Operator

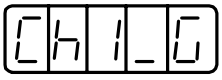
1. Press the DSPL/SET Key to select the auxiliary function mode.



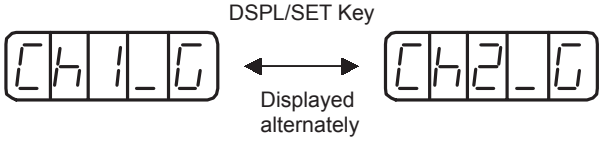
2. Select the parameter Fn00D. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



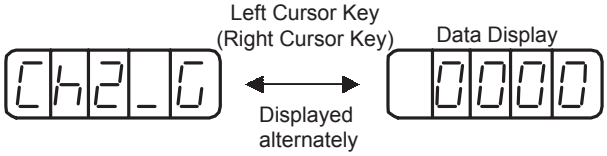
3. Press the DATA/ENTER Key. The following display will appear.



4. Press the DSPL/SET Key, and the monitor output for the two channels will be displayed alternately as shown below.



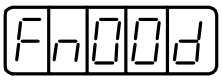
5. Press the Left or Right Cursor Key to display the analog monitor gain constant. Pressing the Left or Right Cursor Key again will return to the display shown in the above step 3. or 4.



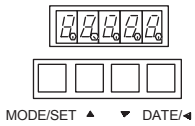
6. Press the Up or Down Cursor Key to adjust the gain for the analog monitor output.



7. When the gain adjustment has been completed for the two channels, press the DATA/ ENTER Key to return to the auxiliary function mode display.

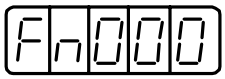


This completes the manual gain adjustment of the analog monitor output.

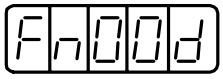


Using the Panel Operator

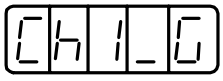
1. Press the MODE/SET Key to select the auxiliary function mode.



2. Press the Up or Down Cursor Key to select the parameter Fn00D.



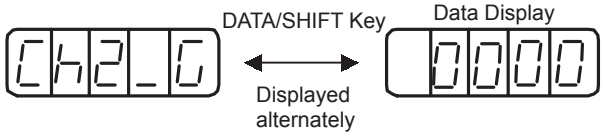
3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



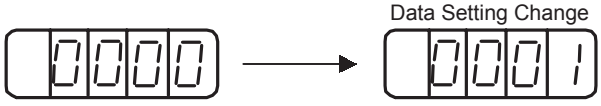
4. Press the MODE/SET Key, and the monitor output for the two channels will be displayed alternately as shown below.



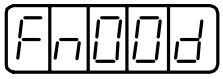
5. Press the DATA/SHIFT Key for less than one second, and the analog monitor gain constant will be displayed. Pressing the DATA/SHIFT Key again for less than one second will return to the display shown in the above step 3. or 4.



6. Press the Up or Down Cursor Key to adjust the gain for the analog monitor output.



7. When the gain adjustment has been completed for the two channels, press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the manual gain adjustment of the analog monitor output.

6.2.11 Adjusting the Motor Current Detection Offset

Motor current detection offset adjustment is performed at Yaskawa before shipping. Basically, the user need not perform this adjustment. Perform this adjustment only if highly accurate adjustment is required for reducing torque ripple caused by current offset.

The following sections describe automatic and manual adjustment of the current detection offset.

IMPORTANT

If this function, particularly manual adjustment, is executed carelessly, it may worsen the characteristics.

■ Automatic Adjustment of the Motor Current Detection Offset

Follow the procedure below to perform automatic adjustment of the current detection offset.

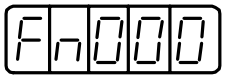
INFO

Automatic adjustment is possible only with power supplied to the main circuits and with the servo OFF.

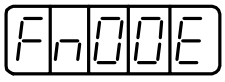


Using the Hand-held Digital Operator

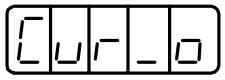
1. Press the DSPL/SET Key to select the auxiliary function mode.



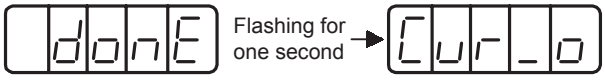
2. Select the parameter Fn00E. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



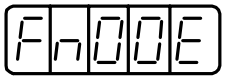
3. Press the DATA/ENTER Key. The following display will appear.



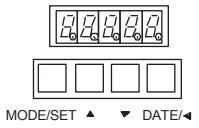
4. Press the DSPL/SET Key. The display will change as shown below and offset will be automatically adjusted.



5. Press the DATA/ENTER Key to return to the auxiliary function mode display.

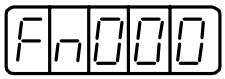


This completes the automatic adjustment of the motor current detection offset.

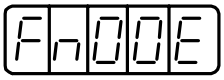


Using the Panel Operator

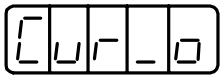
1. Press the MODE/SET Key to select the auxiliary function mode.



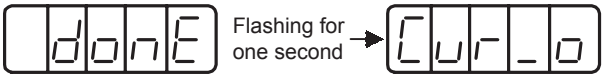
2. Press the Up or Down Cursor Key to select the parameter Fn00E.



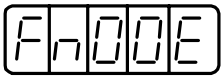
3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



4. Press the MODE/SET Key. The display will change as shown below and offset will be automatically adjusted.



5. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



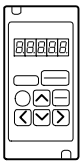
This completes the automatic adjustment of the motor current detection offset.

■ Manually Adjusting the Motor Current Offset

Follow the procedure below to manually adjust the current detection offset.

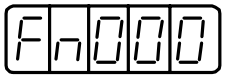
IMPORTANT

When making manual adjustments, run the motor at a speed of approximately 100 min^{-1}, and adjust the Operator until the torque monitor ripple is minimized. (Refer to Section *5.5 Analog Monitor*.) Adjust the phase-U and phase-V offsets alternately several times until these offsets are well balanced.

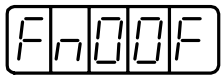


Using the Hand-held Digital Operator

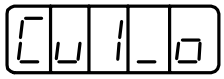
1. Press the DSPL/SET Key to select the auxiliary function mode.



2. Select the parameter Fn00F. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



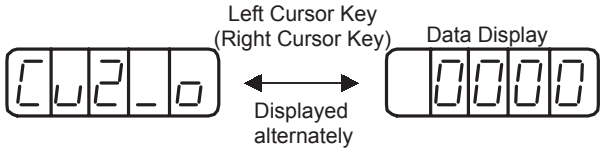
3. Press the DATA/ENTER Key. The following display will appear.



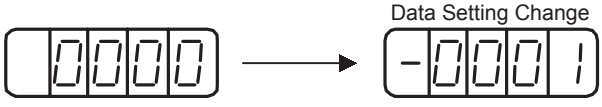
4. Press the DSPL/SET Key to switch between the phase-U (Cu1_0) and phase-V (Cu2_0) current detection offset adjustment mode.



5. Press the Left or Right Cursor Key to display the current detection data. Pressing the Left or Right Cursor Key again will return to the display shown in the above step 3. or 4.

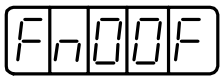


6. Press the Up or Down Cursor Key to adjust the offset. Carefully adjust the offset while monitoring the torque reference monitor signal.

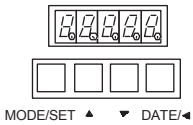


7. When the current offset adjustment has been completed for the phase U (Cu1_0) and phase V (Cu2_0), press the DATA/ENTER Key to return to the auxiliary function mode display.

6

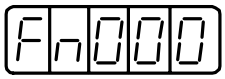


This completes the manual adjustment of the motor current detection offset.

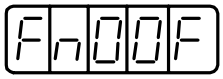


Using the Panel Operator

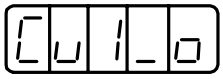
1. Press the MODE/SET Key to select the auxiliary function mode.



2. Press the Up or Down Cursor Key to select the parameter Fn00F.



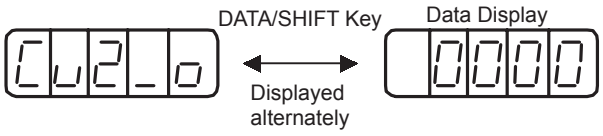
3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



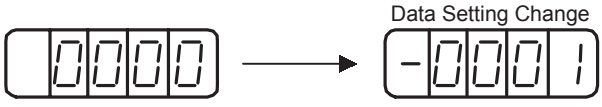
4. Press the MODE/SET Key to switch between phase-U (Cu1_0) and phase-V (Cu2_0) current detection offset adjustment mode.



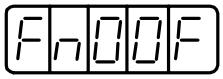
5. Press the DATA/SHIFT Key for less than one second to display the current detection data. Pressing the DATA/SHIFT Key again for less than one second will return to the display shown in the above step 3. or 4.



6. Press the Up or Down Cursor Key to adjust the offset. Carefully adjust the offset while monitoring the torque reference monitor signal.



7. When the current offset adjustment has been completed for the phase U (Cu1_0) and phase V (Cu2_0), press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the manual adjustment of the motor current detection offset.

6.2.12 Password Setting (Write Prohibited Setting)

The password setting is used for preventing careless changes of the parameter. Parameters Pn□□□ and some of Fn□□□ become write prohibited by setting the password.

Password setting values are as follows:

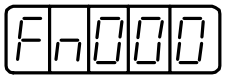
- "0000": Write enabled (Releases write prohibited mode.)
- "0001": Write prohibited (Parameters become write disabled from the next power ON.)

Follow the procedure below to set the password.



Using the Hand-held Digital Operator

1. Press the DSPL/SET Key to select the auxiliary function mode.



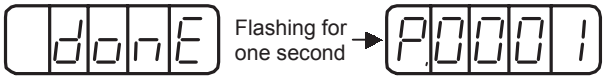
2. Select the parameter Fn010. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



3. Press the DATA/ENTER Key. The following display will appear.



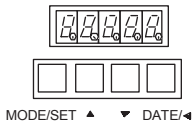
4. Input the password (0001) and press the DSPL/SET Key. The display will change as shown below and the password will be registered.



5. Press the DATA/ENTER Key to return to the auxiliary function mode display.

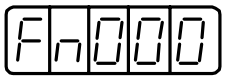


This completes the procedure for setting the password. The newly set password will become valid from the next power ON.



Using the Panel Operator

1. Press the MODE/SET Key to select the auxiliary function mode.



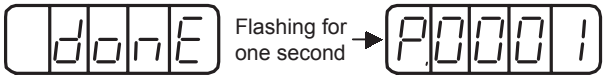
2. Press the Up or Down Cursor Key to select the parameter Fn010.



3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



4. Input the password (0001) and press the MODE/SET Key. The display will change to one shown below and the password will be registered.



5. Press the DATA/SHIFT Key for a minimum of one second to return to the auxiliary function mode display.



This completes the procedure for setting the password. The newly set password will become valid from the next power ON.

6.2.13 Clearing Option Unit Detection Results

The alarm A.E7 (option unit detection fail) occurs when turning ON the power for the first time when the SGDH is used without option unit after the SGDH has been used with option unit.

The following operation does not permanently reset the alarm A.E7. Restarting again after performing the following operation will clear and reset the alarm A.E7. Then, the operation of SGDH without option unit is enabled.

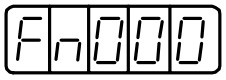
IMPORTANT

Because the parameter is set for the SGDH with an option unit, change the setting or initialize the parameter value (Fn005 of auxiliary function mode) as required.



Using the Hand-held Digital Operator

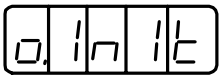
1. Press the DSPL/SET Key to select the auxiliary function mode.



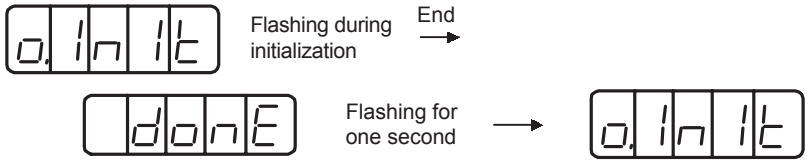
2. Select the parameter Fn014. Press the Left or Right Cursor Key to select the digit. Press the Up or Down Cursor Key to change the number.



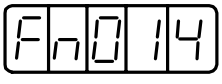
3. Press the DATA/ENTER Key. The following display will appear.



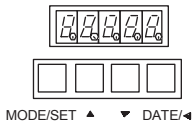
4. Press the DSPL/SET Key. The display will change as shown below and the option unit detection result will be cleared.



5. Press the DATA/ENTER Key to return to the auxiliary function mode display.

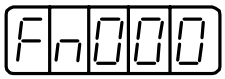


This completes the clear of the option unit detection results.



Using the Panel Operator

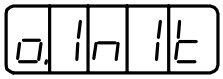
1. Press the MODE/SET Key to select the auxiliary function mode.



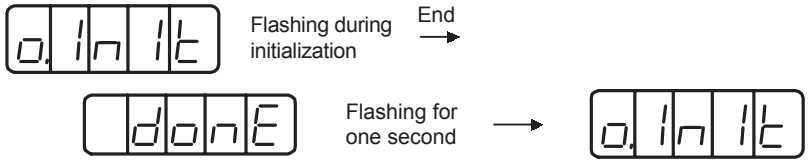
2. Press the Up or Down Cursor Key to select the parameter Fn014.



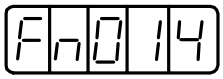
3. Press the DATA/SHIFT Key for a minimum of one second. The following display will appear.



4. Press the MODE/SET Key. The display will change as shown below and the option unit detection result will be cleared.



5. Press the DATA/SHIFT Key to return to the auxiliary function mode display.



This completes the clear of the option unit detection results.

7

Servo Selection and Data Sheets

This chapter describes how to select Σ-II Series servodrives and peripheral devices. The chapter also presents the specifications and dimensional drawings required for selection and design. Refer to this chapter for selecting or designing an appropriate servodrive.

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7.1 Selecting a Σ-II Series Servodrives

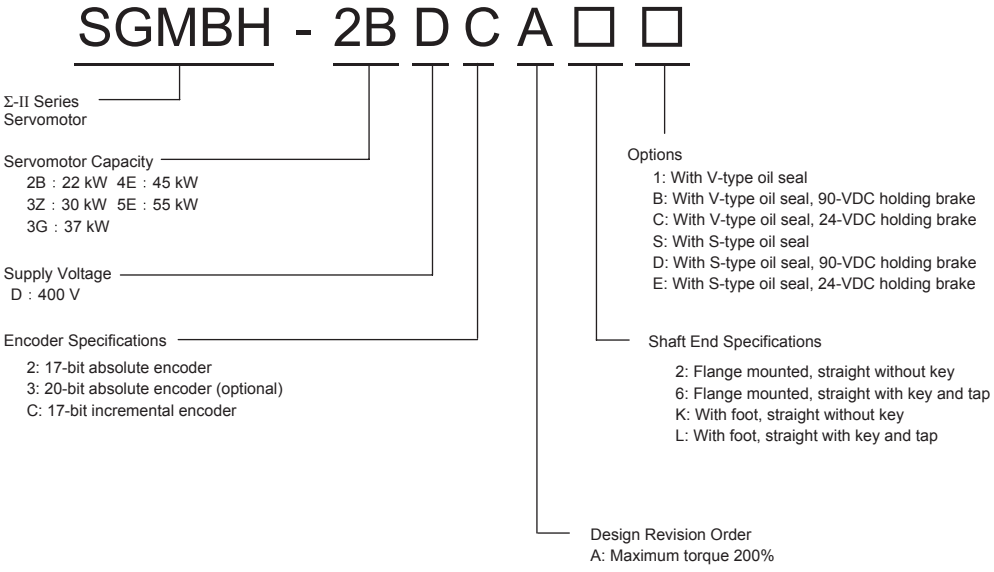
This section describes how to select the Σ-II Series servomotor, SERVOPACK, and Digital Operator.

7.1.1 Selecting Servomotors

This section describes the available models and provides flowcharts for selecting servomotors.

Model Designations

A servomotor can be selected based on the seven-digit alphanumeric characters after SGMBH.

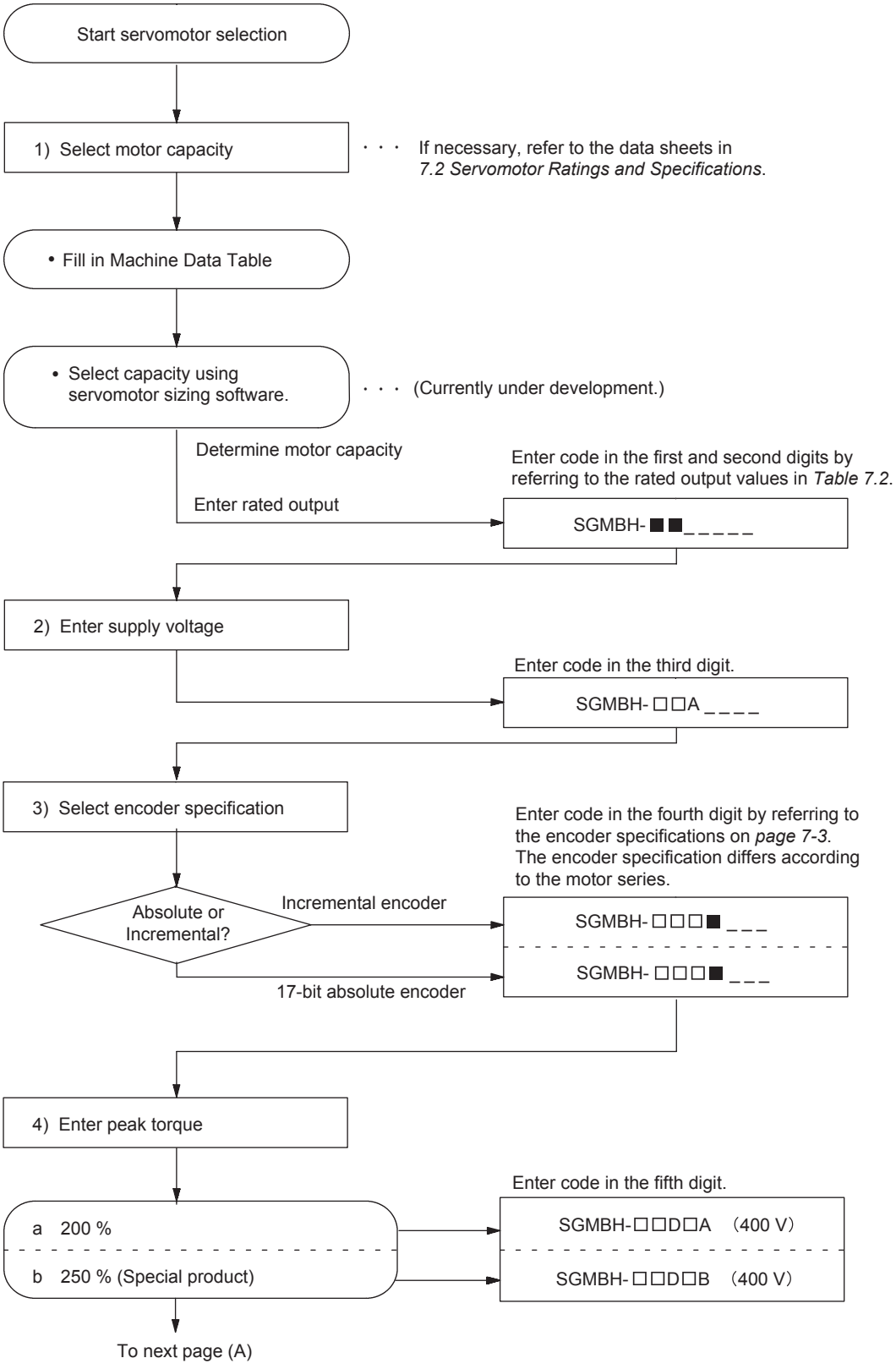


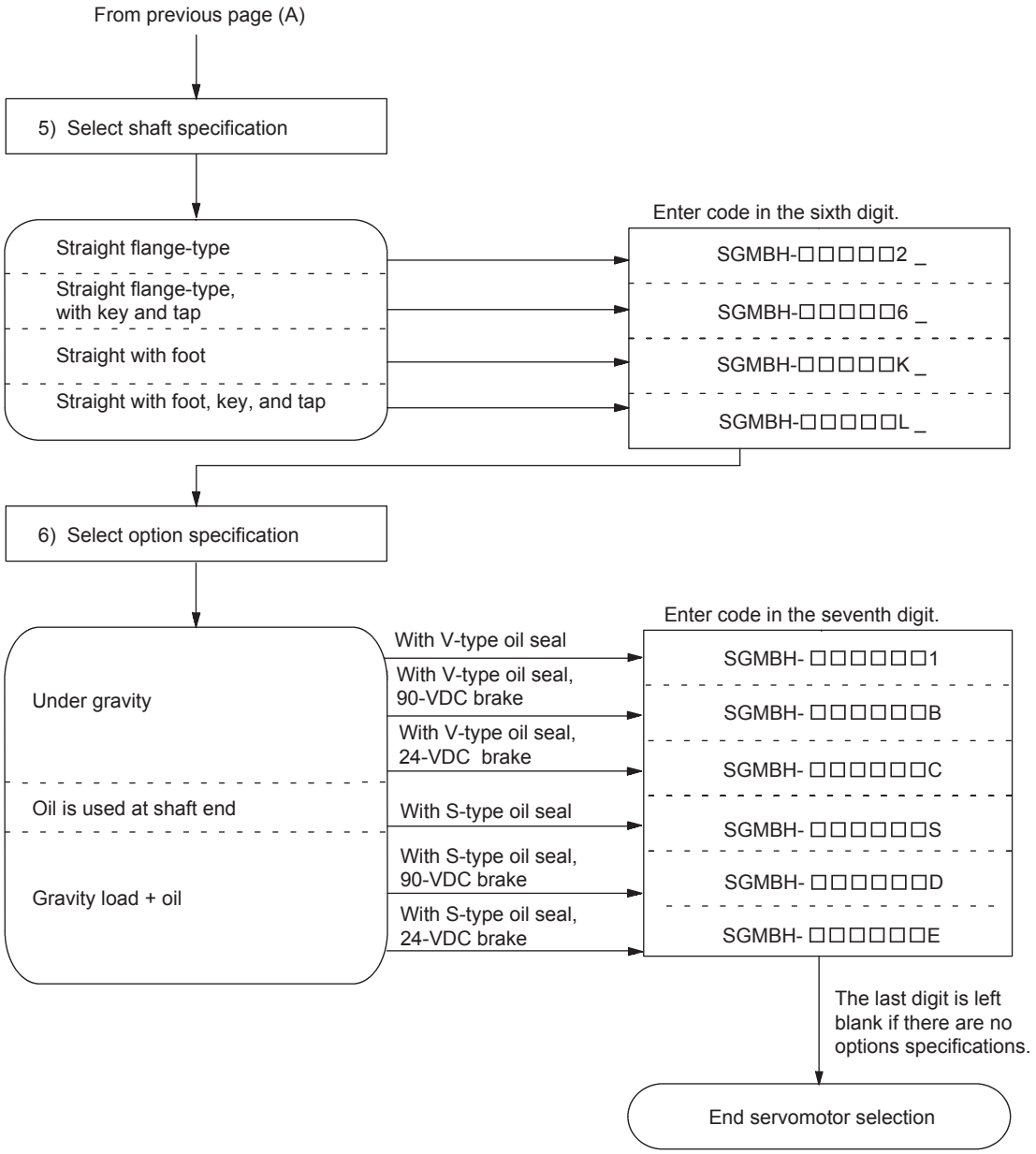
Flowchart for servomotor selection

	Selected Motor Model
Example	SGMBH- 2 B D C A □ □
Axis 1	SGMBH- □ □ □ □ □ □ □
Axis 2	SGMBH- □ □ □ □ □ □ □
· · ·	· · · · · · Blank for standard specification

Servomotor Selection Flowchart

Use the following flowchart to select a servomotor.




From previous page (A)
5) Select shaft specification
Enter code in the sixth digit.
Straight flange-type
Straight flange-type, with key and tap
Straight with foot
Straight with foot, key, and tap
SGMBH-□□□□□2 _
SGMBH-□□□□□6 _
SGMBH-□□□□□K _
SGMBH-□□□□□L _
6) Select option specification
Enter code in the seventh digit.
Under gravity
Oil is used at shaft end
Gravity load + oil
With V-type oil seal
With V-type oil seal, 90-VDC brake
With V-type oil seal, 24-VDC brake
With S-type oil seal
With S-type oil seal, 90-VDC brake
With S-type oil seal, 24-VDC brake
SGMBH- □□□□□□1
SGMBH- □□□□□□B
SGMBH- □□□□□□C
SGMBH- □□□□□□S
SGMBH- □□□□□□D
SGMBH- □□□□□□E
The last digit is left blank if there are no options specifications.
End servomotor selection

7

Selecting Capacity Based on Machine Specifications

Fill out the data table below as an aid in selecting a drive system. When the machine data table is complete, use the Servomotor Sizing Software to select motor capacity.

Table 7.1 Machine Data Table

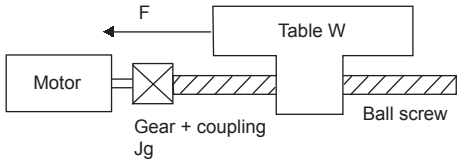
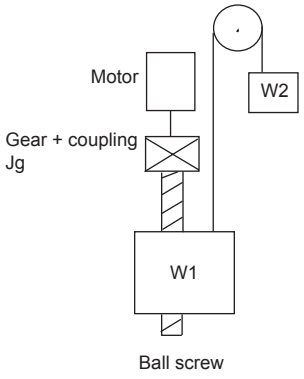
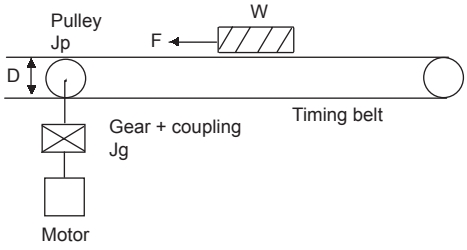
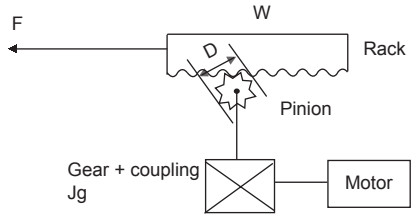
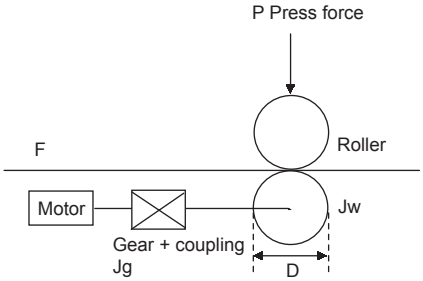
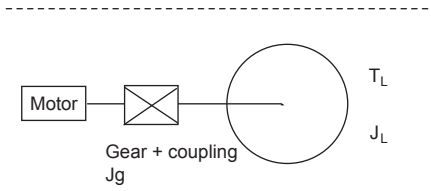
Ball Screw Horizontal Axis			Device Configuration
Load mass*1	W	kg	
Thrust	F	N	
Friction coefficient	μ		
Overall efficiency	η		
Gear ratio*2	R (=N_M/N_L)		
Gear + coupling*3	Jg	kg • cm^2	
Ball screw pitch	P	mm	
Ball screw diameter	D	mm	
Ball screw length	L	mm	
Ball Screw Vertical Axis			
Load mass	W1	kg	
Counterweight	W2	kg	
Friction coefficient	μ		
Overall efficiency	η		
Deceleration ratio	R (=N_M/N_L)		
Gear + coupling	Jg	kg • cm^2	
Ball screw pitch	P	mm	
Ball screw diameter	D	mm	
Ball screw length	L	mm	
Timing Belt			
Load mass	W	kg	
Thrust	F	N	
Friction coefficient	μ		
Overall efficiency	η		
Deceleration ratio	R (=N_M/N_L)		
Gear + coupling	Jg	kg • cm^2	
Pulley moment of inertia	J_P	kg • cm^2	
Pulley diameter	D	mm	

Table 7.1 Machine Data Table (cont'd)

Rack and Pinion		
Load mass	W	kg
Thrust	F	N
Friction coefficient	μ	
Overall efficiency	η	
Deceleration ratio	R (=N_M/N_L)	
Gear + coupling	Jg	kg • cm^2
Pinion diameter	D	mm
Pinion thickness	t	mm
Roll Feeder		
Load moment of inertia	J_W	kg • cm^2
Tension	F	N
Press force	P	N
Roller diameter	D	mm
Friction coefficient	μ	
Overall efficiency	η	
Deceleration ratio	R (=N_M/N_L)	
Gear + coupling	Jg	kg • cm^2
Rotor		
Load moment of inertia	J_L	kg • cm^2
Load torque	T_L	kg • cm
Overall efficiency	η	
Deceleration ratio	R (=N_M/N_L)	
Gear + coupling	Jg	kg • cm^2
Others		
Load moment of inertia	J_L	kg • cm^2
Load torque	T_L	N • m
Motor speed	N_M	min^{-1}
Duty	t c	s
Positioning time	t s	s
Accel/decel time	t a	s

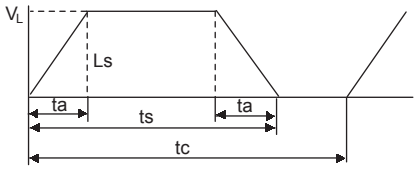






7

Table 7.1 Machine Data Table (cont'd)

Duty Cycle			
Duty	t c	s	
Positioning distance	Ls	mm	
Slide speed	V_L	m/min	
Positioning time	t s	s	
Accel/decel time	t a	s	
Enter either V_L or ts. Specify the priority if both are entered.			
Operating environment Ambient temperature Others			

* 1. Moment of inertia J for table W (load mass) can be calculated with the Sizing Software.
Moment of inertia J for the servomotor is calculated automatically with the Sizing Software.
* 2. Gear ratio R = N_M/N_L = Motor speed/load-end speed
* 3. Gear + coupling Jg: Gear or coupling moment of inertia. This is the moment of inertia for coupling between the servomotor and the load (machine).

7.1.2 Selecting SERVOPACKs

The following section describes SERVOPACK models and applicable servomotors.

SGDH - 2B D E

Σ-II Series
SGDH SERVOPACK

Rated Output (motor capacity)
2B : 22 kW 4E : 45 kW
3Z : 30 kW 5E : 55 kW
3G : 37 kW

Supply Voltage
D : 400 V

Model
E: For speed/torque control and position control

Flowchart for SERVOPACK selection

	Selected SERVOPACK Model
Example	SGDH- 2 B D E
Axis 1	SGDH- □□□□
Axis 2	SGDH- □□□□
. . .	. . . . .

7.2 Servomotor Ratings and Specifications

This section provides the ratings, specifications, and mechanical characteristics of the SGMBH servomotors.

7.2.1 Ratings and Specifications

The following sections provide the ratings and specifications of the servomotors by model.

■ SGMBH Servomotors

- Time Rating: Continuous
- Thermal Class: F
- Vibration Class: 15μm or below
- Withstand Voltage: 1800 VAC
- Insulation Resistance: 500 VDC, 10 MΩ min.
- Enclosure: Totally enclosed, cooled separately, IP44
- Ambient Temperature: 0 to 40°C
- Ambient Humidity: 20% to 80% (with no condensation)
- Excitation: Permanent magnet
- Drive Method: Direct drive
- Mounting: Foot and flange-mounted type

Table 7.2 SGMBH Standard Servomotor Ratings and Specifications

Servomotor Model SGMBH-		2BD□A	3ZD□A	3GD□A	4ED□A	5ED□A
Rated Output*1	kW	22	30	37	45	55
Rated Torque*1	N • m	140	191	236	286	350
	lb • in*2	1240	1690	2090	2530	3100
Instantaneous Peak Torque*1	N • m	280	382	471	572	700
	lb • in*2	2480	3380	4170	5060	6120
Rated Current *1	A (rms)	58	80	100	127	150
Instantaneous Max. Current *1	A (rms)	120	170	210	260	310
Rated Speed *1	min^{-1}	1500				
Max. Speed *1	min^{-1}	2000				
Rotor Moment of Inertia *J*	$\times 10^{-4}$ kg • m^2	592	773	1390	1510	1970
	$\times 10^{-3}$ lb • in • s^{2*2}	525	685	1230	1490	1750
Rated Power Rate *1	kW/s	331	472	401	542	622
Rated Angular Acceleration*1	rad/s^2	2360	2470	1700	1890	1780

* 1. These items and torque-motor speed characteristics quoted in combination with an SGDH SERVOPACK are at an armature winding temperature of 20°C (68°F).

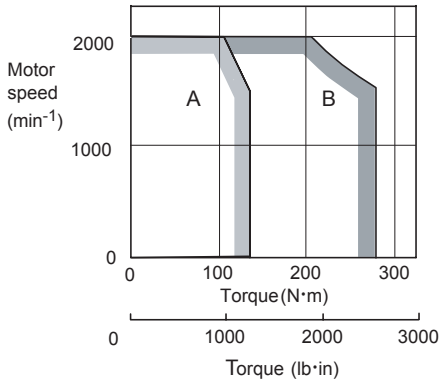
* 2. These values are reference values.

Note: These characteristics are values with the following heat sinks attached for cooling.
SGMBH-2B, -3Z: 650 × 650 × 35 (mm) [26 × 26 × 1.38 (in.)]
SGMBH-3G, -4E, -5E: 750 × 750 × 45 (mm) [30 × 30 × 1.77 (in.)]

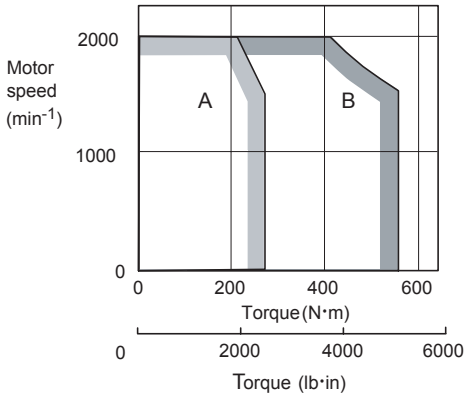
Torque-Motor Speed Characteristics

The torque-motor speed characteristics for the SGMBH servomotor (rated motor speed: 1500 min^{-1}) are shown below.

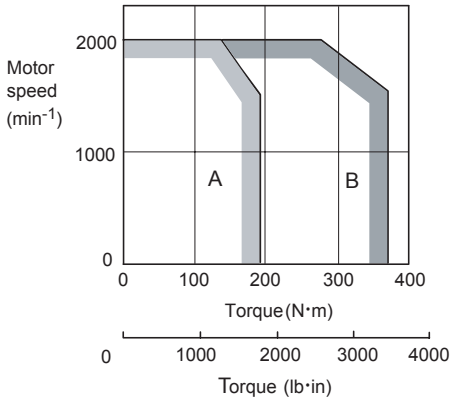
SGMBH-2BD□□



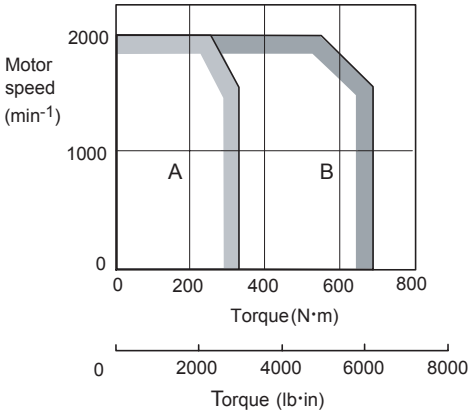
SGMBH-4ED□□



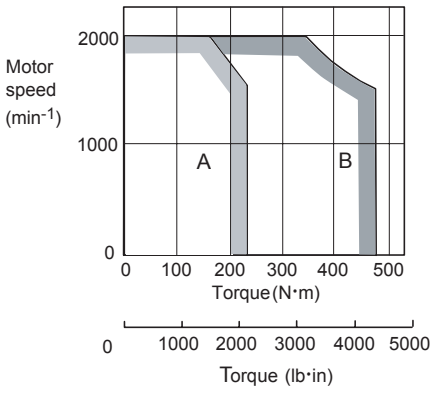
SGMBH-3ZD□□



SGMBH-5ED□□



SGMBH-3GD□□



7.2.2 Mechanical Characteristics

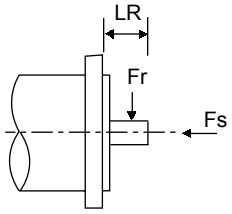
The following sections provide the mechanical characteristics of the SGMBH servomotors.

■ Allowable Radial and Thrust Loads

The following table shows the allowable loads on the output shafts of the SGMBH servomotors.

Conduct mechanical design such that the radial loads and thrust loads do not exceed the values shown in *Table7.3*.

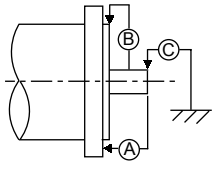
Table 7.3 Allowable Radial and Thrust Loads for the Servomotor

Servomotor Model SGMBH-	Allowable Radial Load Fr [N (lbf)]	Allowable Thrust Load Fs [N (lbf)]	LR mm (inch)	Reference Diagram
2BD□□	5880 (1323)	2156 (485)	100 (3.94)	
3ZD□□	6272 (1412)	2156 (485)	100 (3.94)	
3GD□□	7448 (1676)	2156 (485)	100 (3.94)	
4ED□□	7840 (1764)	2156 (485)	100 (3.94)	
5ED□□	8428 (1897)	2156 (485)	110 (4.33)	

Note: Allowable radial and thrust loads shown above are the maximum values that could be applied to the shaft end from motor torque or other loads.

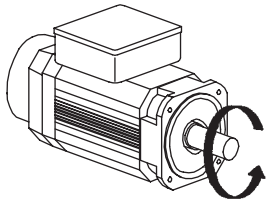
■ Mechanical Tolerance

The following table shows tolerances for SGMBH servomotor output shaft and installation area. See the dimensional drawing of the individual servomotor for more details on tolerances.

Tolerance T. I. R. (Total Indicator Reading)		Reference Diagram
Perpendicularity between the flange face and output shaft Ⓐ	0.05	
Mating concentricity of the flange O.D. Ⓑ	0.05	
Run-out at the end of the shaft Ⓒ	0.03	

■ Direction of Servomotor Rotation

Positive rotation of the servomotor is counterclockwise when viewed from the load.

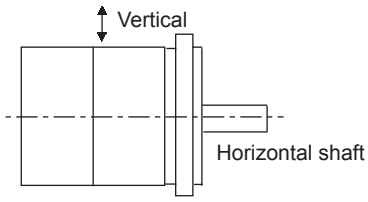


Positive direction

■ Impact Resistance

Mount the servomotor with the axis horizontal. The servomotor will withstand the following vertical impacts:

- Impact Acceleration: 490 m/s^2
- Number of Impacts: 2



Impact applied to the servomotor

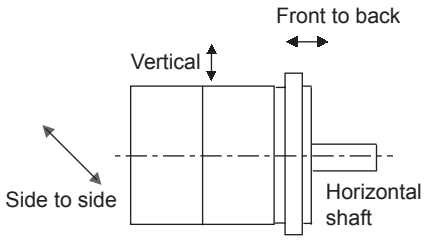
IMPORTANT

SGMBH servomotors have a precision detector attached to the end of the shaft opposite the load. Avoid direct impact on the shaft because it may damage the detector.

■ Vibration Resistance

Mount the servomotor with the axis horizontal. The servomotor will withstand the following vibration acceleration in three directions: Vertical, side to side, and front to back.

- Vibration Acceleration: 24.5 m/s^2

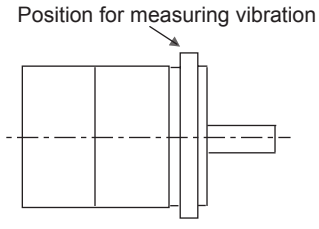


Impact applied to the servomotor

■ Vibration Class

The vibration class for the SGMBH servomotors at rated motor speed is as follows:

- Vibration Class: 15 μm or below



7.3 SERVOPACK Ratings and Specifications

This section provides the ratings, specifications, and mechanical characteristics of the SGDH SERVOPACKs.

7.3.1 Combined Specifications

The following table shows the specifications obtained when SGDH SERVOPACKs are combined with SGMBH servomotors:

Table 7.4 SERVOPACK and Servomotor Combination Specifications

SERVOPACK Model SGDH-		2BDE	3ZDE	3GDE	4EDE	5EDE
Applicable Servomotor	Model SGMBH-	2BD	3ZD	3GD	4ED	5ED
	Capacity (kW)	22	30	37	45	55
	Motor Speed min^{-1}	Rated 1500/maximam 2000				
Applicable Encoder		Standard: 17-bit incremental encoder or 17-bit absolute encoder				
Continuous Output Current A (rms)		58	80	100	127	150
Max. Output Current A (rms)		120	170	210	260	310
Allowable Load Moment of Inertia J $\times 10^{-4}$ kg • m^2 ($\times 10^{-3}$oz • in • s^2)		2960 (2621)	3865 (3422)	6950 (6153)	7550 (6684)	9850 (8721)

7.3.2 Ratings and Specifications

The following table shows ratings and specifications for the SGDH SERVOPACK. Refer to them as required when selecting a SERVOPACK.

Table 7.5 SERVOPACK Ratings and Specifications

SERVOPACK Model SGDH-			400 V Series				
			2BDE	3ZDE	3GDE	4EDE	5EDE
Applicable Servomotor Model SGMBH-			3BD	3ZD	3GD	4ED	5ED
Continuous Output (kW)			22	30	37	45	55
Allowable Load Moment of Inertia J $\times 10^{-4}$ kg • m^2 ($\times 10^{-3}$oz • in • s^2)			2960 (2621)	3865 (3422)	6950 (6153)	7550 (6684)	9850 (8721)
Basic Specifications	Input Power Supply *1	Main Circuit	Three-phase 380 to 480 VAC +10 to -15%, 50/60 Hz				
		Main Circuit Power Supply Capacity (kVA)	36.7	50.1	61.8	75.2	91.9
		Control Circuit	24 VDC ±15%				
		Control Circuit Power Supply Capacity	150 VA				
	Control Mode		Three-phase full-wave rectification IGBT-PWM (sine-wave driven)				
	Feedback		Incremental encoder, absolute encoder				
	Operating Conditions:	Ambient/Storage Temperature *2	0 to + 55 °C / -20 to + 85 °C (32 to 131 °F / -4 to 185 °F)				
		Ambient/Storage Humidity	90% RH or less (with no condensation)				
		Vibration/Shock Resistance	4.9 m/s^2 / 19.6 m/s^2				
	Configuration		Base-mounted				
	Approx. Mass kg (lb)		40 (88)		60 (132)	65 (144)	

Table 7.5 SERVOPACK Ratings and Specifications (cont'd)

SERVOPACK Model SGDH-				400 V Series				
				2BDE	3ZDE	3GDE	4EDE	5EDE
Speed and Torque Control Mode	Performance	Speed Control Range		1:5000 (The lowest speed of the speed control range is the speed at which the servomotor will not stop with a rated torque load.)				
		Speed Regulation *3	Load Regulation	0 to 100% load: ±0.01% max. (at rated speed)				
			Voltage Regulation	Rated Voltage ±10%: 0% (at rated speed)				
			Temperature Regulation	25 ± 25 °C (77 ± 77 °F) : ±0.1% max. (at rated speed)				
		Frequency Characteristics		400 Hz (at $J_L = J_M$)				
		Torque Control Tolerance (Repeatability)		±2 %				
		Soft Start Time Setting		0 to 10 s (Can be set individually for acceleration and deceleration.)				
	Input Signal	Speed Reference Input	Reference Voltage *4	±6 VDC (Variable setting range: ±2 to ±10 VDC) at rated speed (positive rotation with positive reference), input voltage: ±12 V (max.)				
			Input Impedance	Approx. 14 kΩ				
			Circuit Time Constant	Approx. 47 μs				
		Torque Reference Input	Reference Voltage *4	±3 VDC (Variable setting range: ±1 to ±10 VDC) at rated torque (positive torque reference with positive reference), input voltage: ±12 V (max.)				
			Input Impedance	Approx. 14 kΩ				
			Circuit Time Constant	Approx. 47 μs				
		Contact Speed Reference	Rotation Direction Selection	With P control signal				
			Speed Selection	With forward/reverse current limit signal (speed 1 to 3 selection), servomotor stops or another control method is used when both are OFF.				
Position Control Mode	Performance	Bias Setting		0 to 450 min^{-1} (setting resolution: 1 min^{-1})				
		Feed-forward Compensation		0 to 100% (setting resolution: 1%)				
		Positioning Completed Width Setting		0 to 250 reference units (setting resolution: 1 reference unit)				
	Input Signals	Reference Pulse	Type	Sign + pulse train, 90 ° phase difference 2-phase pulse (phase A + phase B), or CCW + CW pulse train				
			Form	Line driver (+5 V level), open collector (+5 V or +12 V level)				
			Frequency	500/200 kpps max. (line driver/open collector)				
		Control Signal		Clear signal (input pulse form identical to reference pulse)				
		Built-in Open Collector Power Supply*5		+12 V (1-kΩ resistor built-in)				

Table 7.5 SERVOPACK Ratings and Specifications (cont'd)

SERVOPACK Model SGDH-			400 V Series				
			2BDE	3ZDE	3GDE	4EDE	5EDE
I/O Signals	Position Output	Form	Phase-A, -B, and -C line driver Phase-S line driver (only with an absolute encoder)				
		Frequency Dividing Ratio	Any				
	Sequence Input	Signal allocation can be modified.	Servo ON, P control (or Control Mode switching, forward/reverse motor rotation by internal speed setting, zero clamping, reference pulse prohibited), forward run prohibited (P-OT), reverse run prohibited (N-OT), alarm reset, forward current limit and reverse current limit (or internal speed selection)				
	Sequence Output	Fixed Output	Servo alarm, 3-bit alarm codes				
		Signal allocation can be modified.	Select three signals among the following: positioning complete (speed agree), servomotor rotation, servo ready, current limit, speed limit, brake release, warning, and NEAR signals.				
Built-in Functions	Dynamic Brake (DB)		Operated at main power OFF, servo alarm, servo OFF or overtravel.				
	Regenerative Processing		Incorporated. External regenerative resistor must be mounted.				
	Overtravel Prevention (OT)		Dynamic brake stop at P-OT or N-OT, deceleration to a stop, or free run to a stop				
	Electronic Gear		$0.01 \leq B/A \leq 100$				
	Protection		Overcurrent, overvoltage, low voltage, overload, regeneration error, main circuit voltage error, heat sink overheated, no power supply, overflow, overspeed, encoder error, overrun, CPU error, parameter error, etc.				
	LED Display		Charge, Power, five 7-segment LEDs (built-in Digital Operator functions)				
	Analog Monitor (CN5)		Analog monitor connector built in for monitoring speed, torque and other reference signals. Speed: 1 V/1000 min^{-1} Torque: 1 V/rated torque Pulses remaining: 0.05 V/1 reference unit or 0.05 V/100 reference units				
	Communications	Interface	Digital Operator (hand-held model), RS-422A port such as for a personal computer (RS-232C ports under certain conditions)				
		1:N Communications	Up to N = 14 for RS-422A ports				
		Axis Address Setting	Set with parameters.				
		Functions	Status display, parameter setting, monitor display, alarm trace-back display, JOG and auto-tuning operations, speed, torque reference signal and other drawing functions.				
	Others		Reverse rotation connection, zero point search, automatic servomotor ID, DC reactor connection terminal for high power supply frequency control				

* 1. Supply voltage must not exceed the following values. Otherwise, SERVOPACK may malfunction. If the voltage exceeds these values, use a step-down transformer so that the voltage will be within the specified range.
SERVOPACK for 400 V: 528 Vrms (max.)

* 2. Use the SERVOPACK within the ambient temperature range. When enclosed in a box, internal temperatures must not exceed the ambient temperature range.

* 3. Speed regulation is defined as follows:

$$\text{Speed regulation} = \frac{\text{No-load motor speed - Total load motor speed}}{\text{Rated motor speed}} \times 100\%$$

The motor speed may change due to voltage variations or amplifier drift and changes in processing resistance due to temperature variation. The ratio of speed changes to the rated speed represent speed regulation due to voltage and temperature variations.

* 4. Forward is clockwise viewed from the non-load side of the servomotor. (Counterclockwise viewed from the load and shaft end.)

* 5. The built-in open collector power supply is not electrically insulated from the control circuit in the SERVOPACK.

7.3.3 Overload Characteristics

SERVOPACKs have a built-in overload protective function that protects the SERVOPACKs and servomotors from overload. Allowable power for the SERVOPACKs is limited by the overload protective function as shown in the figure below.

The overload detection level is set under hot start[1] conditions at a servomotor ambient temperature of 40 °C (104 °F).

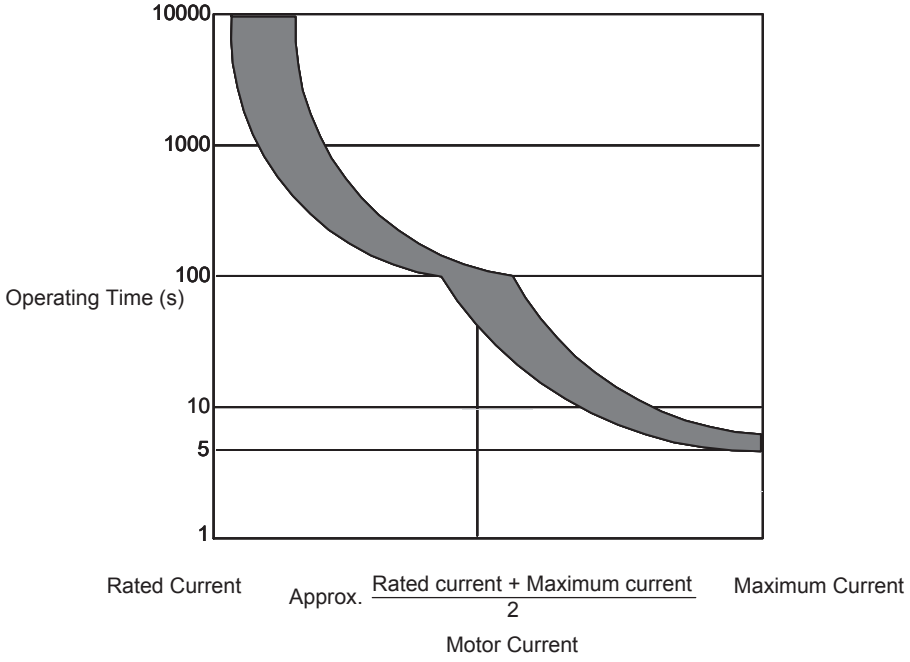


Fig. 7.1 Overload Characteristics

TERMS

[1] Hot Start

A hot start indicates that both the SERVOPACK and the servomotor have run long enough at the rated load to be thermally saturated.

7.3.4 Starting and Stopping Time

The motor starting time (tr) and stopping time (tf) under a constant load are calculated using the following formulas. Motor viscous torque and friction torque are ignored.

Starting time: $$tr = \frac{2\pi \cdot N_M (J_M + J_L)}{60 \cdot (T_{PM} - T_L)} [s]$$

Stopping time: $$tf = \frac{2\pi \cdot N_M (J_M + J_L)}{60 \cdot (T_{PM} - T_L)} [s]$$

N_M: Rated motor speed (min^{-1})

J_M: Motor rotor moment of inertia ($kg \cdot m^2$)

J_L: Load converted to shaft moment of inertia ($kg \cdot m^2$)

T_{PM}: Instantaneous peak motor torque when combined with a SERVOPACK (N·m)

T_L: Load torque (N·m)

Calculate the torque from the motor current using servomotor torque constant × motor current (effective value).

Fig.7.2 shows the motor torque and motor speed timing chart.

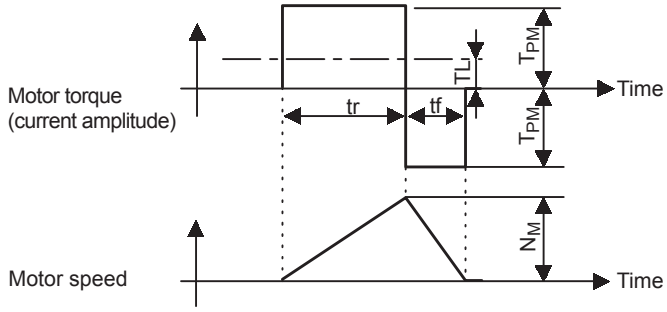


Fig. 7.2 Motor Torque (Current Amplitude) and Motor Speed Timing Chart

7.3.5 Load Moment of Inertia

The larger the load moment of inertia, the worse the movement response of the load. The size of the load moment of inertia (J_L) allowable when using a servomotor is limited to within 5 times the moment of inertia (J_M).

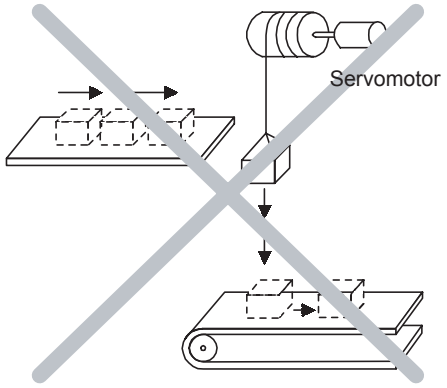
If the load moment of inertia exceeds five times the motor moment of inertia, an overvoltage alarm may arise during deceleration. Take one of the steps below if this occurs.

- Reduce the torque limit.
- Reduce the deceleration rate.
- Reduce the maximum motor speed.
- Consult your Yaskawa representative if the alarm cannot be cleared.

7.3.6 Overhanging Load

A servomotor may not be operated with an overheating load, i.e., a load which tends to continuously rotate the motor. *Fig.7.3* shows a typical example of such a load.

• Vertical Axis Motor Drive without Counterweight



• Feeding Motor Drive

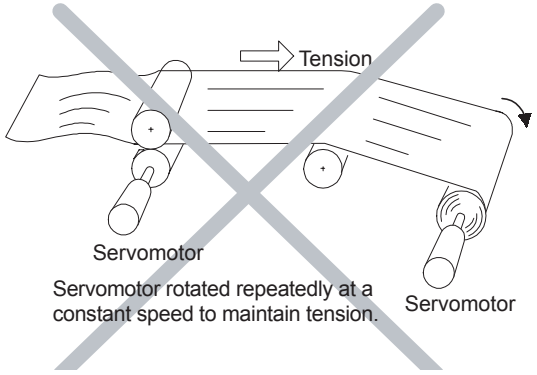


Fig. 7.3 Examples of Overhanging Loads

IMPORTANT

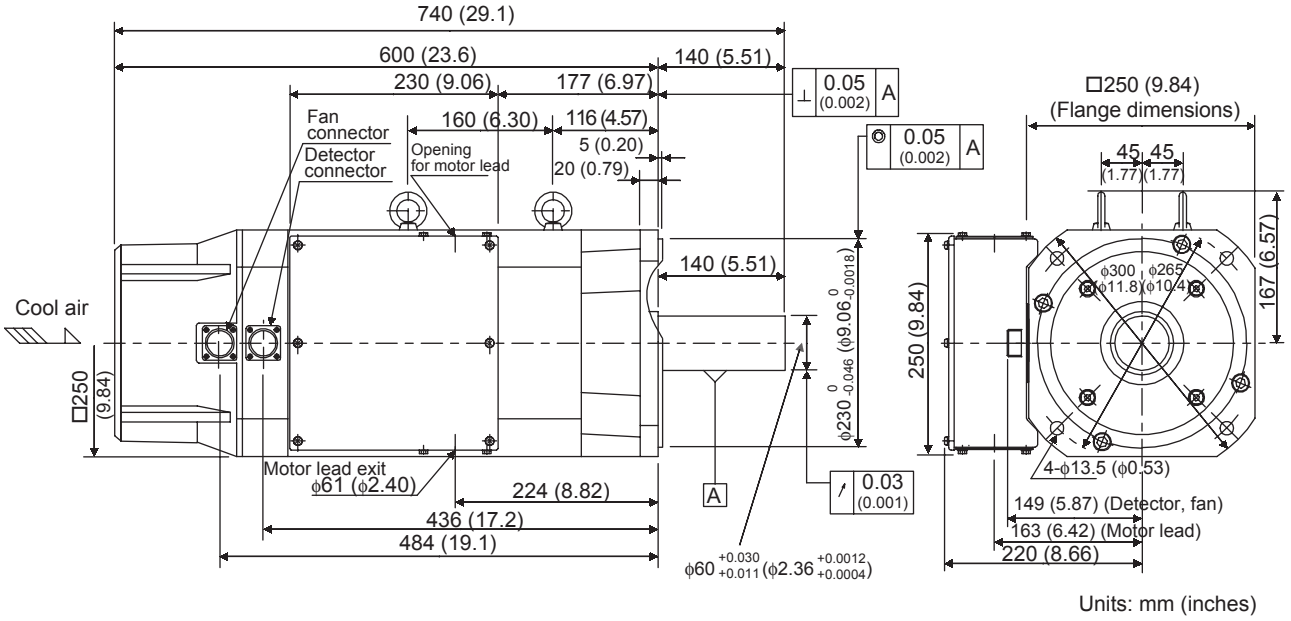
Doing so will cause the SERVOPACK's regenerative brake to be applied continuously and the regenerative energy of the load may exceed the allowable range causing damage to the SERVOPACK. The regenerative brake capacity of the SGDH SERVOPACKs is rated for short-term operation approximately equivalent to the time it takes to decelerate to a stop.

7.4 Servodrive Dimensional Drawings

This section provides dimensional drawings for the servomotor and SERVOPACK.

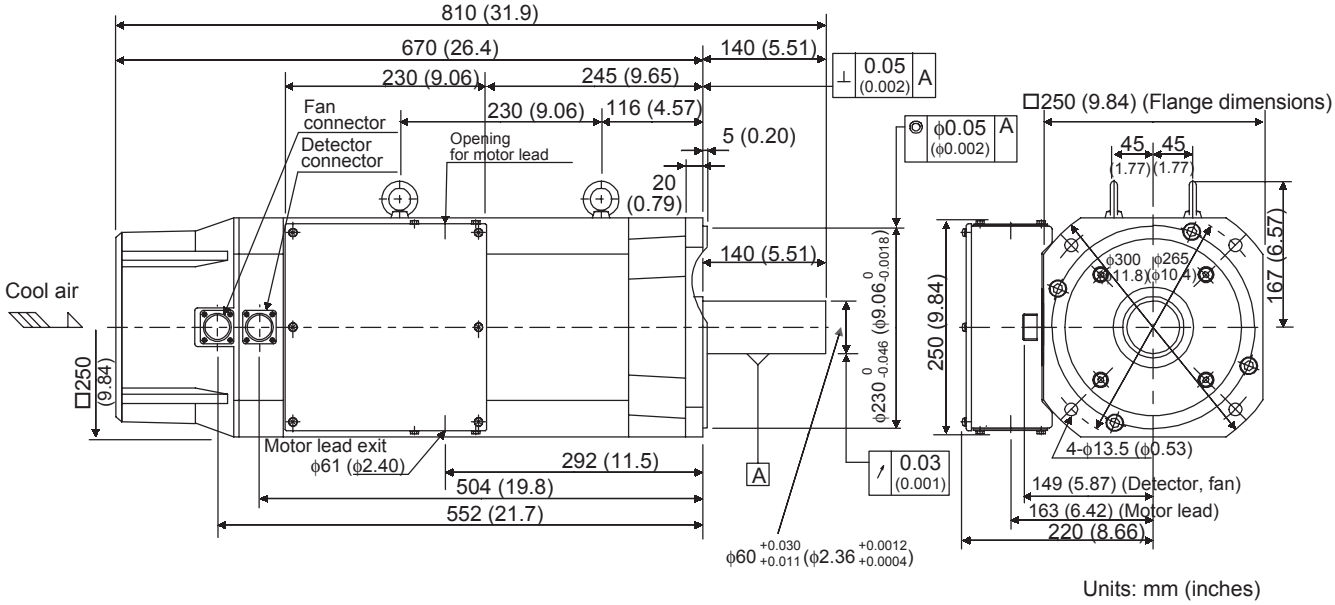
7.4.1 Servomotors

■ SGMBH-2BD□A Servomotors



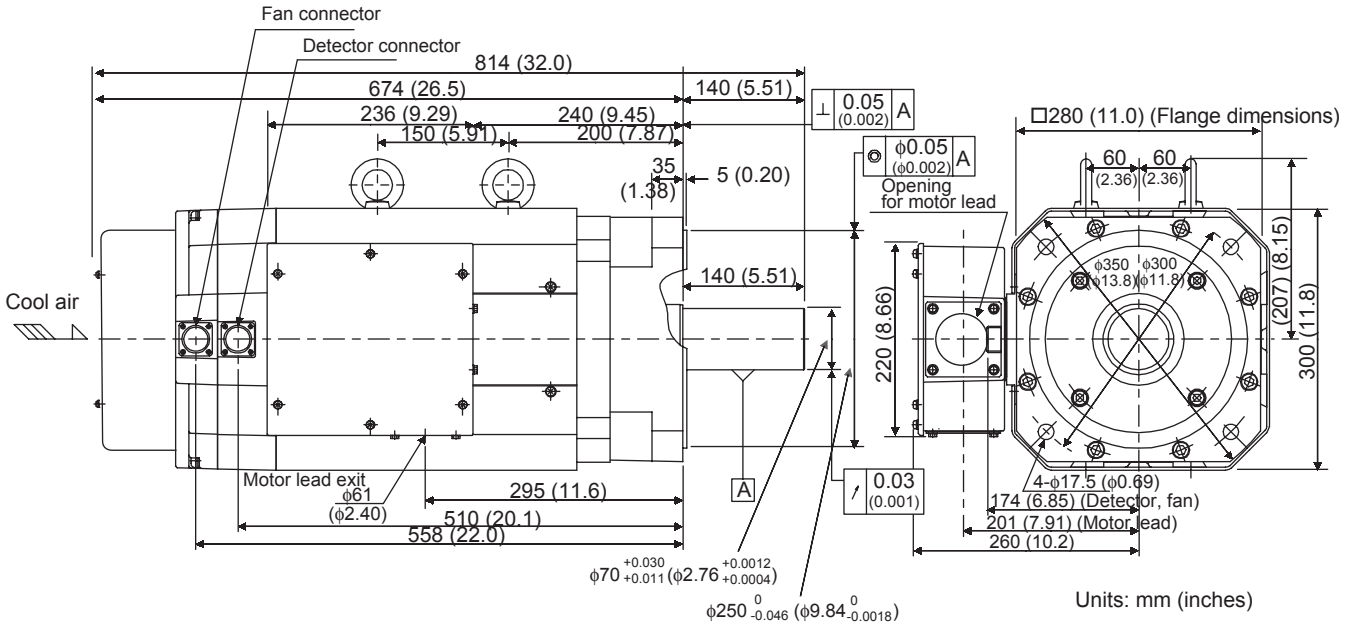
Units: mm (inches)

■ SGMBH-3ZD□A Servomotors

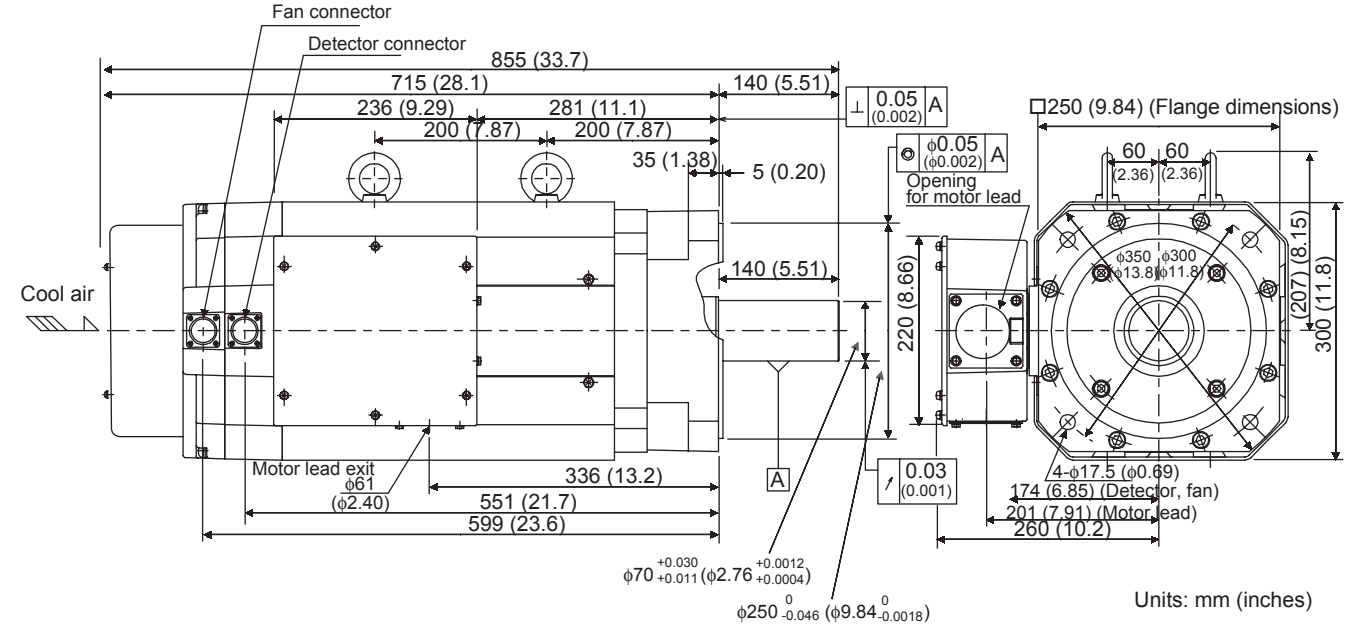


Units: mm (inches)

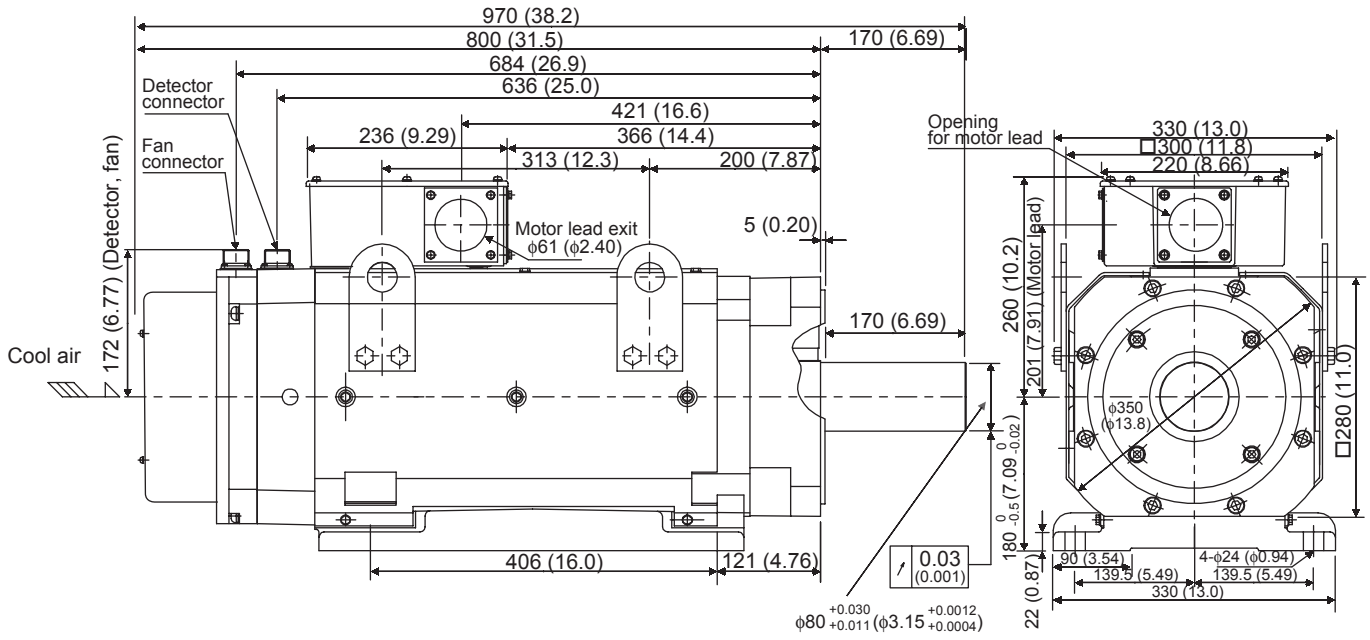
■ SGMBH-3GD□A Servomotors



■ SGMBH-4ED□A Servomotors



■ SGMBH-5ED□A Servomotors

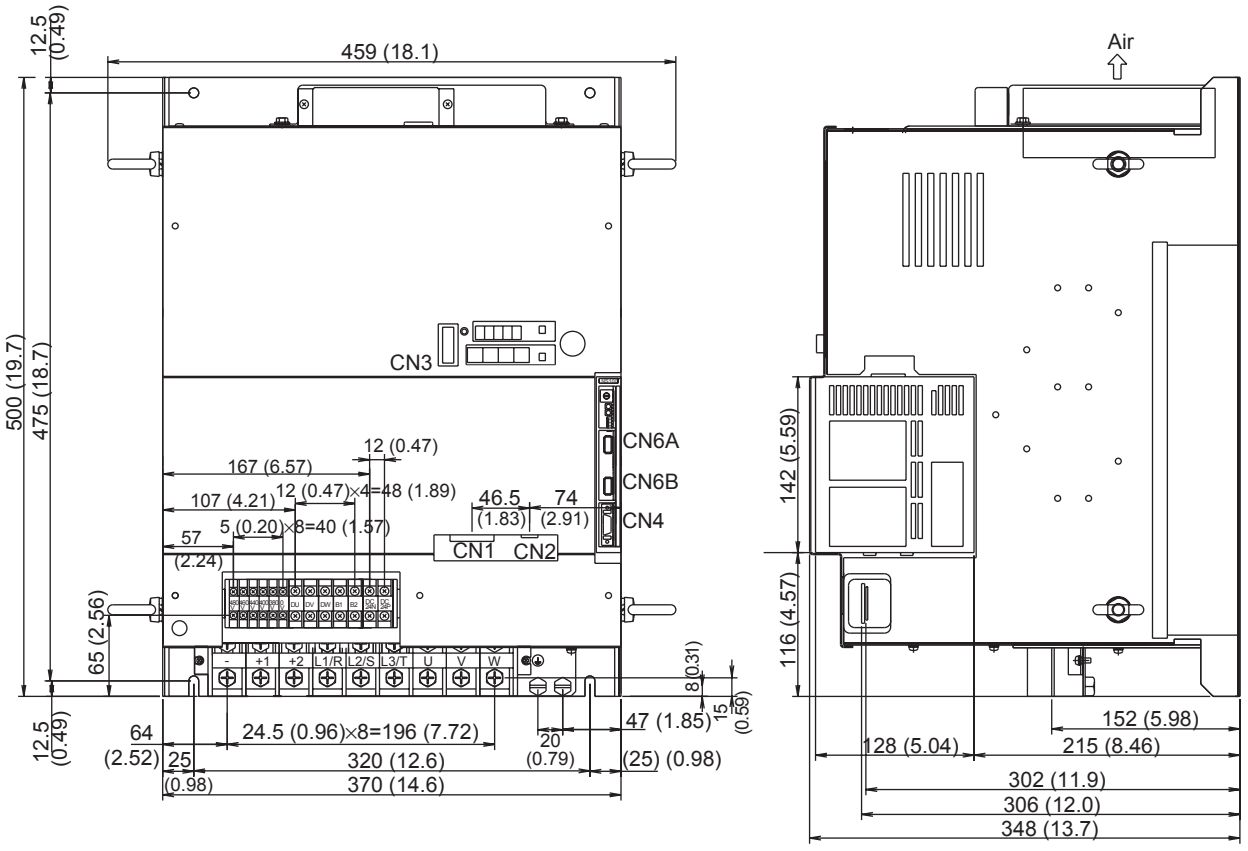


Units: mm (inches)

7

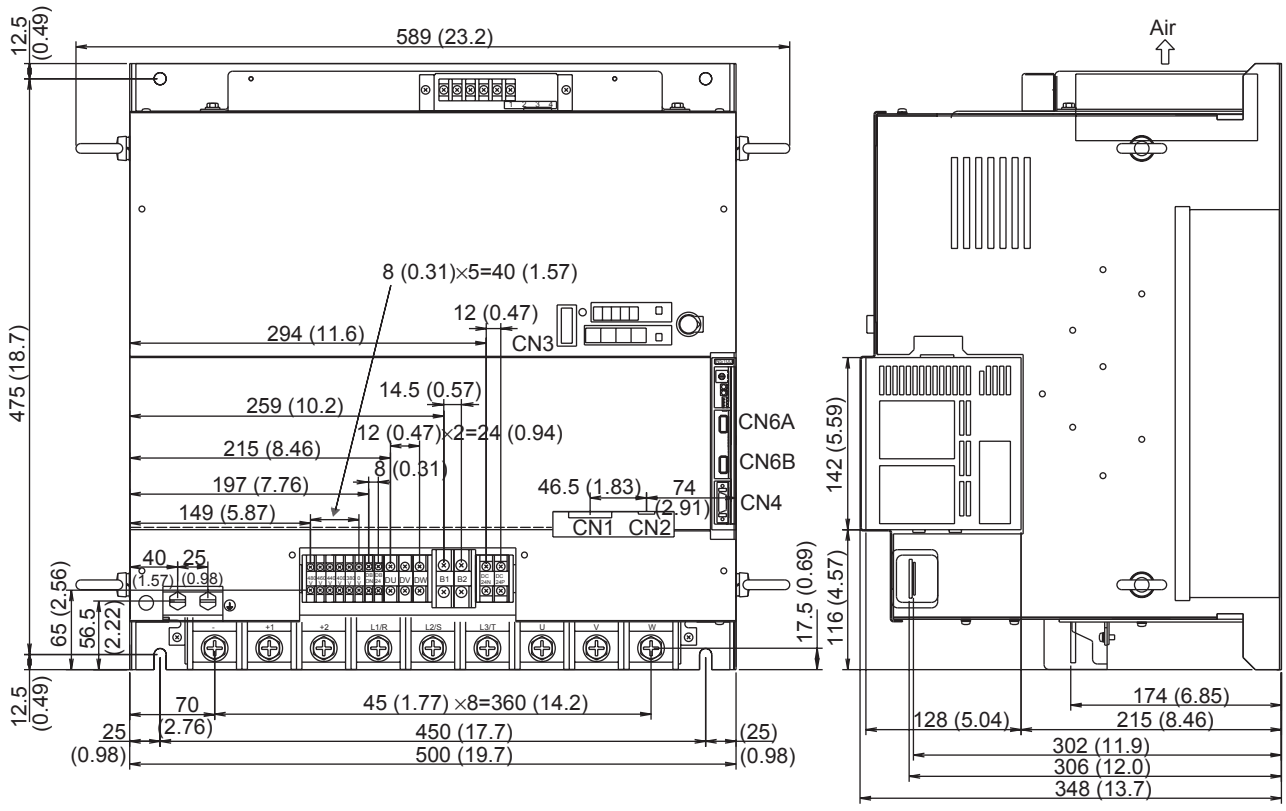
7.4.2 SERVOPACKs

■ SGDH-2BDE (Single-phase 480 V, 22 kW),
SGDH-3ZDE (Single-phase 480 V, 30 kW)



Units: mm (inches)
Approx. mass: 40 kg (88.2 lbs)

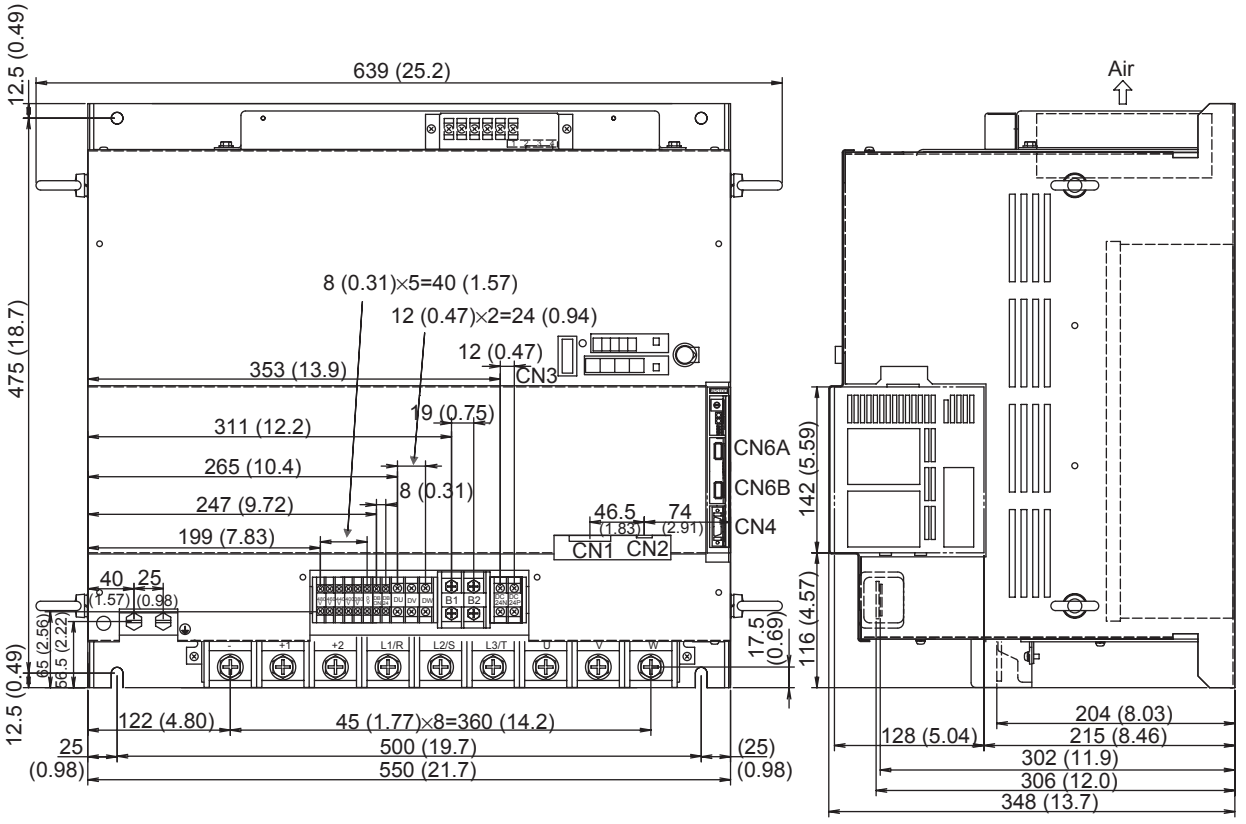
■ SGDH-3GDE (Single-phase 480 V, 37 kW)



Units: mm (inches)
Approx. mass: 60 kg (132 lbs)

7

■ SGDH-4EDE (Single-phase 480 V, 45 kW), SGDH-5EDE (Single-phase 480 V, 55 kW)



Units: mm (inches)
Approx. mass: 65 kg (143 lbs)

7.5 Specifications and Dimensional Drawings for Peripheral Devices

This section provides specifications and dimensional drawings for peripheral devices required in a Σ-II Series Servo System.

7.5.1 Cable Specifications and Peripheral Devices

Ratings and specifications for peripheral devices as well as cable specifications for SERVOPACKs are summarized in *Table7.6* to *Table7.9*.

⚠ CAUTION

Wiring Precautions

- Do not bundle or run power and signal lines together in the same duct.
  Keep power and signal lines at least 30 cm (11.81 in) apart.
- Use twisted-pair wires or multi-core shielded-pair wires for signal and encoder (PG) feedback lines.
- The Maximum lengths for signal lines are as follows:
  - Maximum of 3 m (9.84 ft) for reference input lines.
  - Maximum of 20 m (65.6 ft) for PG feedback lines.

■ Cable Specifications

Table7.6 and *Table7.7* provide wire size specifications for servomotors and SERVOPACKs.

Table 7.6 SERVOPACK Wire Sizes

External Terminal Name		Terminal Symbol	Wire Size Examples [mm^2 (in^2)]				
			SERVOPACK Model SGDH-				
			2BDE	3ZDE	3GDE	4EDE	5EDE
Online Terminals	Main Power Input Terminals	L1/R, L2/S, L3/T, ⏚	HIV 14 (0.022) min.	HIV 14 (0.022) min.	HIV 22 (0.034) min.	HIV 30 (0.047) min.	HIV 38 (0.059) min.
	Servomotor Connection Terminals	U, V, W, ⏚	HIV 14 (0.022) min.	HIV 22 (0.034) min.	HIV 30 (0.047) min.	HIV 38 (0.059) min.	HIV 50 (0.078) min.
	Control Power Input Terminal	DC24P, DC24N	HIV 1.25 (0.002) min.				
	Regenerative Resistor Terminal	B1, B2	HIV 2.0 (0.003) min.				HIV 3.5 (0.0054) min.
	Input Terminals for Actuator Control	0 V, 380 V, 400 V, 440 V, 460 V, 480 V	HIV 1.25 (0.002) min.				
	Dynamic Brake Unit Connection Terminal	DU, DV, DW	HIV 1.25 (0.002) min.				HIV 2.0 (0.003) min.
		DBON, DB24	HIV 1.25 (0.002) min.				
Offline Terminals	Control I/O Signal Connector	1CN	Twisted-pair or shielded twisted-pair wires Core wire at least 0.12 mm^2 (0.0002 in^2), tinned, annealed copper twisted wires. Finished cable dimension: max.ϕ16mm (0.63 in) for CN1 and max. ϕ11 (0.43 in) for CN2.				
	PG Signal Connector	2CN					

Table 7.7 Servomotor Wire Sizes

External Terminal Name		Terminal Symbol	Wire Size Examples [mm^2 (in^2)]				
			SERVOPACK Model SGDH-				
			2BDE	3ZDE	3GDE	4EDE	5EDE
Offline Terminals	Fan Terminals	U (A), V (B), W (C)	HIV 1.25 (0.002) min.				
	Brake Power Supply Connection Terminals (for servomotor with brake only)	A, B					
	Thermal Protector Terminals	1, 1b					

Note: 1. Wire sizes were selected for three cables per bundle at 40°C ambient temperature with the rated current.
2. Use cable with a minimum withstand voltage of 600 V for main circuits.
3. If cables are bundled in PVC or metal ducts, consider the reduction ratio of the allowable current.
4. Use heat-resistant cable under high ambient or panel temperatures where normal vinyl cable will rapidly deteriorate.

The following table shows types of cables and must be used in conjunction with *Table7.6* and *Table7.7*.

Cable Types		Allowable Conductor Temperature °C
Symbol	Name	
PVC	Normal vinyl cable	-
IV	600-V vinyl cable	60
HIV	Temperature-resistant vinyl cable	75

Note: 1. Use cable with a minimum withstand voltage of 600 V for main circuits.
2. If cables are bundled in PVC or metal ducts, consider the reduction ratio of the allowable current.
3. Use heat-resistant cable under high ambient or panel temperatures where normal vinyl cable will rapidly deteriorate.

■ Peripheral Device Types and Capacities

Table7.8 shows SERVOPACK peripheral device types and capacities.

Table 7.8 Peripheral Device Types and Capacities

SERVOPACK Model SGDH-	Applicable Servomotor Model SGMBH-	Power Supply Capacity*4 kVA	Molded-case Circuit Breaker (MCCB) or Fuse Capacity *1 A	Main Power Inrush Current (peak value) A	Recommended Line Filter*2	Magnetic Contactor*3
2BDE	2BD□A	36.7	100	162	FN258L-75-34	HI-65J (65 A)
3ZDE	3ZD□A	50.1	150	650	FN258L-100-35	HI-80J (80 A)
3GDE	3GD□A	61.8	150	650	FN258L-130-35	HI-80J (80 A)
4EDE	4ED□A	75.2	225	1300	FN258L-180-07	HI-125J (125 A)
5EDE	5ED□A	91.9	225	1300	FN258L-180-07	HI-125J (125 A)

* 1. Braking characteristics at 25°C: 200% for 2 s min., 700% for 0.01 s min.
* 2. Manufactured by SCHAFFNER. (Available from Yaskawa Controls Co., Ltd.)
* 3. Manufactured by Yaskawa Controls Co., Ltd.
* 4. The supply voltage capacity shown is the value for a rated load.

Table7.9 shows appropriate cables for CN1 and CN2 SERVOPACK connectors.

Wire sizes were selected for three cables per bundle at 40°C ambient temperature with the rated current.

Table 7.9 Cables for CN1 and CN2 Connectors

Control I/O Signal Connector	CN1	Cable	Use twisted-pair or shielded twisted-pair wire.
		Applicable wire	AWG24, 26, 28, 30
		Finished cable dimension	ϕ16.0 mm (0.63 in) max.
PG Signal Connector	CN2	Cable	Use Yaskawa cable, or shielded twisted-pair wire if Yaskawa cable is not used.
		Applicable wire	AWG24, 26, 28, 30 Use AWG22 (0.33 mm^2 (0.001 in^2)) for the encoder power supply and FG line, and AWG26 (0.12 mm^2 (0.0002 in^2)) for other signals. These conditions permit wiring distances up to 20 m (65.6 ft).
		Finished cable dimension	ϕ6.8 mm (0.27 in) max.

7.5.2 Digital Operator

The SGDH SERVOPACK has Digital Operator functions built in, but a hand-held Digital Operator can be connected to the SERVOPACK just as with conventional Σ-Series SERVOPACKs.

The cable section specifications are different from those of conventional hand-held Digital Operators (JUSP-OP02A-1). A conventional unit can be used simply by replacing the cable section.

Fig.7.4 shows the Digital Operator (unit + cable) and cable configuration.

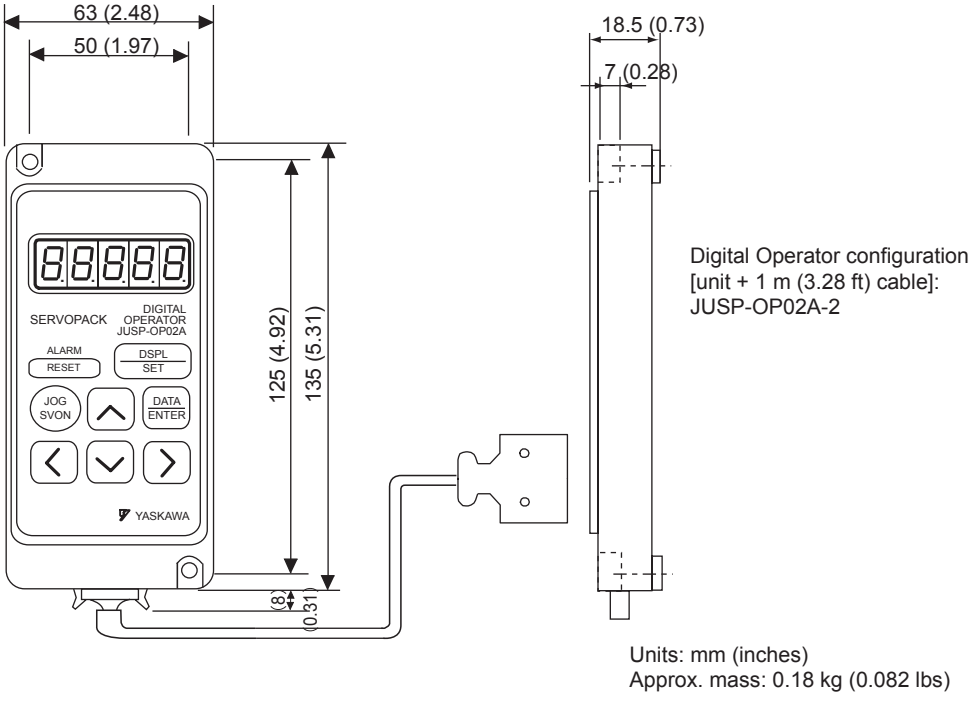


Fig. 7.4 Digital Operator

7.5.3 CN1 Connector

CN1 connectors are required to connect the host controller to CN1 of the SERVOPACK. CN1 connectors are comprised of a connector and a case.

The following section provides types and dimensional drawings for CN1.

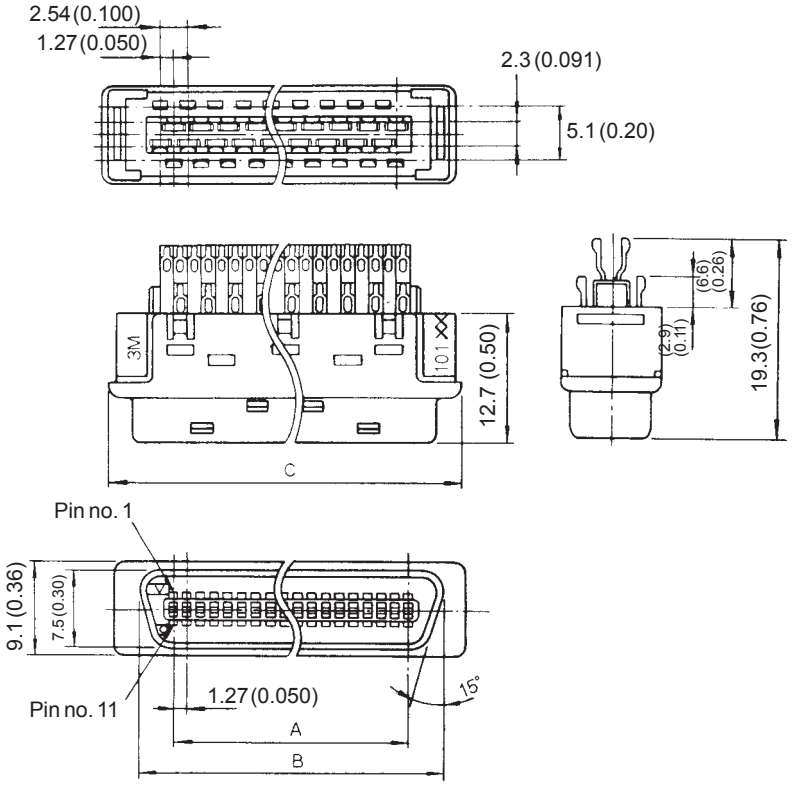
■ Configuration

Connector Model	Application	Connector Part List			
		Connector		Case	
		Model	Qty	Model	Qty
JZSP-CKI9	I/O connector for CN1	10150-3000VE*	1	10350-52A0-008*	1

* Manufactured by Sumitomo 3M Co.

■ Dimensional Drawings

• Connector

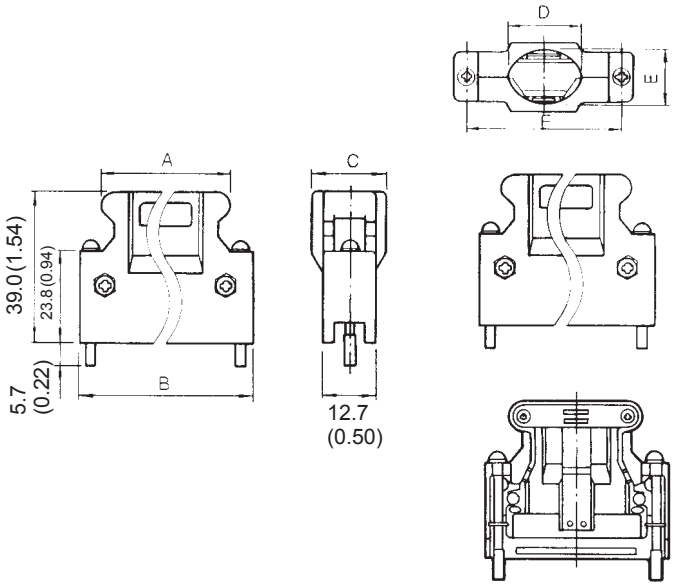


Unit: mm (in)

Connector Model	A	B	C
10150-3000VE	30.48 (1.20)	36.7 (1.44)	41.1 (1.62)

Manufactured by Sumitomo 3M Co.

• Case



Assembly Diagram

Unit: mm (in)

Connector Model	Case Model	A	B	C	D	E	F
10150-3000VE	10350-52A0-008	41.1 (1.62)	52.4 (2.06)	18.0 (0.71)	17.0 (0.67)	14.0 (0.55)	46.5 (1.83)

Manufactured by Sumitomo 3M Co.

7.5.4 Connector Terminal Block Converter Unit

The Connector Terminal Block Converter Unit is comprised of a CN1 connector and cable. The terminal block numbers match CN1 connector numbers on the SERVOPACK-end connector.

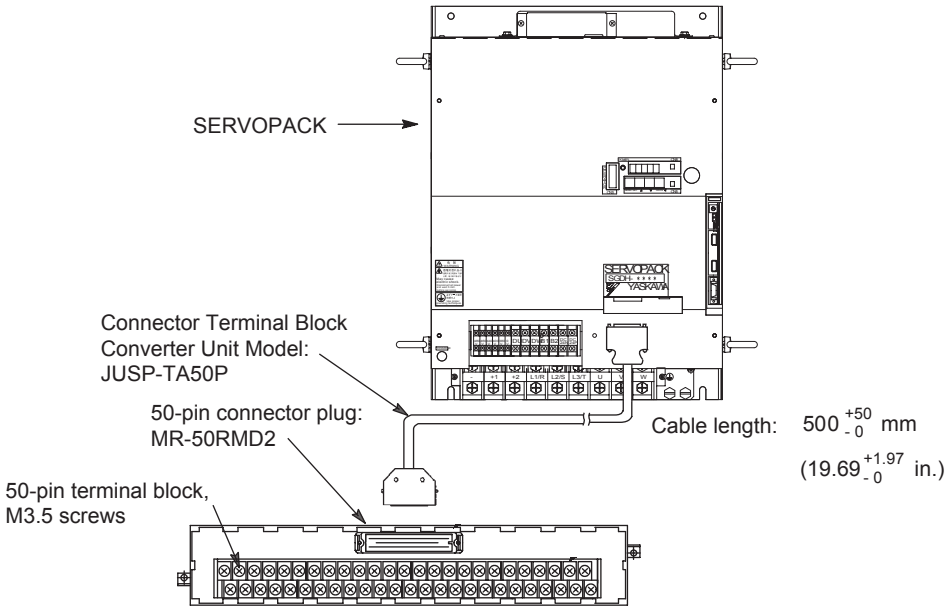


Fig. 7.5 Connector Terminal Block Converter Unit Connected to a SERVOPACK

■ Terminal Block Pin Numbers and Signal Names

Fig.7.6 shows terminal block pin numbers and signal names.

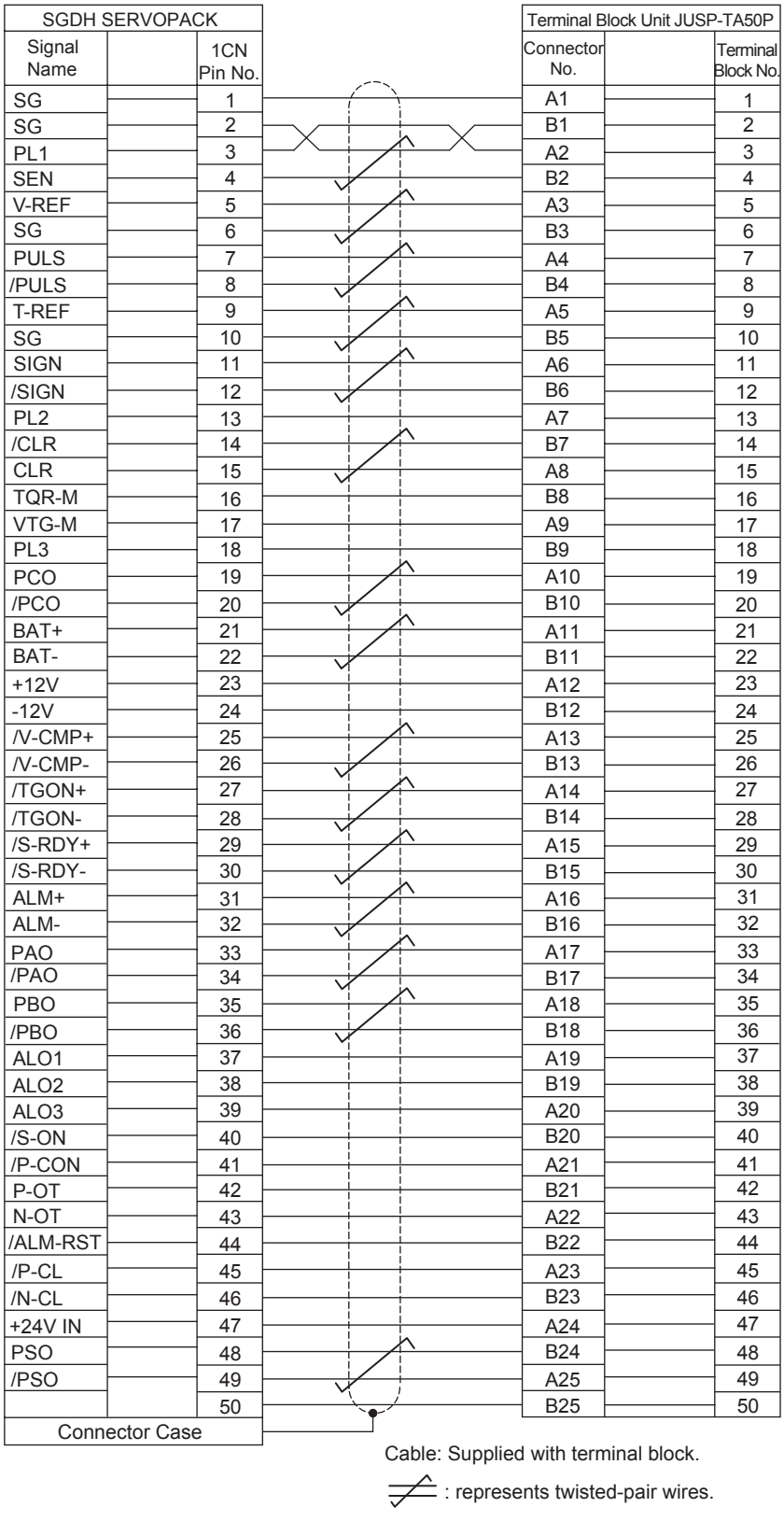
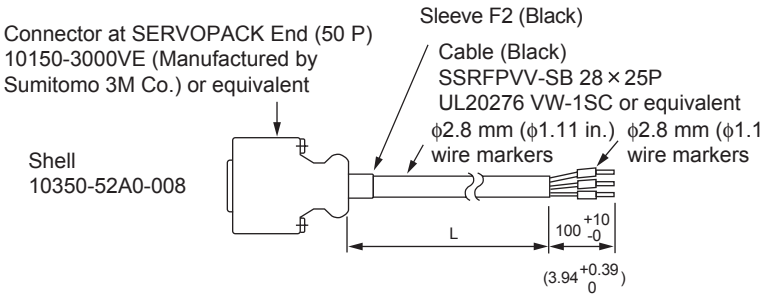
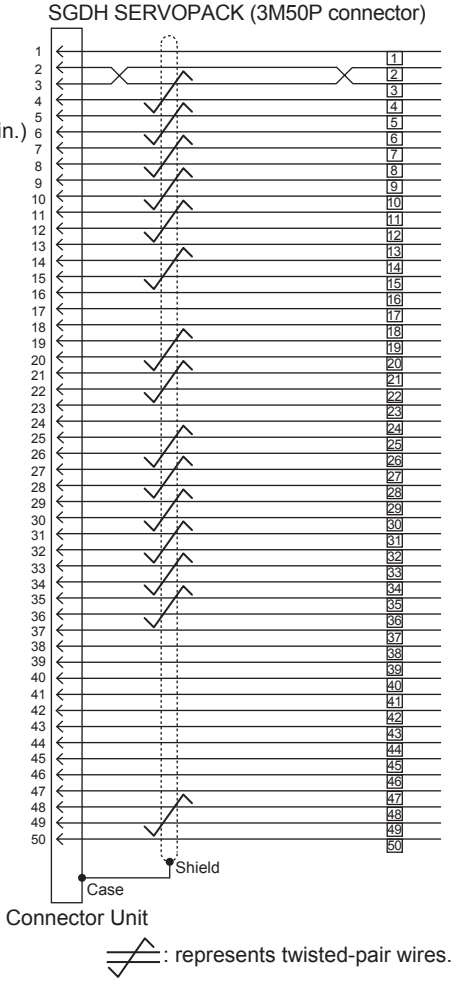


Fig. 7.6 Terminal Block Pin Numbers and Signal Names

7.5.5 Cable With CN1 Connector and One End Without Connector

These cables do not have a host controller connector. The loose leads are labeled with terminal numbers.





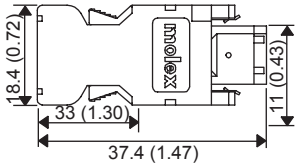
Cable Length

Model	L in mm (feet)
JZSP-CKI01-1	1000 +30 -0 (3.33 +0.1 0)
JZSP-CKI01-2	2000 +50 -0 (6.67 +0.17 0)
JZSP-CKI01-3	3000 +50 -0 (10 +0.17 0)

7.5.6 CN2 Encoder Connector at SERVOPACK

Only one type of CN2 encoder connector is available for the SERVOPACK end of the cable.

- Encoder Connector at SERVOPACK

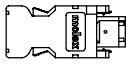


Units: mm (inches)

- Connector Kit

  A connector kit is comprised of an encoder connector (soldered) for the servomotor and SERVOPACK ends of the cable. *Table7.10* shows cable kit models and appearance.

Table 7.10 Connector Kit Types

Type	Connector Kit Model	List of Connector Kit Parts
Plug for a SERVOPACK CN2 encoder connector	JZSP-CMP9-1	

7.5.7 Encoder Cables

Encoder cables are used to connect the SERVOPACK to the encoder mounted to the servomotor.

The following section shows encoder cable models and appearance. Specify the cable model when ordering.

7

Cables With SERVOPACK and Servomotor Connectors

Table7.11 shows cable models.

Table 7.11 Cables With SERVOPACK and Servomotor Connectors

Applicable Servomotors		Cable Model	Length (L)
SGMBH Servomotors	With straight plug	JZSP-CMP01-03	3 m (9.84 ft)
		JZSP-CMP01-05	5 m (16.4ft)
		JZSP-CMP01-10	10 m (32.8 ft)
		JZSP-CMP01-15	15 m (49.2 ft)
		JZSP-CMP01-20	20 m (65.6 ft)
	With L–shape plug	JZSP-CMP02-03	3 m (9.84 ft)
		JZSP-CMP02-05	5 m (16.4 ft)
		JZSP-CMP02-10	10 m (32.8 ft)
		JZSP-CMP02-15	15 m (49.2 ft)
		JZSP-CMP02-20	20 m (65.6 ft)

Fig.7.7 and *Fig.7.8* show cable dimensions.

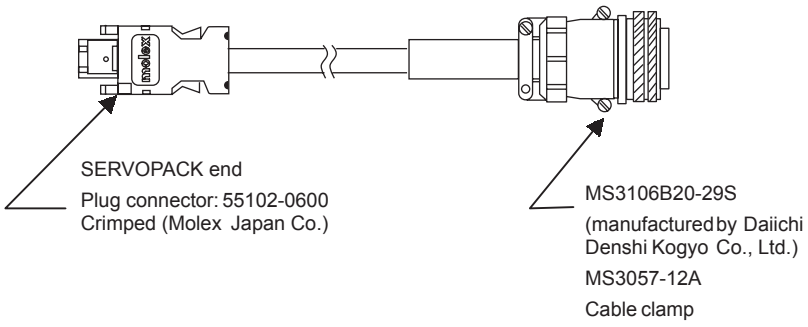


Fig. 7.7 SGMBH Servomotor Cables With Straight Plugs

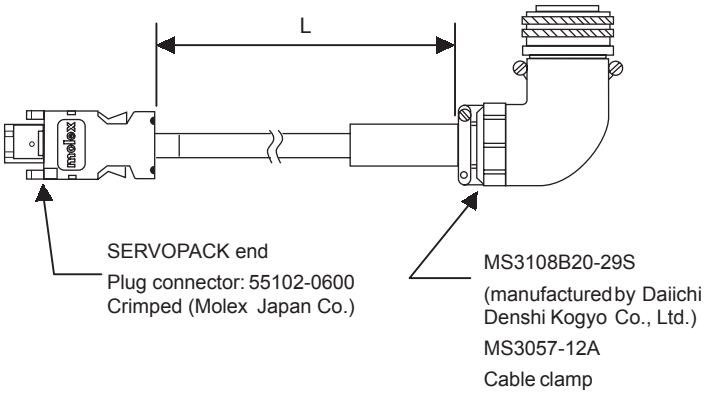


Fig. 7.8 SGMBH Servomotor Cables With L-shaped Plugs

Cables With a SERVOPACK Connector and Encoder Loose Leads

Table7.12 shows cable models.

Table 7.12 Cables With a SERVOPACK Connector and Encoder Loose Leads

Cable Model	Length (L)
JZSP-CMP03-03	3 m (9.84 ft)
JZSP-CMP03-05	5 m (16.4ft)
JZSP-CMP03-10	10 m (32.8 ft)
JZSP-CMP03-15	15 m (49.2 ft)
JZSP-CMP03-20	20 m (65.6 ft)

Fig.7.9 shows cable dimensions.

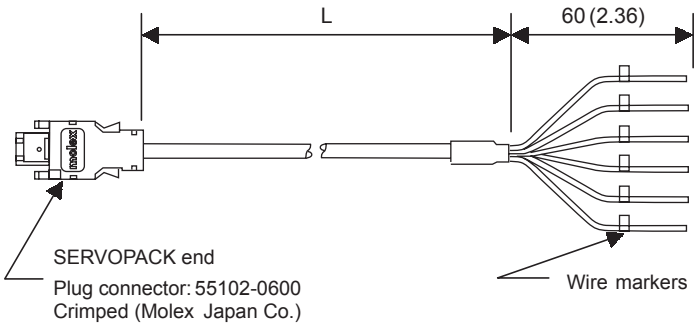


Fig. 7.9 Cables With a SERVOPACK Connector and Encoder Loose Leads

Cable Lines

The following describes models and specifications for encoder cables without connectors. *Table7.13* shows cable models and lengths.

Table 7.13 Cables Without Connectors

Cable Type	Cable Model	Length (L)
A standard encoder cable can be used up to 20 m (65.6 ft).	JZSP-CMP09-05	5 m (16.4 ft)
	JZSP-CMP09-10	10 m (32.8 ft)
	JZSP-CMP09-15	15 m (49.2 ft)
	JZSP-CMP09-20	20 m (65.6 ft)
A 50 m specification encoder cable can be used up to 50 m (164 ft).	JZSP-CMP19-30	30 m (98.4 ft)
	JZSP-CMP19-40	40 m (131 ft)
	JZSP-CMP19-50	50 m (164 ft)

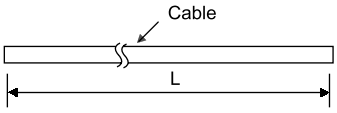
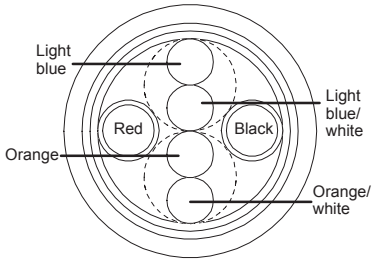
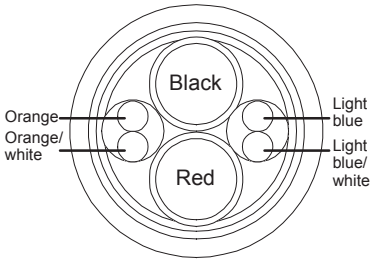


Table7.14 shows specifications for encoder cables without connectors. These cables are not SERVOPACK or servomotor accessories and must be purchased separately.

Table 7.14 Applicable Cable

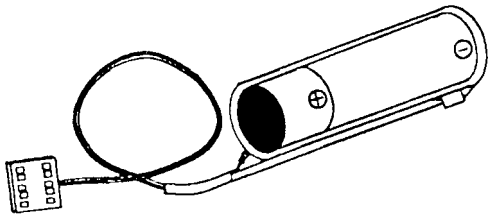
Cable Specifications	Length: 20 m (65.6 ft) max.	Length: 50 m (164 ft) max.
Basic Specifications	T/20276-SB AWG22 × 2C+AWG24 × 2P	T/20276-SB AWG16 × 2C+AWG26 × 2P
Finished Dimensions	ϕ6.5 mm (ϕ0.26 in)	ϕ6.8 mm (ϕ0.27 in)
Internal Configuration and Lead Colors		
Yaskawa Standard Specifications	Standard lengths: 5 m (16.4 ft), 10 m (32.8 ft), 15 m (49.2 ft), 20 m (65.6 ft)	Standard lengths: 30 m (98.4 ft), 40 m (131 ft), 50 m (164 ft)

7.5.8 Absolute Encoder Battery

When the power supply of an absolute encoder is OFF, a data backup battery is required. Customers must purchase one of the absolute encoder batteries below.

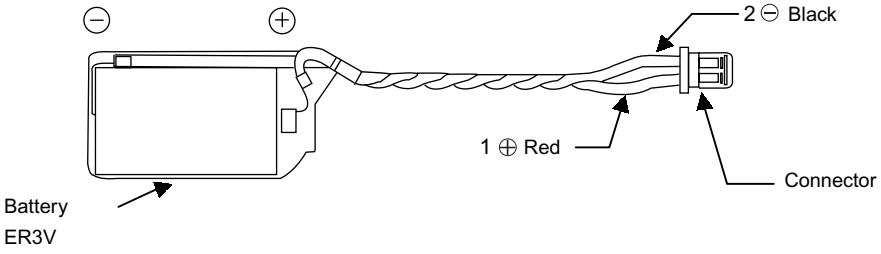
■ Installing the Battery at the Host Device

Model: ER6VC3 (lithium battery)
3.6 V 2000 mAh
Manufactured by Toshiba Battery Co., Ltd.



■ Battery Provided for SERVOPACK

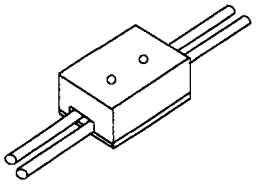
Model: JZSP-BA01 (lithium battery)
(Battery: ER 3 V battery made by Toshiba Battery Co., Ltd.)
3.6 V 1000 mAh



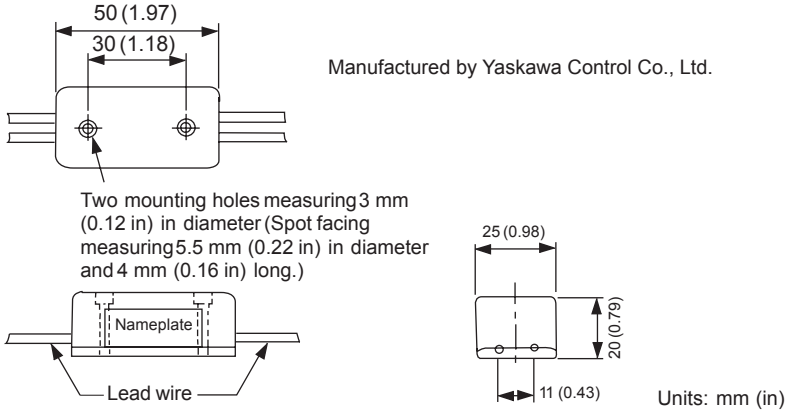
7.5.9 Brake Power Supplies

Brake power supplies are available for 200-V and 100-V inputs for servomotors with brakes.

200 V input: LPSE-2H01
100 V input: LPDE-1H01



■ Dimensional Drawings



■ Specifications

- Lead wire length: About 500 mm (19.69 in) each
- Max. ambient temperature: 60°C
- Lead wires: Color coded

AC Input		Brake End
100 V	200 V	
Blue/White	Yellow/White	Red/Black

■ Internal Circuits

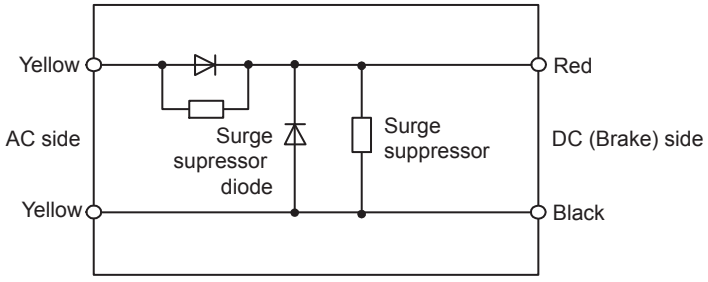
The following shows internal circuits for brake power supplies. While it is possible to switch either the AC or the DC side of the power supplies, it is normally safer to switch the AC side.

IMPORTANT

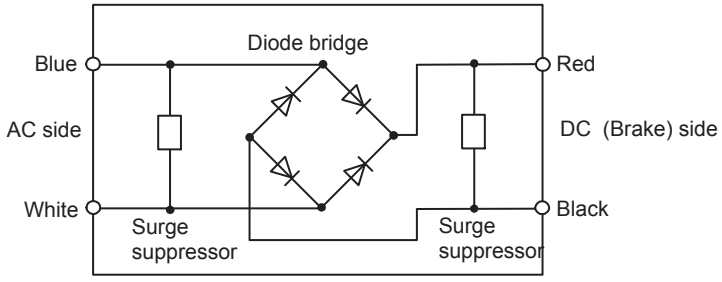
When switching on the DC side, install a surge suppressor near the brake coil to prevent damage to the coil from voltage surges due to DC-side switching.

Brake operation time delay occurs during brake power supply ON/OFF operation. Set output timing of servo OFF operation (motor output stop), referring to *4.4.4 Using the Holding Brake*. Especially, if the AC side of the brake power supply is to be switched, brake operation time is extended.

- Internal Circuit for 200 VAC Input (LPSE-2H01)

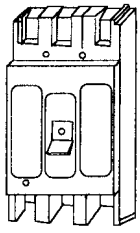


- Internal Circuit for 100 VAC Input (LPDE-1H01)



7.5.10 Molded-case Circuit Breaker (MCCB)

A molded-case circuit breaker is used to protect the power supply line. The customer must provide a molded-case circuit breaker with an appropriate capacity.



• Recommended Product

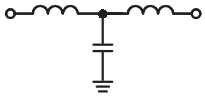
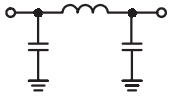
Ground fault detector for servomotor protection manufactured by Mitsubishi Electric Co., Ltd.

Model: MN50-CF

SERVOPACK Model	Power Supply Capacity per SERVOPACK (kVA)	Power Supply Capacity per MCCB or Fuse (A)
SGDH-2BDE	36.7	100
SGDH-3ZDE	50.1	150
SGDH-3GDE	61.8	150
SGDH-4EDE	75.2	225
SGDH-5EDE	91.9	225

7.5.11 Noise Filter

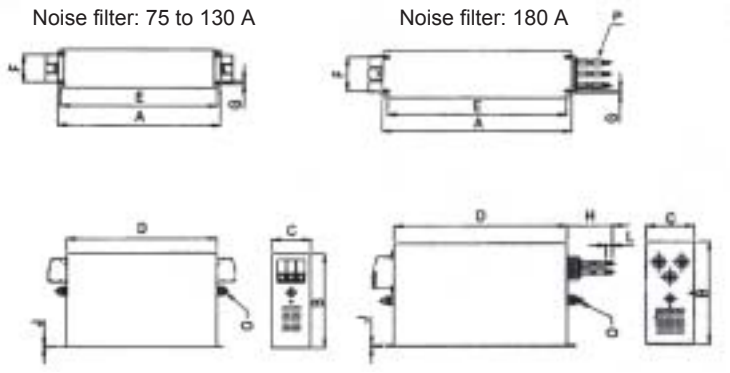
A noise filter is installed to eliminate external noise from the power supply line. Select one of the following noise filters based on SERVOPACK capacity.

SERVOPACK Model	Noise Filter Reference Diagram	Recommended Noise Filter*
SGDH-2BDE	Correct  Incorrect 	FN258L-75-34
SGDH-3ZDE		FN258L-100-35
SGDH-3GDE		FN258L-130-35
SGDH-4EDE		FN258L-180-07
SGDH-5EDE		FN258L-180-07

* Manufactured by SCHAFFNER. (Available from Yaskawa Controls Co., Ltd.)

■ Dimensional Drawing

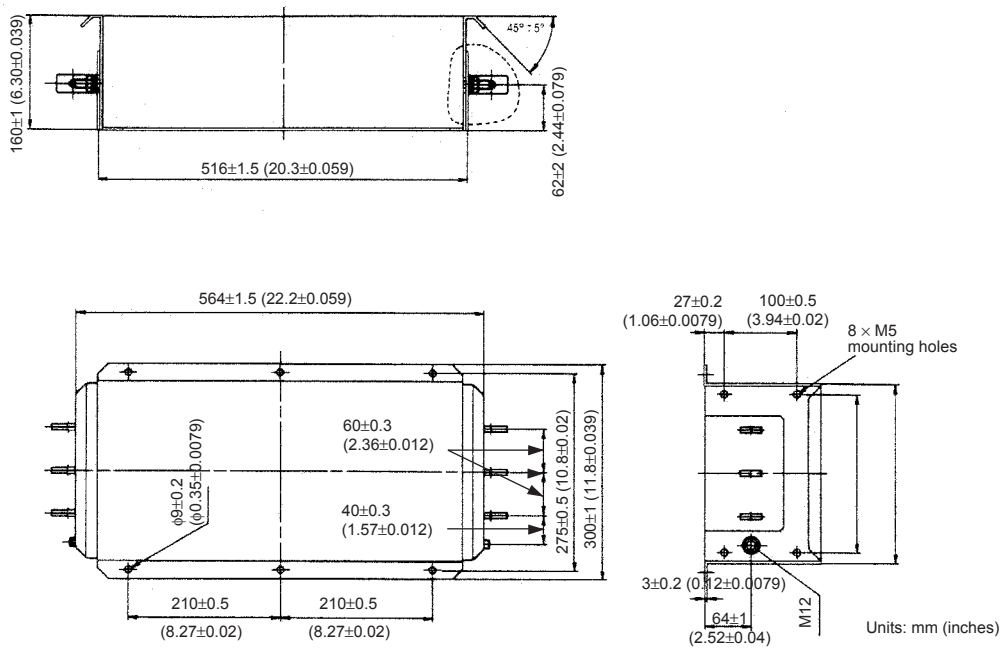
• FN258L



Unit: mm (in)

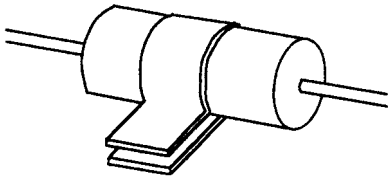
Noise Filter Model	A	B	C	D	E	F	G	H	J	L	O	P
FN258L-75-34	329 (13.0)	220 (8.66)	80 (3.15)	300 (11.8)	314 (12.4)	55 (2.17)	6.5 (0.26)	-	1.5 (0.059)	-	M6	-
FN258L-100-35	379 ± 1.5 (14.9 ± 0.059)	220 (8.66)	90 ± 0.8 (3.54 ± 0.031)	350 ± 1.2 (13.8 ± 0.047)	364 (14.3)	65 (2.56)	6.5 (0.26)	-	1.5 (0.059)	-	M10	-
FN258L-130-35	439 ± 1.5 (17.3 ± 0.059)	240 (9.44)	110± 0.8 (4.33 ± 0.031)	400± 1.2 (15.7 ± 0.047)	414 (16.3)	80 (3.15)	6.5 (0.26)	-	3 (0.12)	-	M10	-
FN258L-180-07	438± 1.5 (17.2 ± 0.059)	240 (9.44)	110± 0.8 (4.33 ± 0.031)	400± 1.2 (15.7 ± 0.047)	413 (16.3)	80 (3.15)	6.5 (0.26)	500 (19.7)	4 (0.16)	15 (0.59)	M10	50 (mm^2)

• FN359



7.5.12 Surge Suppressor

Attach a surge suppressor to the magnetic contactor to prevent power supply noise and protect contacts.



• Recommended Product

Spark Killer manufactured by Okaya electric Industries Co., Ltd.
Model: CR50500BA (250 VAC)
Capacitance: 0.5 µF± 20%
Resistance: 50 Ω (1/2W) ± 30%
(Available from Yaskawa Controls Co., Ltd.)

7.5.13 Regenerative Resistor Unit

Regenerative resistors for processing regenerative energy are externally mounted on SERVOPACKs.

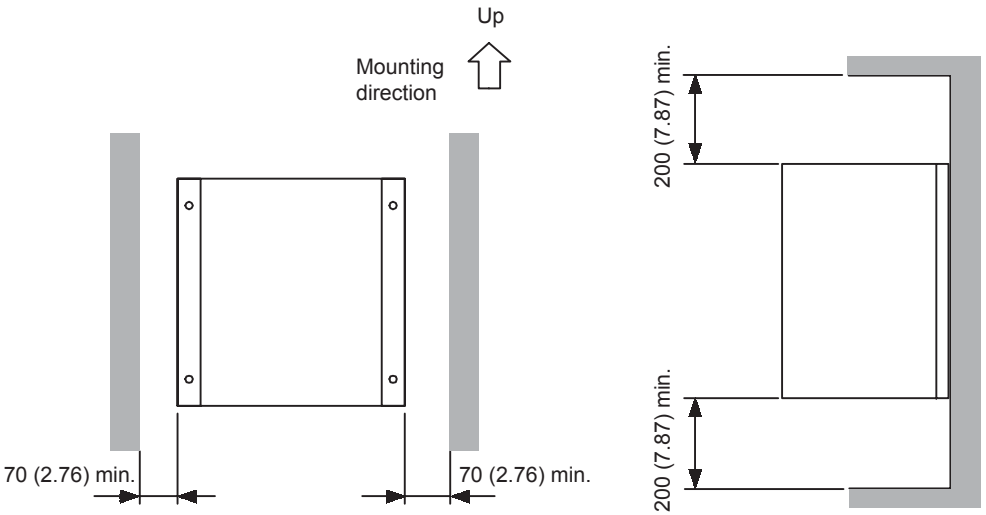
■ Specifications

The following Regenerative Resistor Units are required according to the SERVOPACK model.

SERVOPACK Model SGDH-	2BDE	3ZDE	3GDE	4EDE	5EDE
Regenerative Resistor Unit JUSP-	RA12	RA13	RA14	RA15	RA16
Resistance (Ω)	9	6.7	5	4	3.8
Resistance Capacity (W)	3600	3600	4800	6000	7200
Allowable Load Moment of Inertia	5 times the load moment of inertia				
Allowable Duty	2 % ED at maximum speed ad torque deceleration.				

■ Mounting

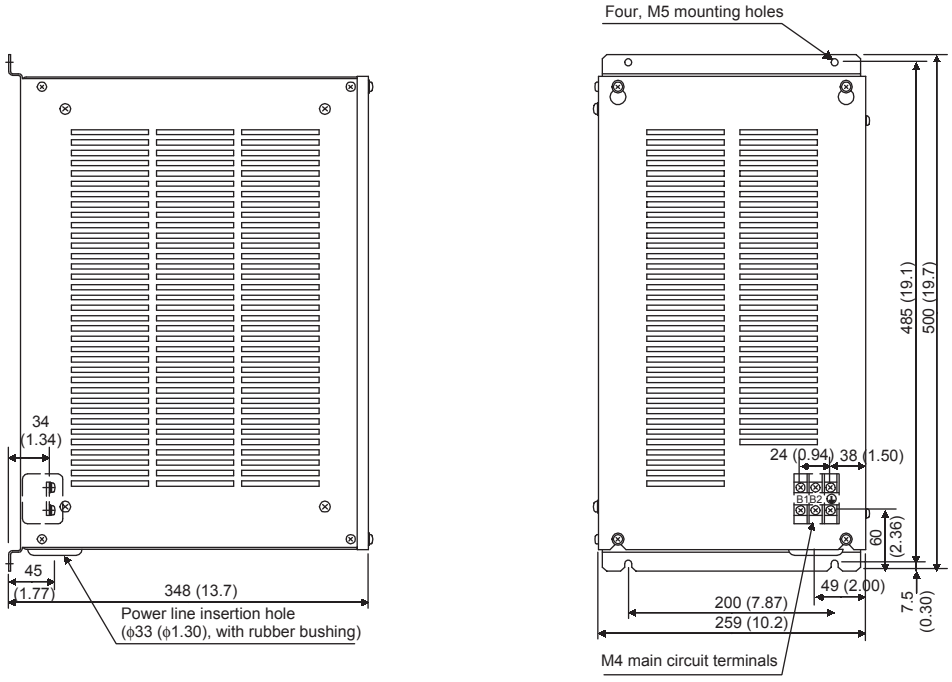
When mounting the Unit, provide sufficient space between the Unit and any devices beside it, as shown in the following diagram.



Units: mm (inches)
Approx. mass: 14.0 kg (30.9 lb)

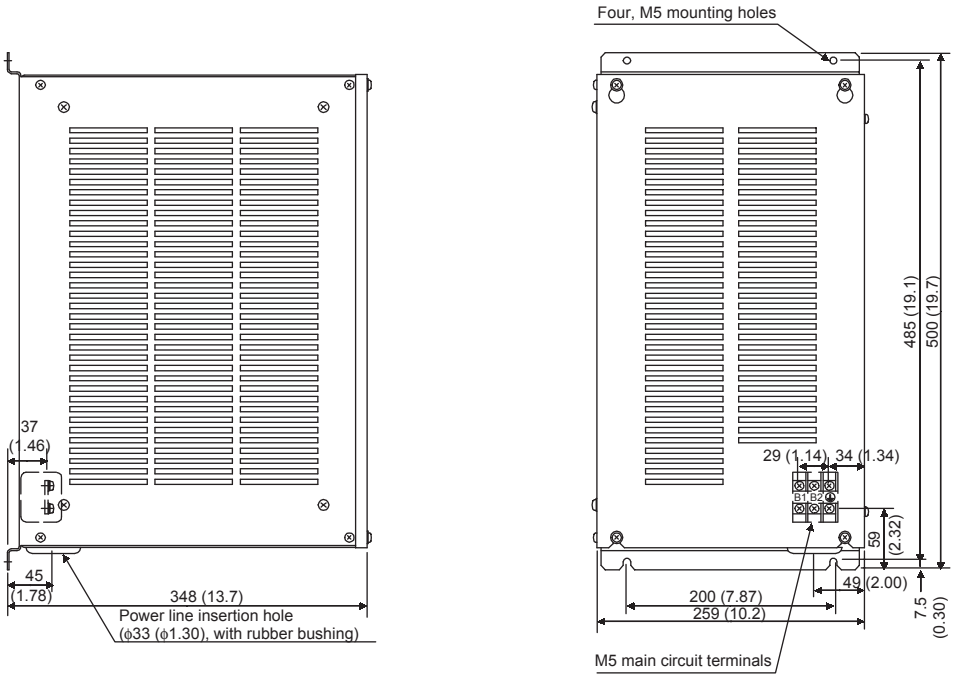
■ Dimensional Drawings

JUSP-RA12 Regenerative Resistor Unit



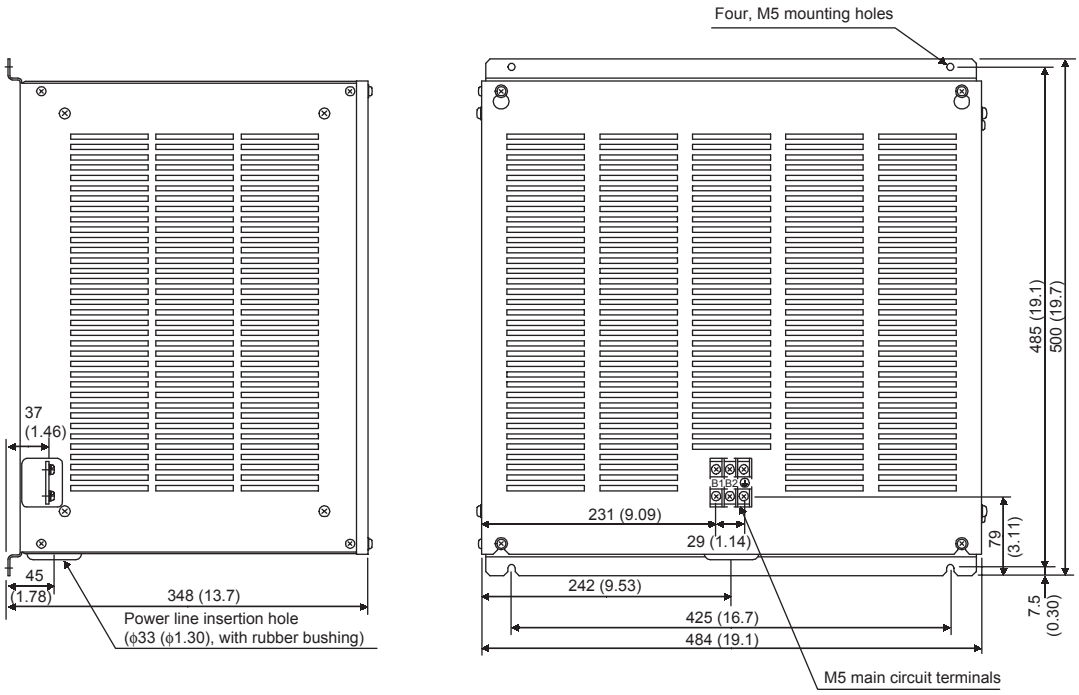
Unit: mm (inches)
Approx. mass: 14 kg (30.9 lb)

JUSP-RA13 Regenerative Resistor Unit



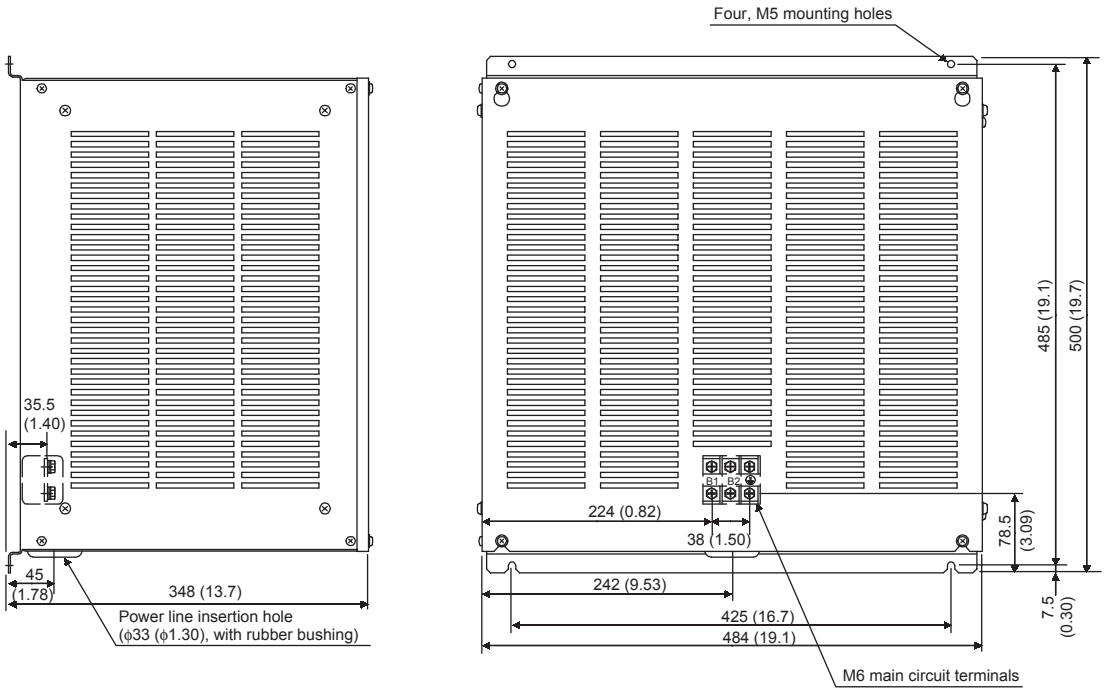
Unit: mm (inches)
Approx. mass: 14 kg (30.9 lb)

JUSP-RA14 Regenerative Resistor Unit



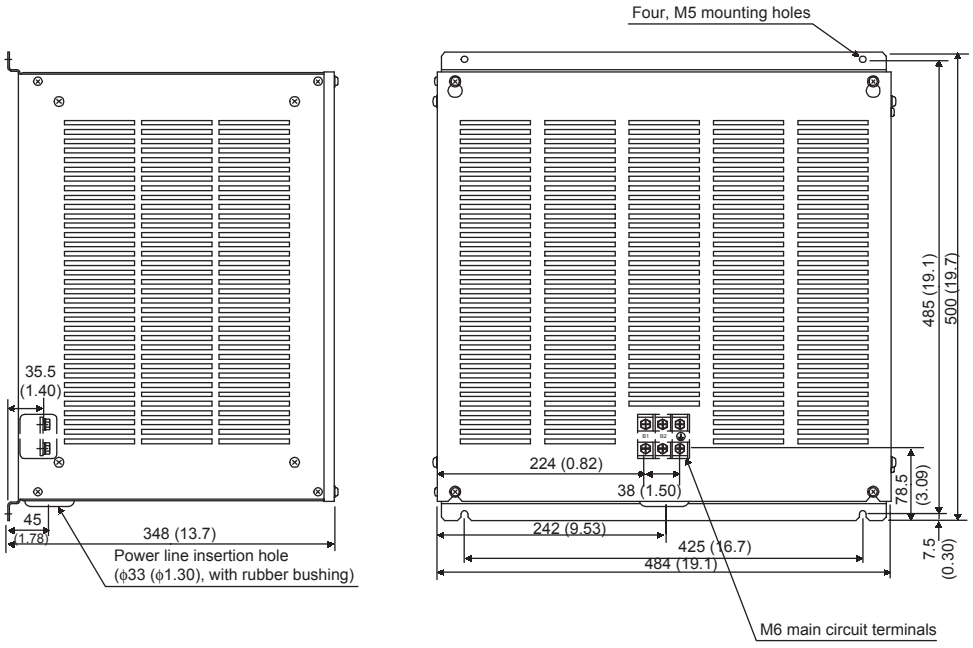
Unit: mm (inches)
Approx. mass: 20 kg (44.1 lb)

JUSP-RA15 Regenerative Resistor Unit



Unit: mm (inches)
Approx. mass: 21.5 kg (47.4 lb)

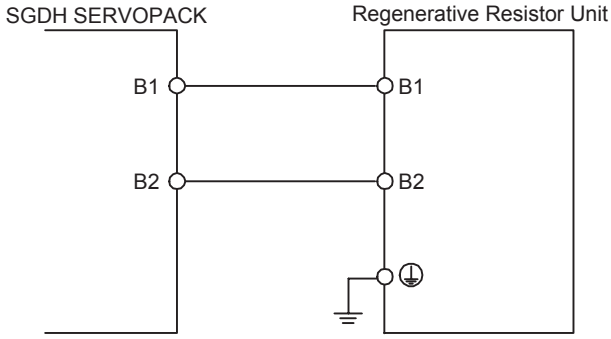
JUSP-RA16 Regenerative Resistor Unit



Unit: mm (inches)
Approx. mass: 23.5kg (51.8 lb)

■ Connections

Connect the Regenerative Resister Unit to the SERVOPACK as shown in the following diagram.



7.5.14 Dynamic Brake (DB) Unit

Externally attach a dynamic brake resistor to the SERVOPACK to dissipate regenerative energy when using the dynamic brake function. The dynamic brake resistor does not need to be installed if the dynamic brake function is not required.

■ Specifications

The following Dynamic Brake Units are required according to the SERVOPACK model.

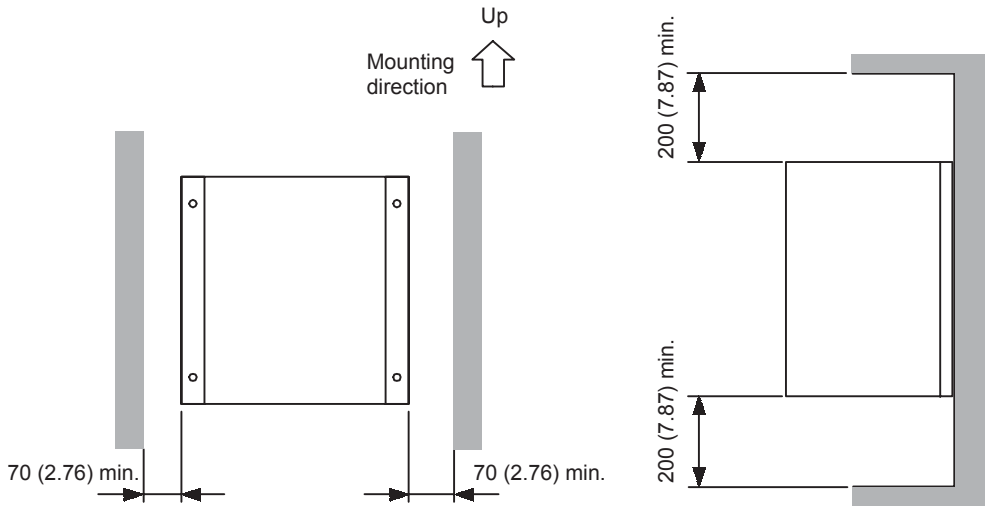
Dynamic Brake (DB) Unit Model	SERVOPACK Model SGDH-	Resistance Specifications (Star Wiring 人)	DB Contactor and Surge Absorption Unit
JUSP-DB03	2BDE, 3ZDE	180 W, 08 Ω	Built into SERVOPACK
JUSP-DB04	3GDE	180 W, 0.8 Ω	Built into Dynamic Brake Unit
JUSP-DB05	4EDE	180 W, 0.8 Ω	Built into Dynamic Brake Unit
JUSP-DB06	5EDE	300 W, 0.8 Ω	Built into Dynamic Brake Unit

Use the Dynamic Brake Unit under the following conditions. Contact your Yaskawa representative before using the Unit under conditions more severe than those specified below.

Allowable load moment of inertia: 5 times the load moment of inertia
Frequency of Dynamic Brake (DB) application: Less than one DB stop per hour at maximum rotation speed

■ Mounting

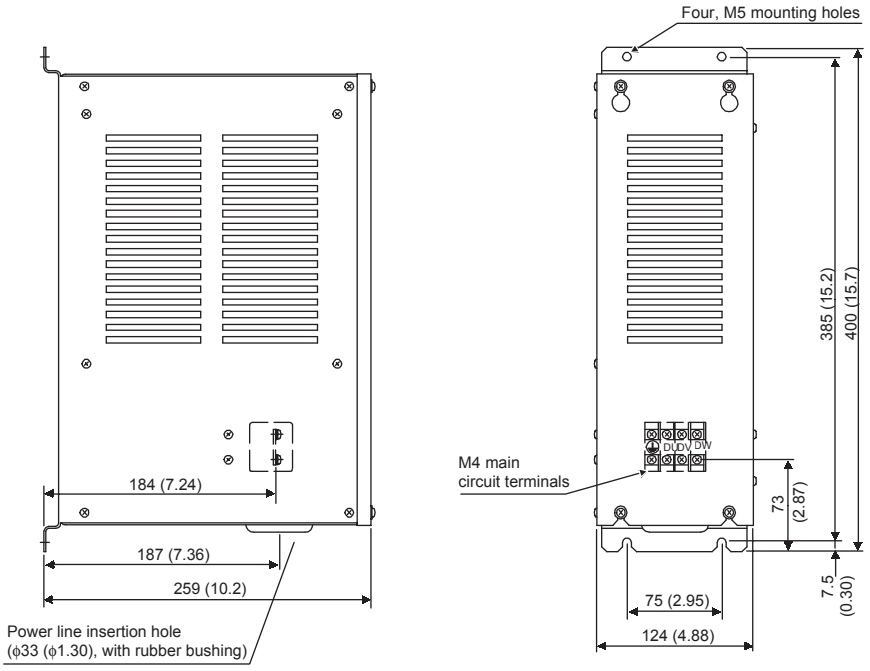
When mounting the Unit, provide sufficient space between the Unit and any devices beside it, as shown in the following diagram.



Units: mm (inches)
Approx. mass: 14.0 kg (30.9 lb)

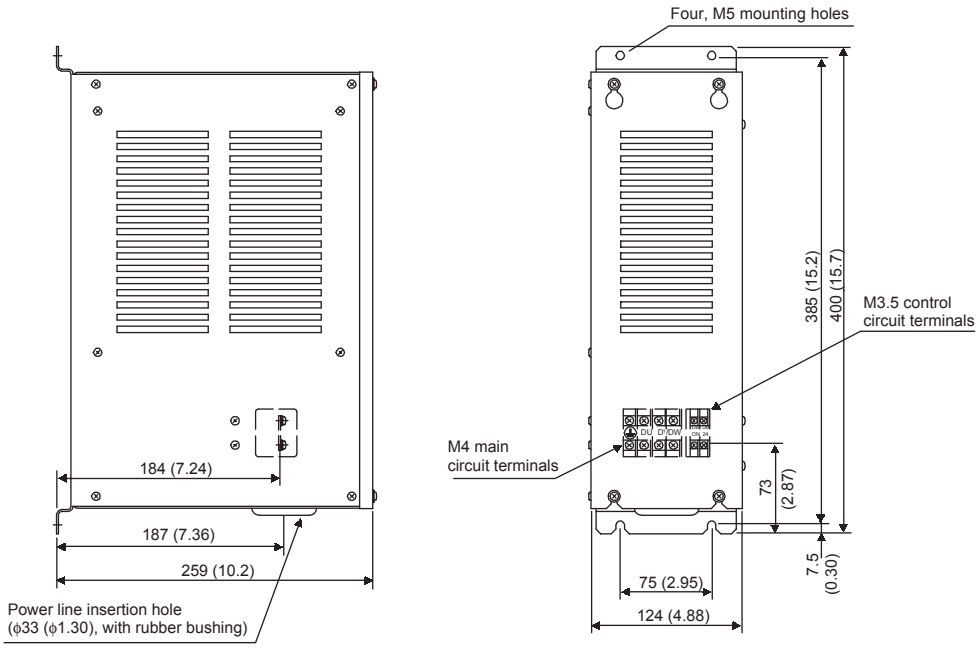
■ Dimensional Drawings

JUSP-DB03 Dynamic Brake Unit



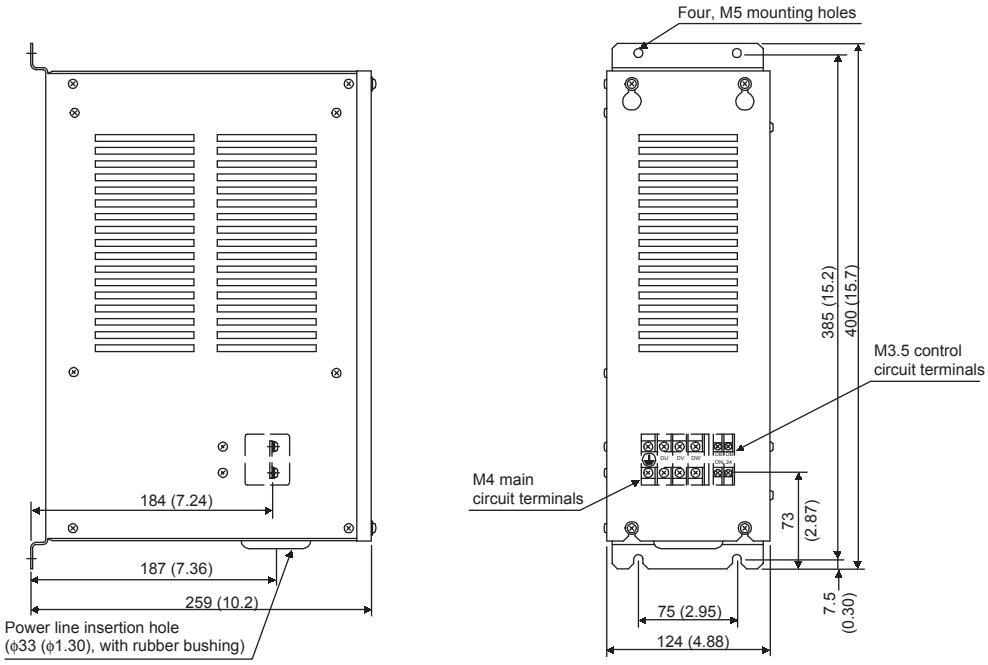
Units: mm (inches)
Approx. mass: 5.0 kg (11 lb)

JUSP-DB04 Dynamic Brake Unit



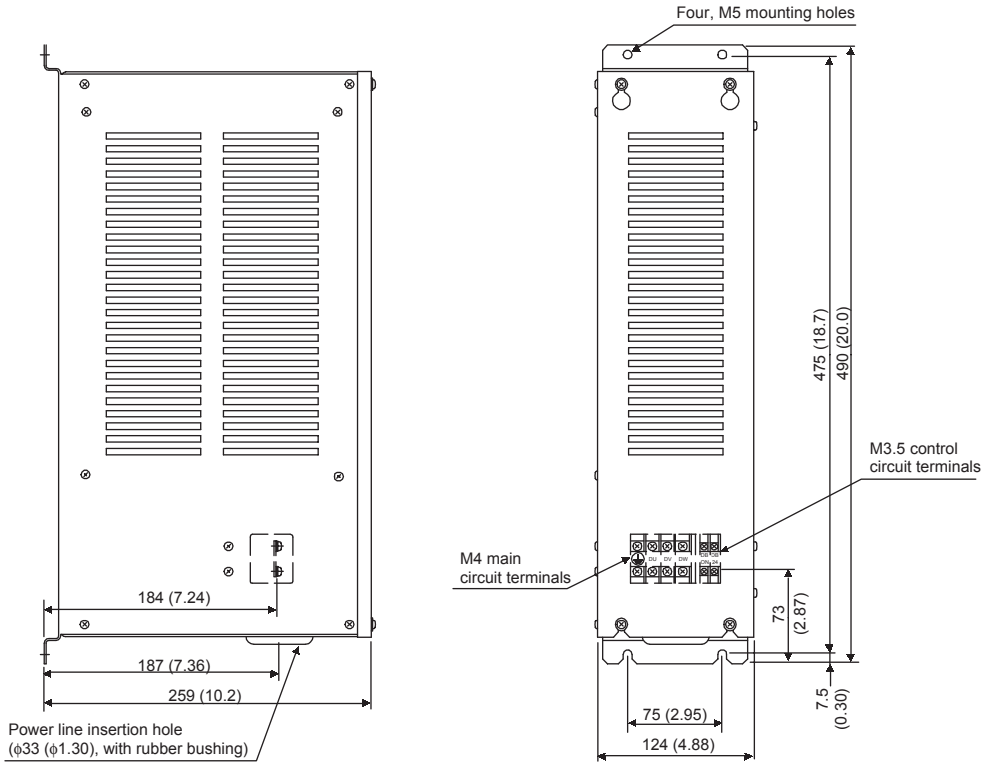
Units: mm (inches)
Approx. mass: 6.0 kg (13.2 lb)

JUSP-DB05 Dynamic Brake Unit



Units: mm (inches)
Approx. mass: 6.0 kg (13.2 lb)

JUSP-DB06 Dynamic Brake Unit



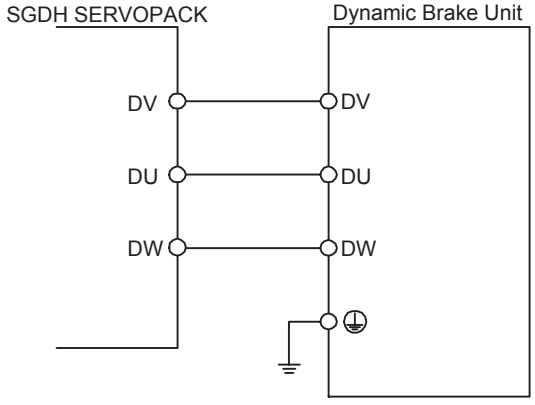
Units: mm (inches)
Approx. mass: 7.0 kg (15.4 lb)

■ Connections

Using a Yaskawa Dynamic Brake Unit

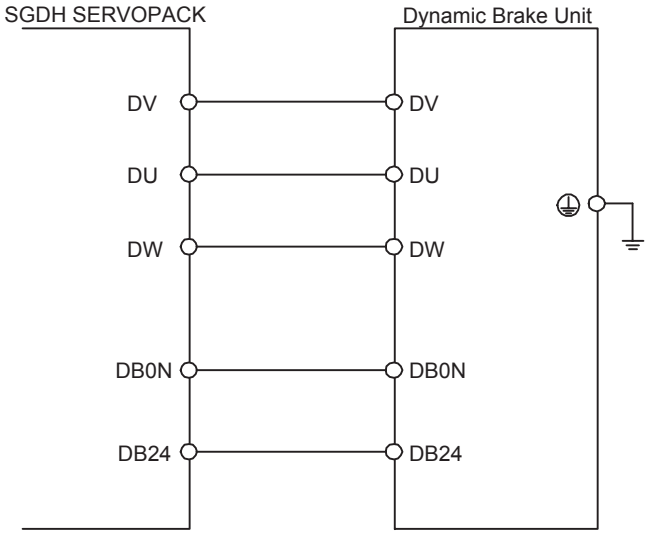
- SGDH-2BDE, 3ZDE SERVOPACKs

  The dynamic brake contactor and Surge Absorption Unit are built into the SERVOPACK. Connect the DU, DV, and DW terminals and the Frame Ground (⏚) on the Dynamic Brake Unit, as sown in the following diagram.



• SGDH-3GDE, 4EDE, 5EDE SERVOPACKs

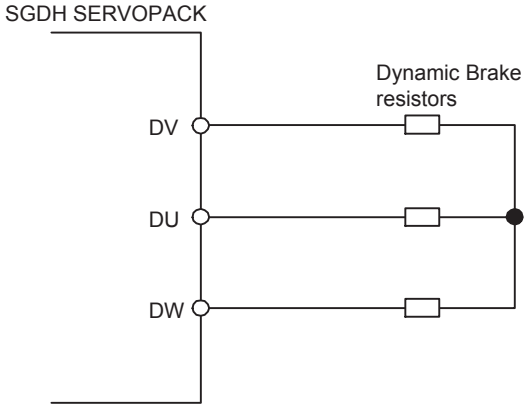
The dynamic brake contactor and Surge Absorption Unit are built into the Dynamic Brake Unit. Connect the DU, DV, and DW terminals and the Frame Ground (⏚) on the Dynamic Brake Unit, and also connect the terminals DBON and DB24 for dynamic brake contactor control, as shown in the following diagram.



Using Dynamic Brake Resistors Prepared by the Customer

• SGDH-2BDE, 3ZDE SERVOPACKs

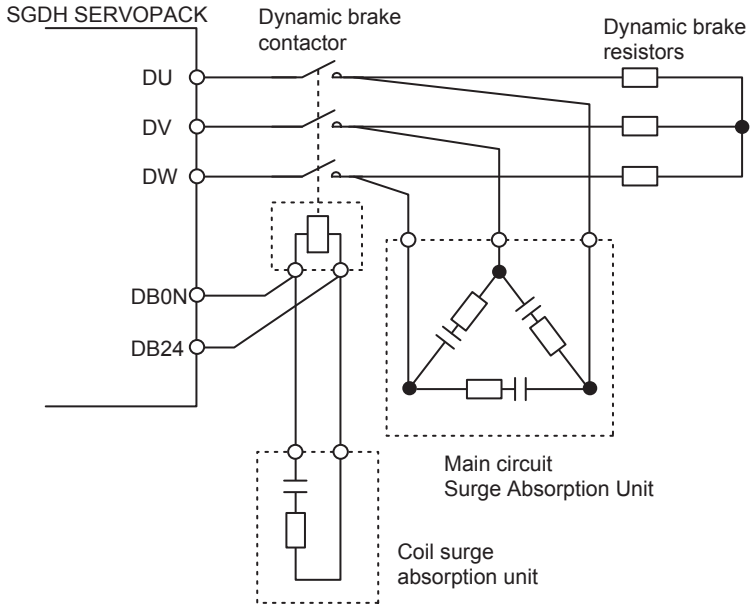
The dynamic brake contactor and Surge Absorption Unit are built into the SERVOPACK. Connect the dynamic brake resistors only, as shown in the following diagram.



Note: Connect dynamic brake resistors with the following resistance specifications.
400-V SERVOPACKs: Higher than 0.8 Ω

• SGDH-3GDE, 4EDE, 5EDE SERVOPACKs

Connect a dynamic brake contactor and Surge Absorption Unit, as shown in the following diagram.



Note: Connect dynamic brake resistors with the following resistance specifications.
400-V SERVOPACKs: Higher than 0.8 Ω

Use the following dynamic brake contactor and Surge Absorption Unit. The main circuit Surge Absorption Unit is available as a side-connection type or a front-connection type.

Name		Model	Manufacturer
Contactor		SC-4-1/G 24-VDC coil	Fuji Electric Co., Ltd.
Main Circuit Surge Absorption Unit	Front Connection	SZ-ZM1	
	Side Connection	SZ-ZM2	
Coil Surge Absorption Unit		SZ-Z4	

7.5.15 Thermal Relays

Connect a thermal relay to the SERVOPACK to protect the regenerative resistor and dynamic brake resistor from heat damage when operating under extreme conditions.

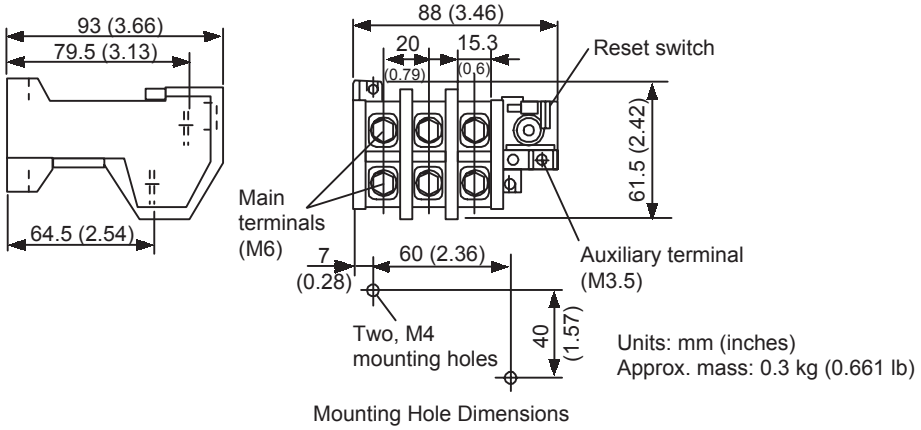
■ Recommended Thermal Relay Models

Select the appropriate thermal relay from the following list when using Yaskawa Regenerative Resistor Units and Dynamic Brake Units.

Dynamic Brake (DB) Unit and Regenerative Resistor Unit Model	Thermal Relay Model	Thermal Relay Current Range A	Thermal Relay Current A	Manufacturer
JUSP-DB03 JUSP-DB04 JUSP-DB05	TR-3N/3 7 A	7 to 11	7	Fuji Electric Co., Ltd.
JUSP-DB06	TR-3N/3 7 A	7 to 11	9	
JUSP-RA08	TR-3N/3 12 A	12 to 18	14	
JUSP-RA09	TR-3N/3 18 A	18 to 26	23	
JUSP-RA11	TR-3N/3 18 A	18 to 26	24	
JUSP-RA12	TR-3N/3 7 A	7 to 11	9	
JUSP-RA13	TR-3N/3 9 A	9 to 13	10	
JUSP-RA14	TR-3N/3 12 A	12 to 18	14	
JUSP-RA15	TR-3N/3 12 A	12 to 18	17	
JUSP-RA16	TR-3N/3 18 A	18 to 26	19	

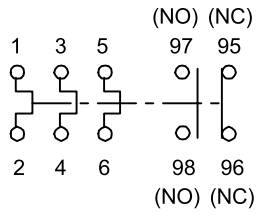
■ Dimensional Drawings

The following dimensional drawing is for a TR-3N Thermal Relay.



■ Internal Connection Diagram

The following connection diagram is for a TR-3N Thermal Relay.

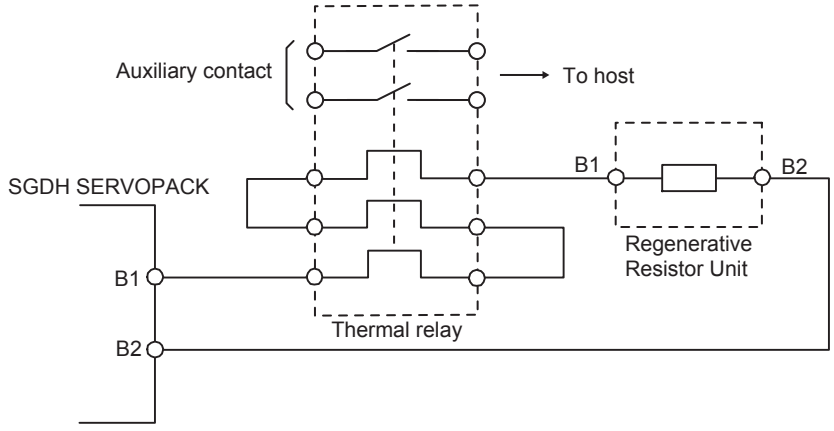


■ Connections

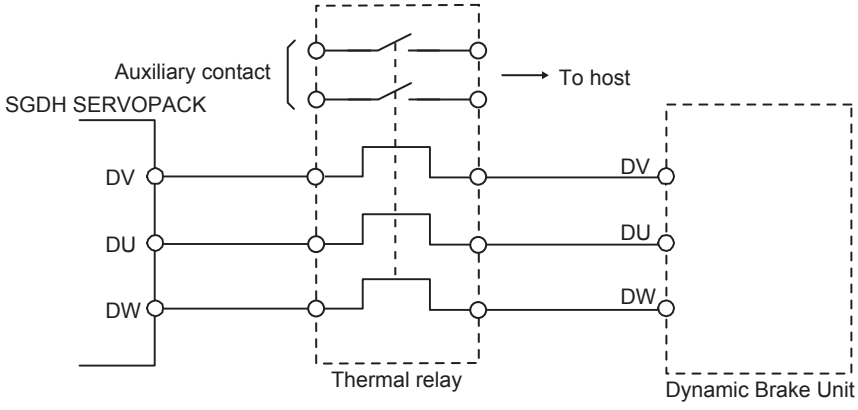
Connect the thermal relay as shown in the following diagram.

When the thermal relay operates, the auxiliary contact turns OFF (or ON). Therefore, configure a sequence so that the main power supply or the servomotor turns OFF when the auxiliary contact turns OFF (or ON).

Connecting to a Regenerative Resistor Unit



Connecting to a Dynamic Brake Unit



■ Selecting a Thermal Relay

When preparing the dynamic brake resistor and regenerative resistor separately, select a thermal relay by calculating the setting current of the thermal relay according to the value and capacity of the resistor being used, as shown in the following equation.

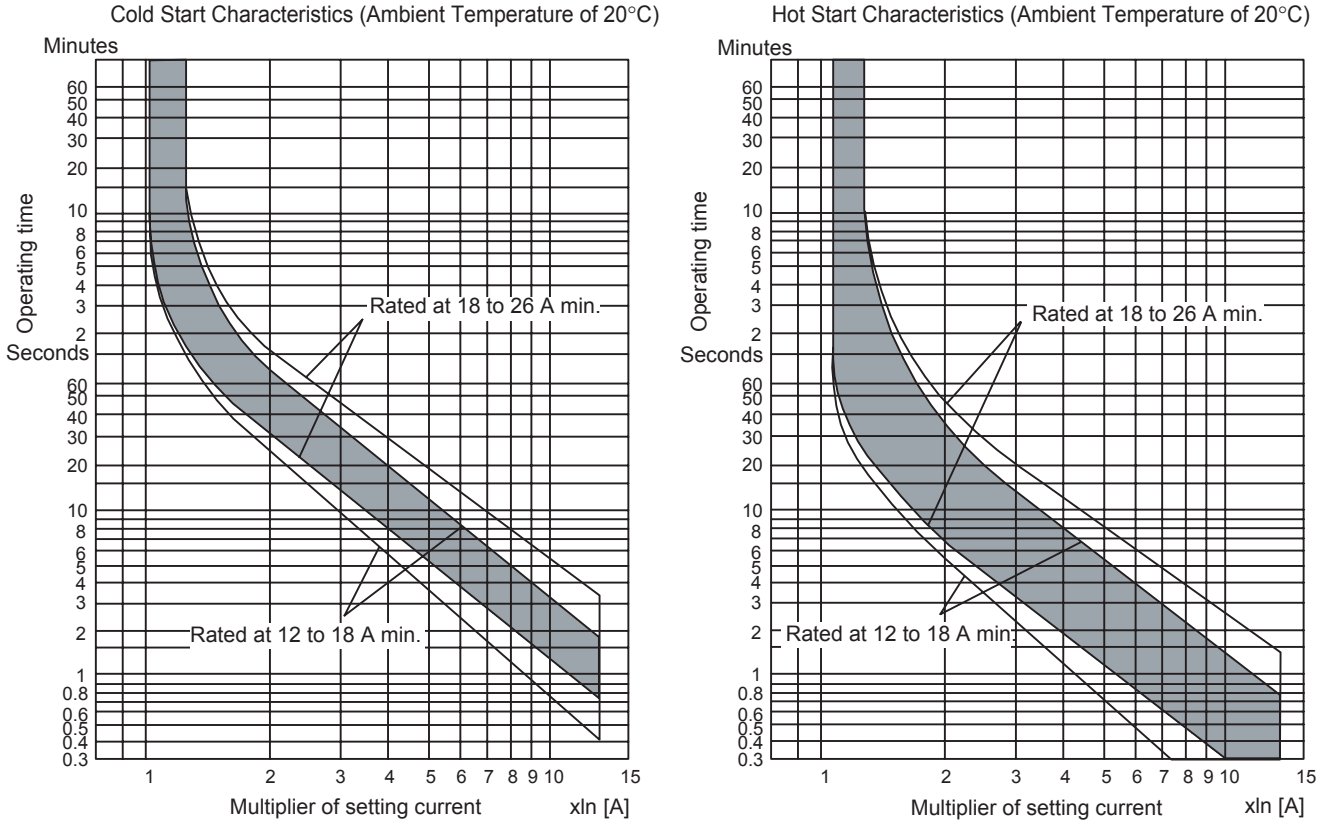
$$\text{Setting current} = \sqrt{\frac{\text{Resistance capacity (W)} \times 0.2}{\text{Resistance value } (\Omega)}}$$

Example for a JUSP-RA08

$$\text{Setting current} = \sqrt{\frac{2000\ (\text{W}) \times 0.2}{2.4\ (\Omega)}} \fallingdotseq 14\ \text{A}$$

Select a thermal relay that has operating characteristics equivalent to those of the recommended product.

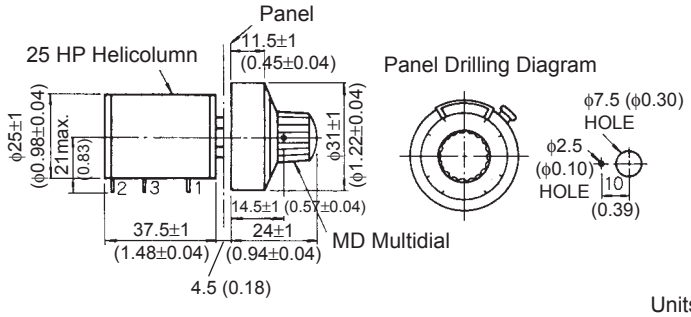
Refer to the following diagrams for the operating characteristics of the recommended thermal relays.



7.5.16 Variable Resistor for Speed Setting

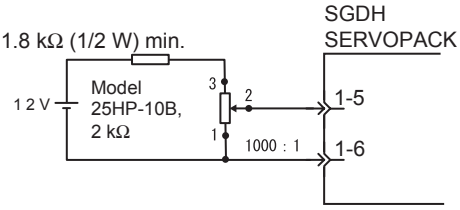
This variable resistor is used to give speed references by applying the speed reference voltage from an external power supply across 1CN pins #5 and #6.

■ Dimensional Drawings



Units: mm (inches)

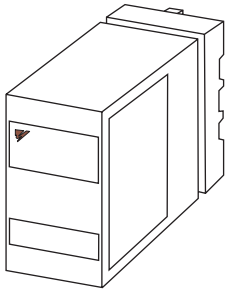
■ Connecting to the External Power Supply

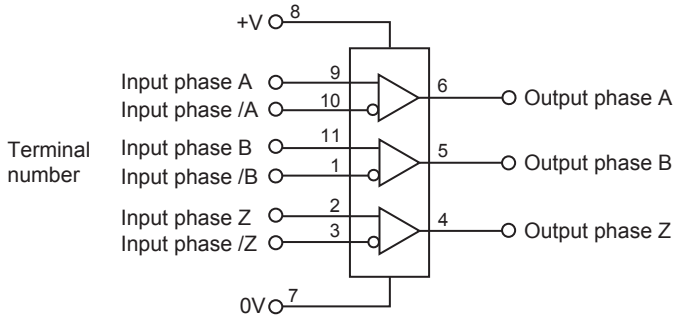


Model 25HP-10B
Multi-wrap variable resistor with
MD10-30B4 dial, manufactured
by Sakae Tsushin Kogyo K.K.

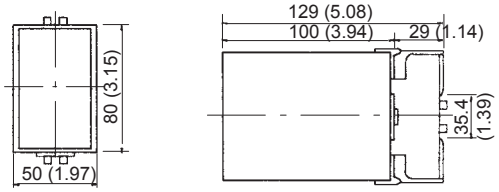
7.5.17 Encoder Signal Converter Unit

Unit to convert the encoder signal output from the line driver to an open collector output or voltage pulse output.





■ Dimensional Drawings



Units: mm (inches)

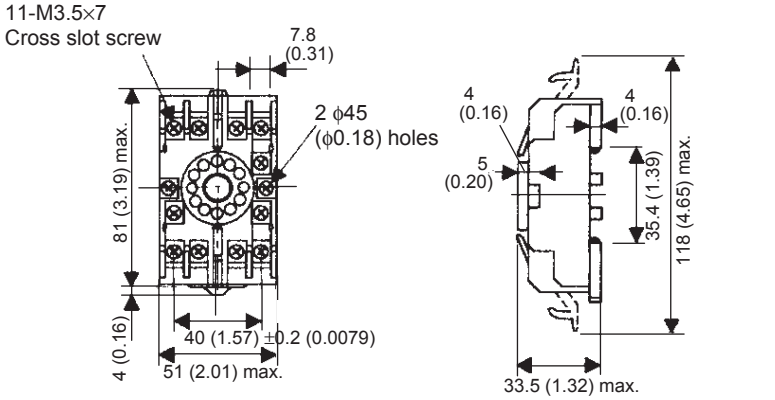
■ Specifications

Specifications	Receiver Unit			
	LRX-01/A1	LRX-01/A2	LRX-01/A3	LRX-01/A4
Power Supply	12 VDC ± 10%, 100 mA		5 VDC ± 5%, 100 mA	
Input Signals	Balanced line driver input (RS-422)			
Output Signals	Voltage pulse output	Open collector output	Voltage pulse output	Open collector output
Input Signal Level	Voltage differential ≥ 0.3 V, internal termination resistance 100 Ω			
Output Signal Level	H: 10 V min. (1 mA) L: 0.5 V max. (30 mA)	L: 0.5 V max. (30 mA) Withstand voltage: 50 V	H: 3 V min. (1 mA) L: 0.5 V max. (30 mA)	L: 0.5 V max. (30 mA) Withstand voltage: 50 V
Operating Ambient Temperature Range	0 to +60°C			
IC Used	AM26LS32C Receiver IC, or equivalent			

Note: Available from Yaskawa Controls Co., Ltd.

■ Mounting Base for LRX

Dimensional Drawings



Units: mm (inches)

Note: Available from Yaskawa Controls Co., Ltd.

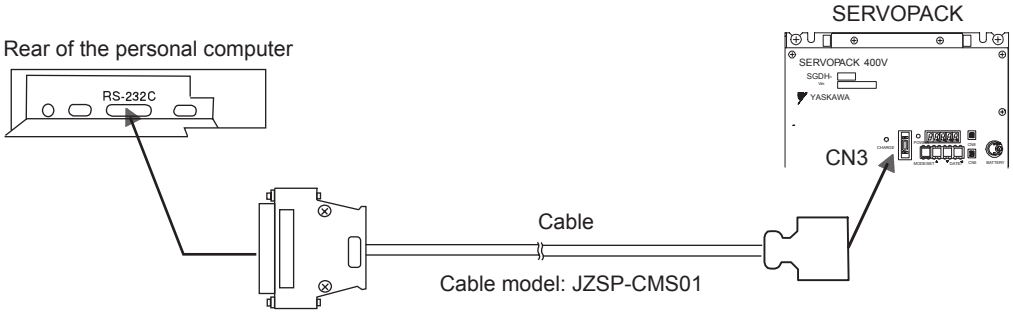
7.5.18 Cables for Connecting PCs to a SERVOPACK

Special cables for connecting a PC to a SERVOPACK. Using these cables allows monitoring and setting of parameters with a PC.

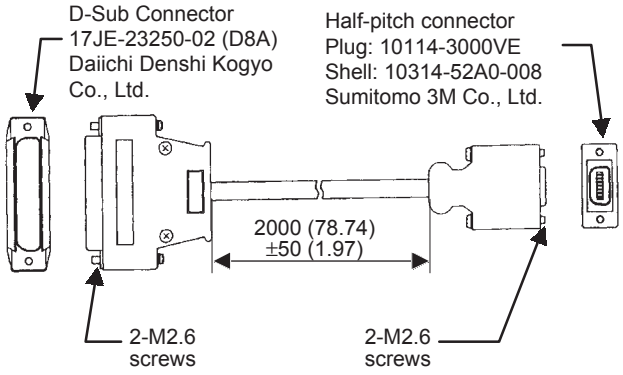
PC software is available for these communications. Contact your Yaskawa representative for details. Operate the software as described in the manual supplied.

■ D-Sub, 25-pin Connector Cable

Connecting a Personal Computer to a SERVOPACK



Cable Configuration



Communications Specifications

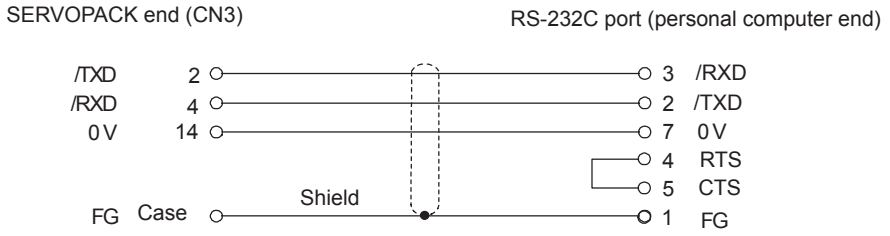
The communications specifications are as follows:

- Baud Rate: 9600 bps
- Number of Bits: Start: 1 bit
  Data: 7 bits
  Stop: 1 bit
  Parity: 1 bit (even)
- Synchronization: Start-Stop
- XON/XOFF Control: None
- Shift Control: None
- Communications Method: Semi-duplex

Connection Circuits

- With an RS-232C Port

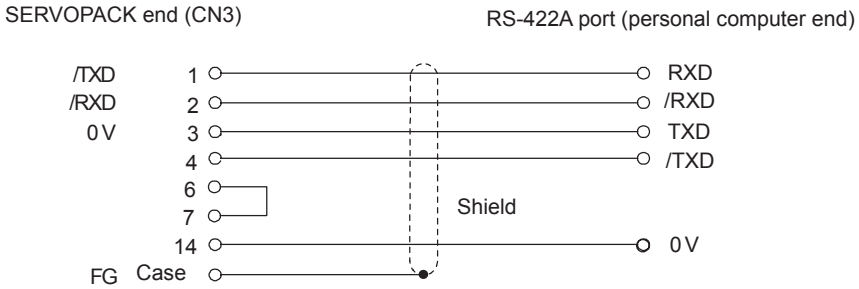
  Maximum cable length is 2 m (6.56 ft). The connection circuit is as follows:



- With an RS-422A Port

  Connection is also possible to the RS-422A port. In this case, the connection circuit is as follows:

  - Transmission Distance: 30 m (98.4 ft) max.
  - Transmission System: RS-422A



- Terminal Arrangement at SERVOPACK End

Table 7.15 Connector Pin Numbers and Signal Names

Pin No.	Signal Name	Signal Circuit Name	Signal Direction
1	TXD	Transmit data (not inverted)	P *1 ← S *2
2	/TXD	Transmit data (inverted)	P ← S
3	RXD	Receive data (not inverted)	P → S
4	/RXD	Receive data (inverted)	P → S
5	OPH	Reserved pin	-
6	/RXD	Shorting pins 6 and 7 inserts 220 Ω termination resistance between RXD and /RXD.	
7	RT		
8	TXD	Transmit data (not inverted)	P ← S
9	/TXD	Transmit data (inverted)	P ← S
10	RXD	Receive data (not inverted)	P → S
11		Reserved pin	# *3
12		Reserved pin	# *3
13	5VPP	Reserved pin	-
14	GND	Signal ground 0 V	-

* 1. P: Personal computer
* 2. S: SERVOPACK
* 3. #: Terminal not used, leave open.

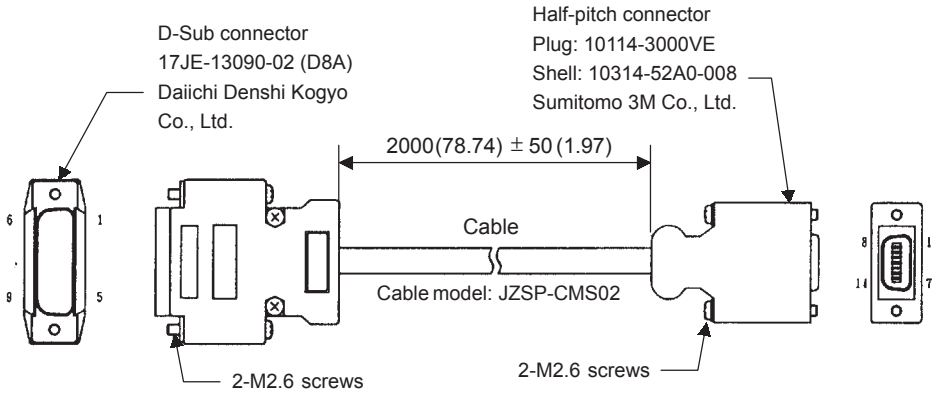
Note: Fold back the cable shielding at each end of the cable and secure it with clamp.

■ Other Cables for Connecting Personal Computers

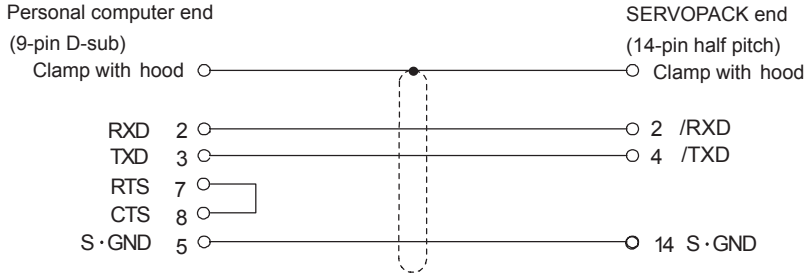
Yaskawa also provides cables for connecting NEC PC98 Series and IBM PC compatible to a SERVOPACK.

D-sub, 9-pin Connector Cable for IBM PC Compatible

- Cable Configuration



- Connection Circuit



7

8

Inspection, Maintenance, and Troubleshooting

This chapter describes the basic inspection and maintenance to be carried out by the user. In addition, troubleshooting procedures are described for problems which cause an alarm display and for problems which result in no alarm display.

8.1 Servodrive Inspection and Maintenance - - - - - - - - - - - - - - - - 8-2
8.1.1 Servomotor Inspection - 8-2
8.1.2 SERVOPACK Inspection - 8-3
8.1.3 Replacing Battery for Absolute Encoder - 8-4
8.2 Troubleshooting - 8-5
8.2.1 Troubleshooting Problems with Alarm Displays - - - - - - - - - - - - - - - - - 8-5
8.2.2 Troubleshooting Problems with No Alarm Display - - - - - - - - - - - - - - - 8-35
8.2.3 Alarm Display Table - 8-37
8.2.4 Warning Displays - 8-39
8.2.5 Internal Connection Diagram and Instrument Connection Examples - 8-40

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8.1 Servodrive Inspection and Maintenance

This section describes the basic inspections and maintenance of servomotors and SERVOPACKs and the procedures for replacing the battery for absolute encoders.

8.1.1 Servomotor Inspection

For inspection and maintenance of servomotors, follow the simple, daily inspection procedures in the following table. The AC servomotors are brushless. Simple, daily inspection is sufficient. The inspection and maintenance frequencies in the table are only guidelines. Increase or decrease the frequency to suit the operating conditions and environment.

IMPORTANT

During inspection and maintenance, do not disassemble the servomotor. If disassembly of the servomotor is required, contact your Yaskawa representative.

Table 8.1 Servomotor Inspections

Item	Frequency	Procedure	Comments
Vibration and Noise	Daily	Touch and listen.	Levels higher than normal?
Exterior	According to degree of contamination	Clean with cloth or compressed air.	-
Insulation Resistance Measurement	At least once a year	Disconnect SERVOPACK and test insulation resistance at 500 V. Must exceed 10 MΩ. *	Contact your Yaskawa representative if the insulation resistance is below 10 MΩ.
Replacing Oil Seal	At least once every 5000 hours	Remove servomotor from machine and replace oil seal.	Applies only to motors with oil seals.
Overhaul	At least once every 20000 hours or 5 years	Contact your Yaskawa representative.	The user should not disassemble and clean the servomotor.

* Measure across the servomotor FG and the phase-U, phase-V, or phase-W power line.

8.1.2 SERVOPACK Inspection

For inspection and maintenance of the SERVOPACK, follow the inspection procedures in the following table at least once every year. Other routine inspections are not required.

Table 8.2 SERVOPACK Inspections

Item	Frequency	Procedure	Comments
Clean Interior and Circuit Boards	At least once a year	Check for dust, dirt, and oil on the surfaces.	Clean with compressed air or cloth.
Loose Screws	At least once a year	Check for loose terminal block and connector screws.	Tighten any loose screws.
Defective Parts in Unit or on Circuit Boards	At least once a year	Check for discoloration, damage or discontinuities due to heating.	Contact your Yaskawa representative.

■ Part Replacement Schedule

The following parts are subject to mechanical wear or deterioration over time. To avoid failure, replace these parts at the frequency indicated.

The parameters of any SERVOPACKs overhauled by Yaskawa are reset to the standard settings before shipping. Be sure to confirm that the parameters are properly set before starting operation.

Table 8.3 Periodical Part Replacement

Part	Standard Replacement Period	Replacement Method
Cooling Fan	4 to 5 years	Replace with new part.
Smoothing Capacitor	7 to 8 years	Test. Replace with new part.
Relays	-	Test. Replace if necessary.
Fuse	10 years	Replace with new part.
Aluminum Electrolytic Capacitor on Circuit Board	5 years	Test. Replace with new circuit board if necessary.

Operating Conditions:

- Ambient Temperature: Annual average of 30°C
- Load Factor: 80% max.
- Operation Rate: 20 hours/day max.

8.1.3 Replacing Battery for Absolute Encoder

If the voltage of the battery for an absolute encoder drops to approx. 2.7 V or less, an Absolute Encoder Battery Alarm (A. 83) will occur in the SERVOPACK. This alarm occurs when the SERVOPACK receives a signal from the absolute encoder when the power to the SERVOPACK is turned ON. Therefore, the SERVOPACK will not give an alarm when the battery voltage drops below the minimum voltage level while the power is being supplied to the SERVOPACK.

Refer to *4.7.3 Handling Batteries* for the battery type recommended for absolute encoders. Replace the battery using the following procedure if the battery voltage drops below the minimum required battery voltage.

■ Battery Replacement Procedure

1. Replace the battery while the control power to the SERVOPACK is ON.
2. After replacement, turn OFF the power to the SERVOPACK in order to clear the Absolute Encoder Battery Alarm (A. 83).
3. Turn ON the power to the SERVOPACK again and confirm that it operates properly to complete battery replacement.

IMPORTANT

The absolute encoder data will be lost when the control power to the SERVOPACK is turned OFF and when the encoder cable is disconnected from the battery. If the data is lost, refer to *4.7.4 Absolute Encoder Setup* and initialize the absolute encoder.

8.2 Troubleshooting

This section describes causes and remedies for problems which cause an alarm display and for problems which result in no alarm display.

8.2.1 Troubleshooting Problems with Alarm Displays

Problems that occur in the Servodrives are displayed on the panel operator as "A. □□" or "CPF□□"."A.- -", however, does not indicate an alarm. Refer to the following sections to identify the cause of an alarm and the action to be taken.

Contact your Yaskawa representative if the problem cannot be solved by the described procedures.

■ A.02

A.02: Parameters Breakdown

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm

At power ON — A, B

Cause		Remedy
A	Power turned OFF during parameter write. Alarm occurred at next power ON.	• Initialize parameters using Fn005 and reinput user settings. • Replace SERVOPACK.
B	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.03

A.03: Main Circuit Detector Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	Circuit board (1PWB or 2PWB) defective.	Replace SERVOPACK.

■ A.04

A.04: Parameter Setting Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	An out-of-range parameter was previously set or loaded.	• Reset all parameters in range. • Otherwise, re-load correct parameter.
B	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.05

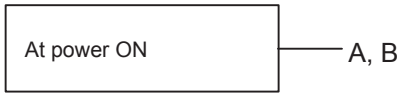
A.05: Combination Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	The range of servomotor capacities that can be combined has been exceeded.	Replace the servomotor so that a suitable combination is achieved.
B	Encoder parameters have not been written properly.	Replace the servomotor.

■ A.10

A.10: Overcurrent or Heat Sink Overheated

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	OFF	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm

During servomotor operation — A, B, D, E, F, G, H

When SERVO ON (/S-ON) signal turned ON — C, D

At power ON — C

Cause		Remedy
A	Wiring shorted between SERVOPACK and servomotor.	Check and correct wiring.
B	Servomotor phase U, V, or W shorted.	Replace the servomotor.
C	• Circuit board (1PWB) defective. • Power transistor defective.	Replace SERVOPACK.
D	Current feedback circuit, power transistor, DB circuit, or circuit board defective.	Replace SERVOPACK.
E	The ambient temperature of the SERVOPACK exceeded 55°C.	Alter conditions so that the ambient temperature goes below 55°C.
F	The air flow around the heat sink is bad.	Follow the installation method and provide sufficient space as specified.
G	Fan stopped.	Replace SERVOPACK.
H	SERVOPACK is operating under an overload.	Reduce load.

Note: E to H can occur with a SERVOPACK with a capacity of all models (400 V) and 1.5 kW to 5 kW (200 V).

■ A.30

A.30: Regenerative Error Detected

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	OFF	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm

During servomotor operation — A, B

Occurred when the control power turned ON — D

Occurred approximately 1 second after the main circuit power ON. — A, B, C

Cause		Remedy
A	Regenerative transistor is abnormal.	Replace SERVOPACK.
B	Disconnection of the regenerative resistor.	Replace SERVOPACK or regenerative resistor.
C	Regenerative Unit disconnected (for an external regenerative resistor).	Check wiring of the external regenerative resistor.
D	SERVOPACK defective.	Replace SERVOPACK.

■ A.32

A.32: Regenerative Overload

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	OFF	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm

During servomotor operation — A, B

Cause		Remedy
A	Regenerative power exceeds the allowable value.	Use an external regenerative resistor that matches the regenerative power capacity.
B	Alarm occurs although an external regenerative resistor is used and the temperature rise of the regenerative resistor is small.	Correct parameter Pn600.

■ A.40

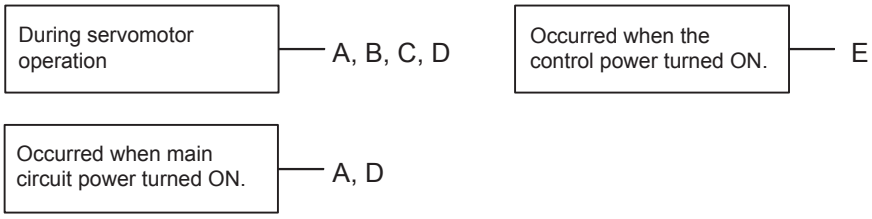
A.40: Main Circuit DC Voltage Error Detected: Overvoltage

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	The power supply voltage is not within the range of specifications.	Check power supply.
B	Load exceeds capacity of the Regenerative Unit.	Check specifications of load moment of inertia and overhanging load.
C	Regenerative transistor is abnormal.	Replace SERVOPACK.
D	Rectifying diode defective.	
E	SERVOPACK defective.	

■ A.41

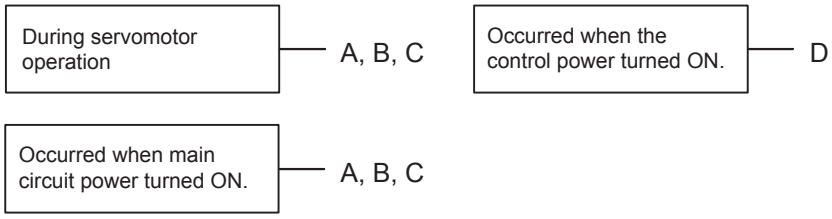
A.41: Main Circuit DC Voltage Error Detected: Undervoltage

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	The power supply voltage is not within the range of specifications.	Check power supply voltage.
B	Fuse blown.	Replace SERVOPACK.
C	Rectifying diode defective.	
D	SERVOPACK defective.	

■ A.51

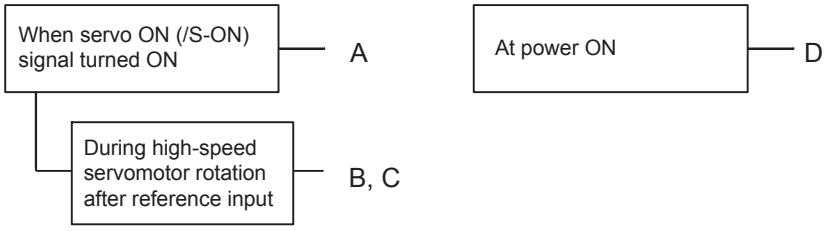
A.51: Overspeed

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Servomotor wiring incorrect.	Check and correct wiring. (Check for phase-U, -V, and -W wiring errors.)
B	Position or speed reference input is too large.	Lower the reference input values.
C	Incorrect reference input gain settings.	Check and correct parameter settings.
D	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.71

A.71: Overload: High Load

The alarm output, status, and remedy for A.71 are the same as for A.72.

■ A.72

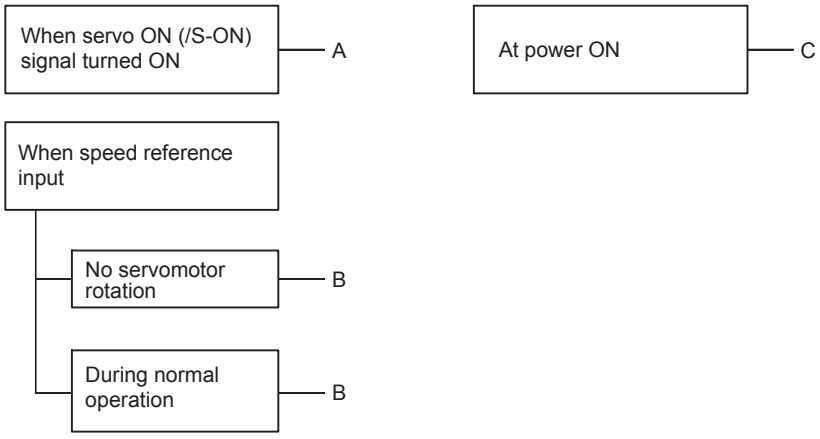
A.72: Overload: Low Load

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Servomotor wiring incorrect or disconnected.	Check wiring and connectors at servomotor.
B	Load greatly exceeds rated torque.	Reduce load torque and moment of inertia. Otherwise, replace with larger capacity servomotor.
C	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.73

A.73: Dynamic Brake Overload

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



	Cause	Remedy
A	The product of the square of rotational motor speed and the combined moment of inertia of the motor and load (rotation energy) exceeds the capacity of the dynamic brake resistor built into SERVOPACK.	• Lower the rotational speed. • Lower the load moment of inertia. • Minimize the use of the dynamic brake.
B	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.74

A.74: Overload of Surge Current Limit Resistor

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Frequently turning the main circuit power ON/OFF.	Do not repeatedly turn ON/OFF the main circuit power.
B	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.7A

A.7A: Heat Sink Overheated

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm

During servomotor operation —— A, B, C, D

When control power turned ON —— E

Cause		Remedy
A	The ambient temperature of the SERVOPACK exceeded 55°C.	Alter conditions so that the ambient temperature goes below 55°C.
B	The air flow around the heat sink is bad.	Follow the installation method and provide sufficient space as specified.
C	Fan stopped.	Replace SERVOPACK.
D	SERVOPACK is operating under an overload.	Reduce load.
E	SERVOPACK defective.	Replace SERVOPACK.

■ A.81

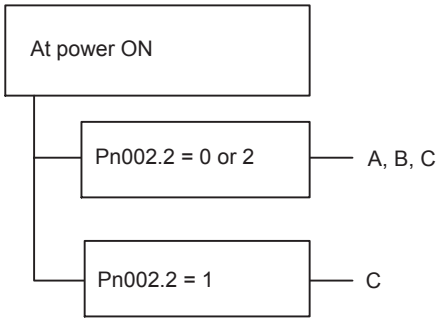
A.81: Absolute Encoder Backup Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	The following power supplies to the absolute encoder all failed: • +5 V supply • Battery power	Follow absolute encoder set-up procedure.
B	Absolute encoder malfunctioned.	Replace the servomotor.
C	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.82

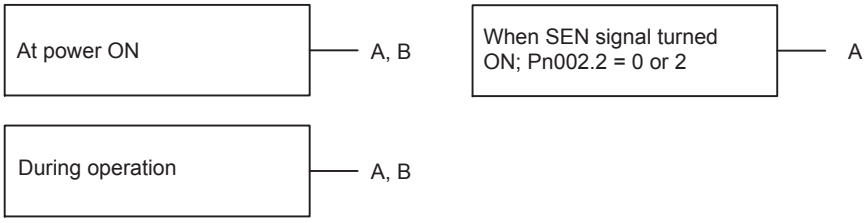
A.82: Encoder Checksum Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	Error during encoder memory check	• Follow absolute encoder set-up procedure. • Replace servomotor if error occurs frequently.
B	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.83

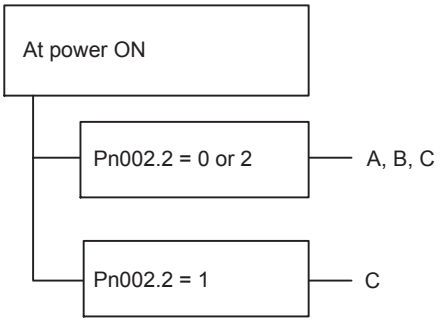
A.83: Absolute Encoder Battery Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	• Battery not connected • Battery connection defective	Check and correct battery connection.
B	Battery voltage below specified value. Specified value: 2.7 V	Install a new battery while the control power to SERVOPACK is ON. After replacement, turn ON the power again.
C	Circuit board (1PWB) defective.	Replace the servomotor.

Note: No alarm will occur at the SERVOPACK if the battery error occurs during operation.

■ A.84

A.84: Absolute Encoder Data Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	Encoder defective.	Replace the servomotor if the problem occurs often.
B	Operational error in encoder caused by external noise.	Check and correct wiring around the encoder (grounding of the servomotor, separation between the encoder cable and the servomotor power cable, insertion of toroidal cores onto cables, etc.).

■ A.85

A.85: Absolute Encoder Overspeed

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	Absolute encoder turned ON at a speed exceeding 200 min^{-1}.	Turn ON power supply with the servomotor stopped.
B	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.86

A.86: Encoder Overheated

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm

During servomotor operation — A, B

Occurred when the control power turned ON. — C, D

Cause		Remedy
A	The ambient temperature of the servomotor is high.	Alter conditions so that the ambient temperature goes below 40°C
B	SERVOPACK is operating under an overload.	Reduce load.
C	Circuit board (1PWB) defective.	Replace SERVOPACK.
D	Encoder defective.	Replace the servomotor.

■ A.b1

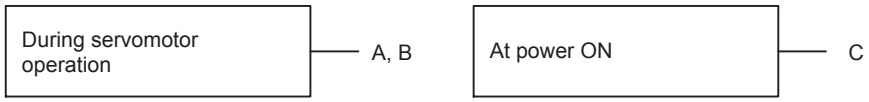
A.b1: Reference Speed Input Read Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	Error in reference read-in unit (A/D Converter, etc.).	Reset alarm and restart operation.
B	Reference read-in unit faulty. (A/D Converter, etc.).	Replace SERVOPACK.
C	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.b2

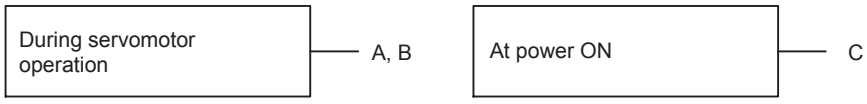
A.b2: Reference Torque Input Read Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	OFF

Note: OFF: Output transistor is OFF (alarm state).

Status and Remedy for Alarm



Cause		Remedy
A	Error in reference read-in unit (A/D Converter, etc.).	Reset alarm and restart operation.
B	Reference read-in unit faulty. (A/D Converter, etc.).	Replace SERVOPACK.
C	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.C1

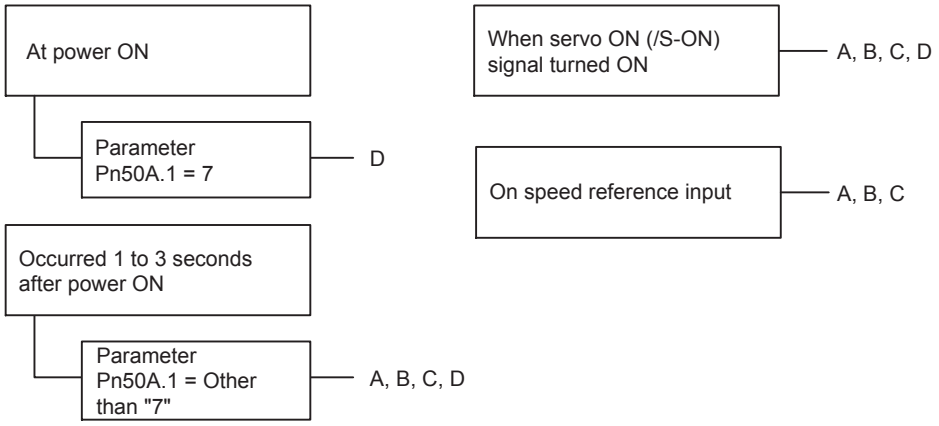
A.C1: Servo Overrun

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Servomotor wiring incorrect or disconnected.	Check wiring and connectors at servomotor.
B	Encoder wiring incorrect or disconnected.	Check wiring and connectors at encoder.
C	Encoder defective.	Replace the servomotor.
D	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.C8

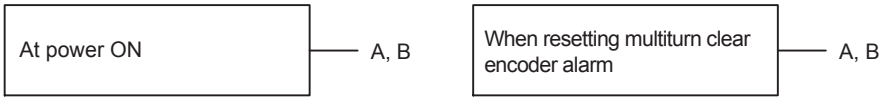
A.C8: Absolute Encoder Clear Error and Multiturn Limit Setting Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Encoder defective.	Replace the servomotor.
B	SERVOPACK defective.	Replace SERVOPACK.

■ A.C9

A.C9: Encoder Communications Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Encoder wiring incorrect or disconnected	Check wiring and connectors at encoder.
B	Encoder defective.	Replace the servomotor.
C	SERVOPACK defective.	Replace SERVOPACK.

■ A.CA

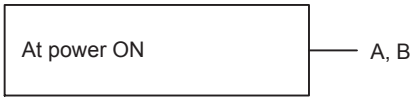
A.CA: Encoder Parameter Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Encoder defective.	Replace the servomotor.
B	SERVOPACK defective.	Replace SERVOPACK.

■ A.Cb

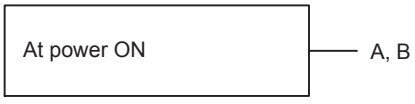
A.Cb: Encoder Echoback Error

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Encoder wiring incorrect or disconnected	Check wiring and connectors at encoder.
B	Encoder defective.	Replace the servomotor.
C	SERVOPACK defective.	Replace SERVOPACK.

■ A.CC

A.CC: Multiturn Limit Disagreement Alarm

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	OFF	ON	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm

At power ON — A, B

	Cause	Remedy
A	The setting of the Multiturn Limit Setting (Pn205) parameter in the SERVOPACK is incorrect.	Change parameter Pn205.
B	The multiturn limit has not been set in the encoder.	Check to be sure the Multiturn Limit Setting (Pn205) parameter in the SERVOPACK is correct, create a Multiturn Limit Disagreement Alarm (A.CC), and then execute the encoder multiturn limit setting change (Fn013).

■ A.d0

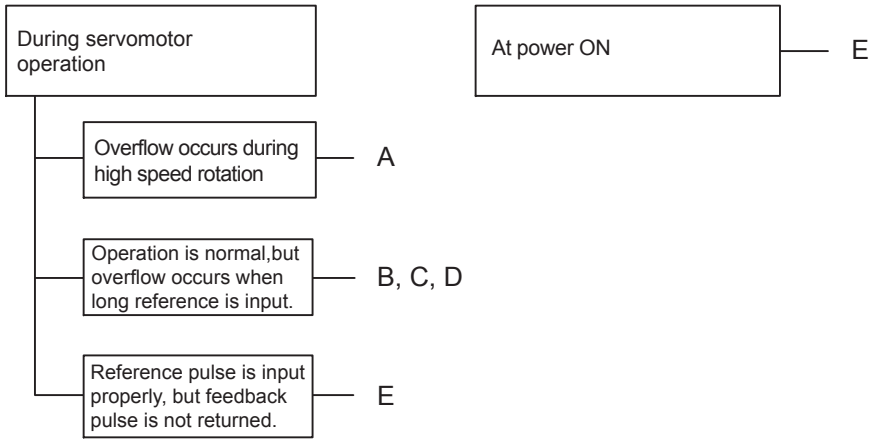
A.d0: Position Error Pulse Overflow

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	OFF	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	Servomotor wiring incorrect.	Check and correct wiring.
B	SERVOPACK was not correctly adjusted.	Increase speed loop gain (Pn100) and position loop gain (Pn102).
C	Motor load was excessive.	Reduce load torque and moment of inertia. Otherwise, replace with larger capacity servomotor.
D	Position reference pulse frequency was too high.	• Increase or decrease reference pulse frequency. • Add smoothing function. • Correct electronic gear ratio.
E	Circuit board (1PWB) defective.	Replace SERVOPACK.

■ A.E7

A.E7: Option Unit Detection Error

A.E7 occurs when the SGDH is used without option unit after it has been used with option unit.

This alarm cannot be cleared by alarm reset.

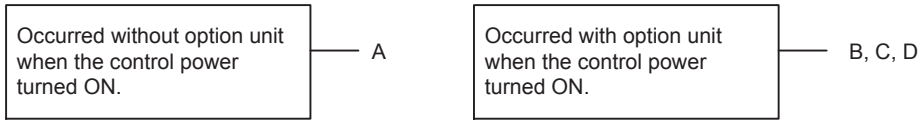
Clear the alarm by Fn014 (option unit detection result clear) of auxiliary function mode.

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
ON	ON	OFF	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	The SGDH is used without option unit after it has been used with option unit.	To continue using the SGDH without option unit, execute Fn014 (option unit detection result clear) of the auxiliary function mode and restart the power.
B	Option unit connection defective.	Check and correct the connection.
C	Option unit defective.	Replace option unit.
D	Connector Cn10 of SERVOPACK defective.	Replace SERVOPACK.

■ A.F1

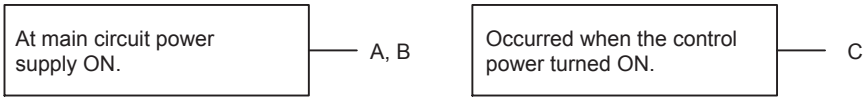
A.F1: Power Line Open Phase

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	ON	OFF	OFF

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

Status and Remedy for Alarm



Cause		Remedy
A	One phase (L1, L2, or L3) of the main circuit power supply is disconnected.	• Check power supply. • Check wiring of the main circuit power supply. • Check QF, noise filter, magnetic contactor.
B	There is one phase where the line voltage is low.	Check power supply.
C	SERVOPACK defective.	Replace SERVOPACK.

■ CPF00

CPF00: Digital Operator Transmission Error 1
This alarm is not stored in the alarm trace-back function memory.

This alarm is also temporarily displayed when an option unit and the Digital Operator are used at the same time and communications between the option unit and the SERVOPACK last for more than one second. Operation with the Digital Operator is disabled during this period.

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
Not specified			

Status and Remedy for Alarm

At power ON. Digital Operator connected before SERVOPACK power turned ON. — A, B, C, D

Digital Operator connected to SERVOPACK after power turned ON. — A, B, C, D

Cause		Remedy
A	Cable defective or poor contact between Digital Operator and SERVOPACK.	• Check connector connections. • Replace cable.
B	Malfunction due to external noise.	Separate Digital Operator and cable from noise source.
C	Digital Operator defective.	Replace Digital Operator.
D	SERVOPACK defective.	Replace SERVOPACK.

■ CPF01

CPF01: Digital Operator Transmission Error 2

This alarm is not stored in the alarm trace-back function memory.

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
Not specified			

Status and Remedy for Alarm

During operation — A, B, C, D

Cause		Remedy
A	Cable defective or poor contact between Digital Operator and SERVOPACK.	• Check connector connections. • Replace cable.
B	Malfunction due to external noise.	Separate Digital Operator and cable from noise source.
C	Digital Operator defective.	Replace Digital Operator.
D	SERVOPACK defective.	Replace SERVOPACK.

■ A.- -

A.- -: Normal Operation

This is not an alarm display.

Display and Outputs

Alarm Outputs			
Alarm Code Outputs			ALM Output
ALO1	ALO2	ALO3	
OFF	OFF	OFF	ON

Note: OFF:Output transistor is OFF (alarm state). ON: Output transistor is ON.

8.2.2 Troubleshooting Problems with No Alarm Display

Refer to the tables below to identify the cause of a problem which causes no alarm display and take the remedy described.

Turn OFF the servo system power supply before commencing the shaded procedures.

Contact your Yaskawa representative if the problem cannot be solved by the described procedures.

Table 8.4 Troubleshooting Table of No Alarm Display

Symptom	Cause	Inspection	Remedy
Servomotor Does Not Start	Power not connected	Check voltage between power supply terminals.	Correct the power circuit.
	Loose connection	Check terminals of connectors (CN1, CN2).	Tighten any loose parts.
	Connector (CN1) external wiring incorrect	Check connector (CN1) external wiring.	Refer to connection diagram and correct wiring.
	Servomotor or encoder wiring disconnected.		Reconnect wiring.
	Overloaded	Run under no load.	Reduce load or replace with larger capacity servomotor.
	Speed/position references not input	Check reference input pins.	Correctly input speed/position references.
	/S-ON is turned OFF	Check settings of parameters Pn50A.0 and Pn50A.1.	Turn /S-ON input ON.
	/P-CON input function setting incorrect	Check parameter Pn000.1.	Refer to section *4.3.5* and set parameters to match application.
	Reference pulse mode selection incorrect.	Refer to section *4.2.2*.	Correct setting of parameter Pn200.0.
	Encoder type differs from parameter setting.	Incremental or absolute encoder?	Set parameter Pn002.2 to the encoder type being used.
	P-OT and N-OT inputs are turned OFF.	Refer to section *4.1.2*.	Turn P-OT and N-OT input signals ON.
	CLR input is turned ON.	Check status of error counter clear input.	Turn CLR input OFF.
	SEN input is turned OFF.	When absolute encoder is used.	Turn SEN input ON.
Servomotor Moves Instantaneously, then Stops	Servomotor or encoder wiring incorrect.		Refer to section *2.3* and correct wiring.
Suddenly Stops during Operation and will Not Restart	Alarm reset signal (/ALM-RST) is turned ON because an alarm occurred.		Remove cause of alarm. Turn alarm reset signal (/ALM-RST) from ON to OFF.
Servomotor Speed Unstable	Wiring connection to motor defective	Check connection of power lead (phases U, V, and W) and encoder connectors.	Tighten any loose terminals or connectors.

Table 8.4 Troubleshooting Table of No Alarm Display (cont'd)

Symptom	Cause	Inspection	Remedy
Servomotor Vibrates at Approximately 200 to 400 Hz.	Speed loop gain value too high.		Reduce speed loop gain (Pn100) preset value.
	Speed/position reference input lead too long.		Minimize length of speed/position reference input lead, with impedance not exceeding several hundred ohms.
	Speed/position reference input lead is bundled with power cables.		Separate reference input lead at least 30 cm from power cables.
High Rotation Speed Overshoot on Starting and Stopping	Speed loop gain value too high.		Reduce speed loop gain (Pn100) preset value. Increase integration time constant (Pn101).
	Speed loop gain is too low compared to position loop gain.		Increase speed loop gain (Pn100) preset value. Reduce the integration time constant (Pn101).
Servomotor Overheated	Ambient temperature too high	Measure servomotor ambient temperature.	Reduce ambient temperature to 40°C max.
	Servomotor surface dirty	Visual check	Clean dust and oil from motor surface.
	Overloaded	Run under no load.	Reduce load or replace with larger capacity servomotor.
Abnormal Noise	Mechanical mounting incorrect	Servomotor mounting screws loose?	Tighten mounting screws.
		Coupling not centered?	Center coupling.
		Coupling unbalanced?	Balance coupling.
	Bearing defective	Check noise and vibration near bearing.	Consult your Yaskawa representative if defective.
	Machine causing vibrations	Foreign object intrusion, damage or deformation of sliding parts of machine.	Consult with machine manufacturer.
Speed Reference 0 V but Servomotor Rotates.	Speed reference voltage offset applied		Adjust reference offset. Refer to sections *6.2.4* and *6.2.5*.

8.2.3 Alarm Display Table

A summary of alarm displays and alarm code outputs is given in the following table.

Table 8.5 Alarm Display Table

Alarm Display	Alarm Code Outputs			ALM Output	Alarm Name	Meaning
	ALO1	ALO2	ALO3			
A.02	OFF	OFF	OFF	OFF	Parameter Breakdown*1	EEPROM data of SERVOPACK is abnormal.
A.03					Main Circuit Encoder Error	Detection data for power circuit is abnormal.
A.04					Parameter Setting Error*1	The parameter setting is outside the allowable setting range.
A.05					Combination Error	SERVOPACK and servomotor capacities do not match each other.
A.10	ON	OFF	OFF	OFF	Overcurrent or Heat Sink Overheated*1	An overcurrent flowed through the IGBT. Heat sink of SERVOPACK was overheated.
A.30	ON	ON	OFF	OFF	Regeneration Error Detected	• Regenerative circuit is faulty. • Regenerative resistor is faulty.
A.32					Regenerative Overload	Regenerative energy exceeds regenerative resistor capacity.
A.40	OFF	OFF	ON	OFF	Overvoltage*2	Main circuit DC voltage is excessively high.
A.41					Undervoltage*2	Main circuit DC voltage is excessively low.
A.51	ON	OFF	ON	OFF	Overspeed	Rotational speed of the motor is excessively high.
A.71	ON	ON	ON	OFF	Overload: High Load	The motor was operating for several seconds to several tens of seconds under a torque largely exceeding ratings.
A.72					Overload: Low Load	The motor was operating continuously under a torque largely exceeding ratings.
A.73					Dynamic Brake Overload	When the dynamic brake was applied, rotational energy exceeded the capacity of dynamic brake resistor.
A.74					Overload of Surge Current Limit Resistor	The main circuit power was frequently turned ON and OFF.
A.7A					Heat Sink Overheated	The heat sink of SERVOPACK overheated.

Table 8.5 Alarm Display Table (cont'd)

Alarm Display	Alarm Code Outputs			ALM Output	Alarm Name	Meaning
	ALO1	ALO2	ALO3			
A.81	OFF	OFF	OFF	OFF	Encoder Backup Error*1	All the power supplies for the absolute encoder have failed and position data was cleared.
A.82					Encoder Checksum Error*1	The checksum results of encoder memory is abnormal.
A.83					Absolute Encoder Battery Error	Battery voltage for the absolute encoder has dropped.
A.84					Encoder Data Error*1	Data in the encoder is abnormal.
A.85					Encoder Overspeed	The encoder was rotating at high speed when the power was turned ON.
A.86					Encoder Overheated	The internal temperature of encoder is too high.
A.b1					Reference Speed Input Read Error	The A/D converter for reference speed input is faulty.
A.b2					Reference Torque Input Read Error	The A/D converter for reference torque input is faulty.
A.bF					System Alarm*1	A system error occurred in the SERVOPACK.
A.C1	ON	OFF	ON	OFF	Servo Overrun Detected	The servomotor ran out of control.
A.C8					Absolute Encoder Clear Error and Multiturn Limit Setting Error*1	The multiturn for the absolute encoder was not properly cleared or set.
A.C9					Encoder Communications Error*1	Communications between SERVOPACK and encoder is not possible.
A.CA					Encoder Parameter Error*1	Encoder parameters are faulty.
A.Cb					Encoder Echoback Error*1	Contents of communications with encoder is incorrect.
A.CC					Multiturn Limit Disagreement	Different multiturn limits have been set in the encoder and SERVOPACK.
A.d0	ON	ON	OFF	OFF	Position Error Pulse Overflow	Position error pulse exceeded parameter (Pn505).
A.E7	OFF	ON	ON	OFF	Option Unit Detection Error	Option unit detection fails.
A.F1	OFF	ON	OFF	OFF	Power Line Open Phase	One phase is not connected in the main power supply.
CPF00	Not specified				Digital Operator Transmission Error	Digital Operator (JUSP-OP02A-2) fails to communicate with SERVOPACK (e.g., CPU error).
CPF01						
A.- -	OFF	OFF	OFF	ON	Not an error	Normal operation status

Note: OFF: Output transistor is OFF (high). ON: Output transistor is ON (low).

* 1. These alarms are not reset for the alarm reset signal (/ALM-RST). Eliminate the cause of the alarm and then turn OFF the power supply to reset the alarms.

* 2. For the SERVOPACK with a capacity of 6.0 kW or higher, alarm 40 indicates main circuit DC voltage is excessively high or low.

8.2.4 Warning Displays

The relation between warning displays and warning code outputs are shown in the following table.

Table 8.6 Warning Displays and Outputs

Warning Display	Warning Code Outputs			Warning Name	Meaning of Warning
	ALO1	ALO2	ALO3		
A.91	ON	OFF	OFF	Overload	This warning occurs before the overload alarms (A.71 or A.72) occur. If the warning is ignored and operation continues, an overload alarm may occur.
A.92	OFF	ON	OFF	Regenerative Overload	This warning occurs before the regenerative overload alarm (A.32) occurs. If the warning is ignored and operation continues, a regenerative overload alarm may occur.
A.93	ON	ON	OFF	Absolute Encoder Battery Warning	This warning occurs when battery voltage for the absolute encoder has dropped. If the warning is ignored and operation continues, a regenerative overload alarm may occur.

Note: OFF: Output transistor is OFF (high). ON: Output transistor is ON (low).

8.2.5 Internal Connection Diagram and Instrument Connection Examples

The following diagrams show the SGDH SERVOPACK internal connection and instrument connection examples. Refer to these diagrams during inspection and maintenance.

■ Internal Connection Diagram

22 kW or 30 kW for 400 V

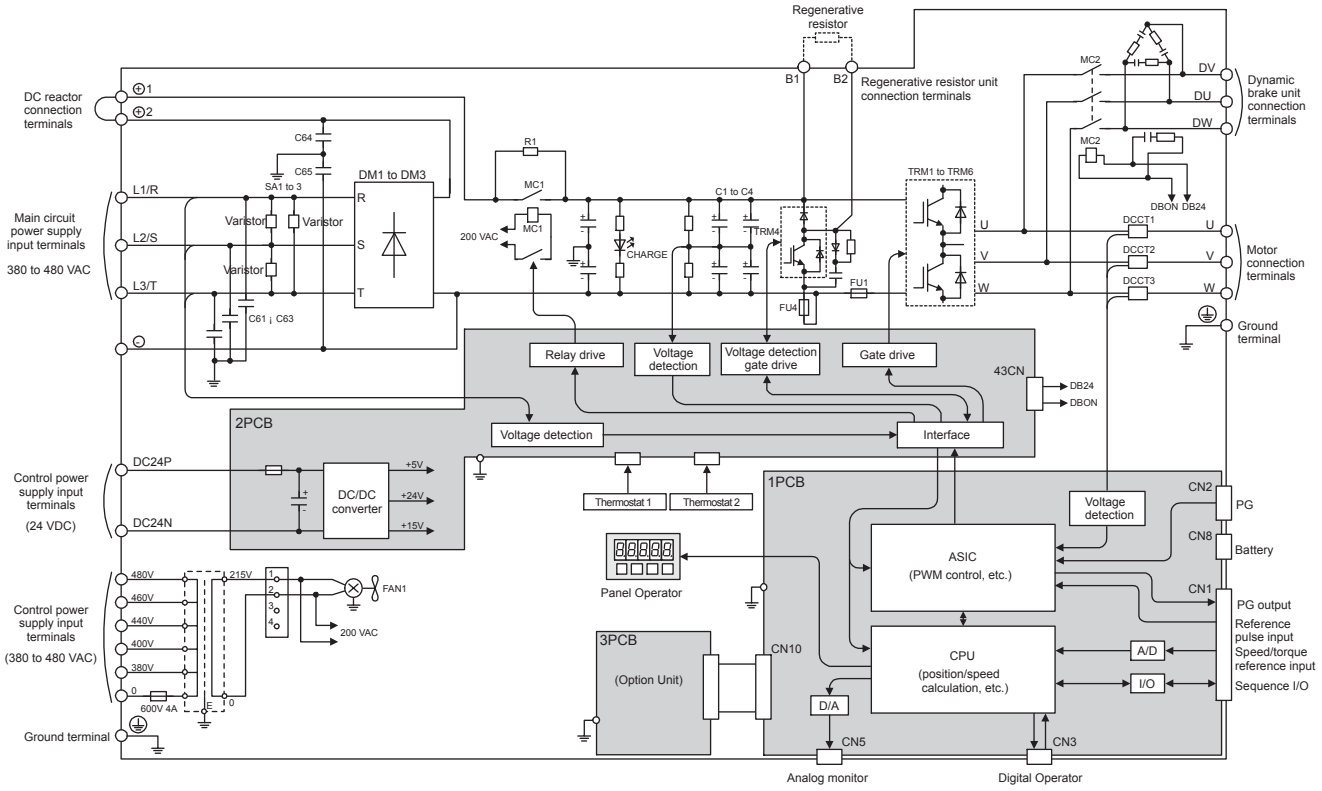


Fig. 8.1 SERVOPACK Internal Connection Diagram of 22 kW or 30 kW for 400 V

37 kW for 400 V

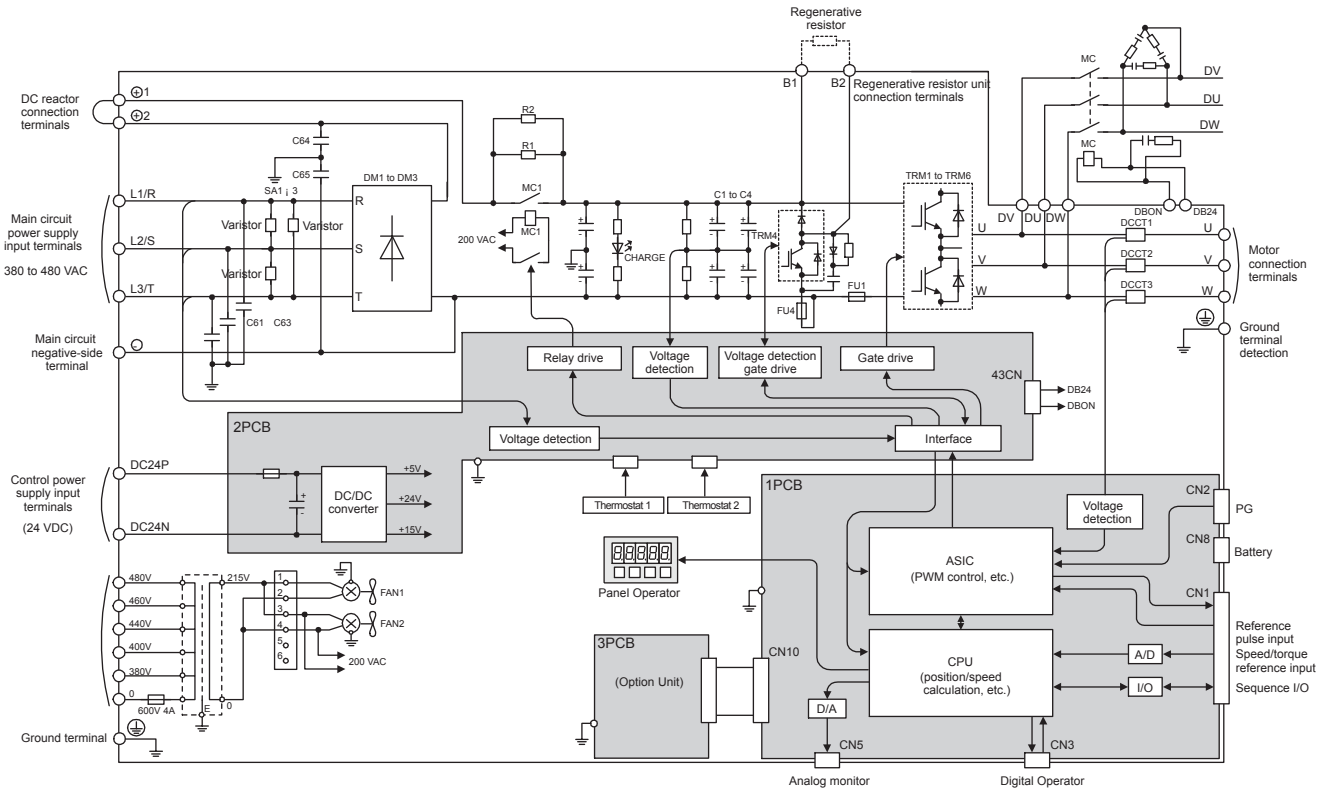


Fig. 8.2 SERVOPACK Internal Connection Diagram of 37 kW for 400 V

45 kW or 55 kW for 400 V

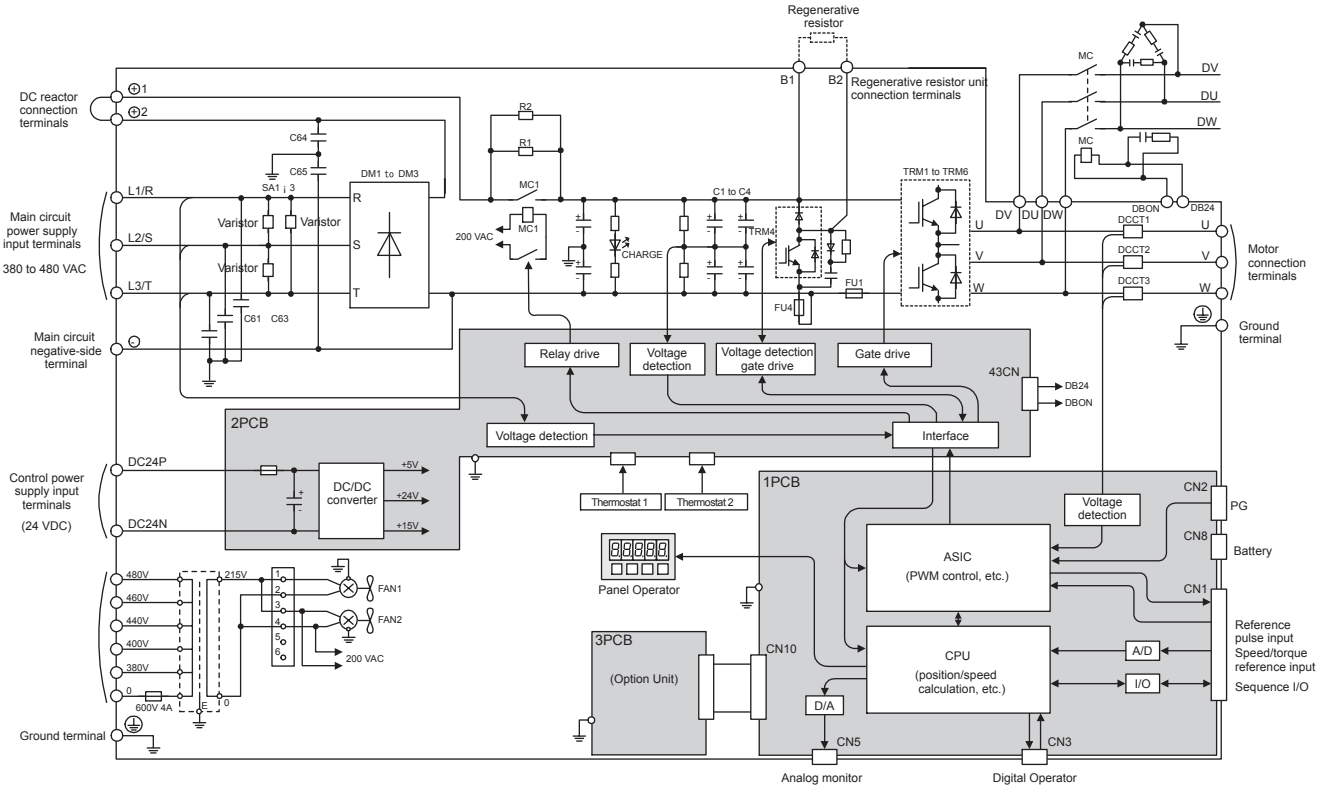
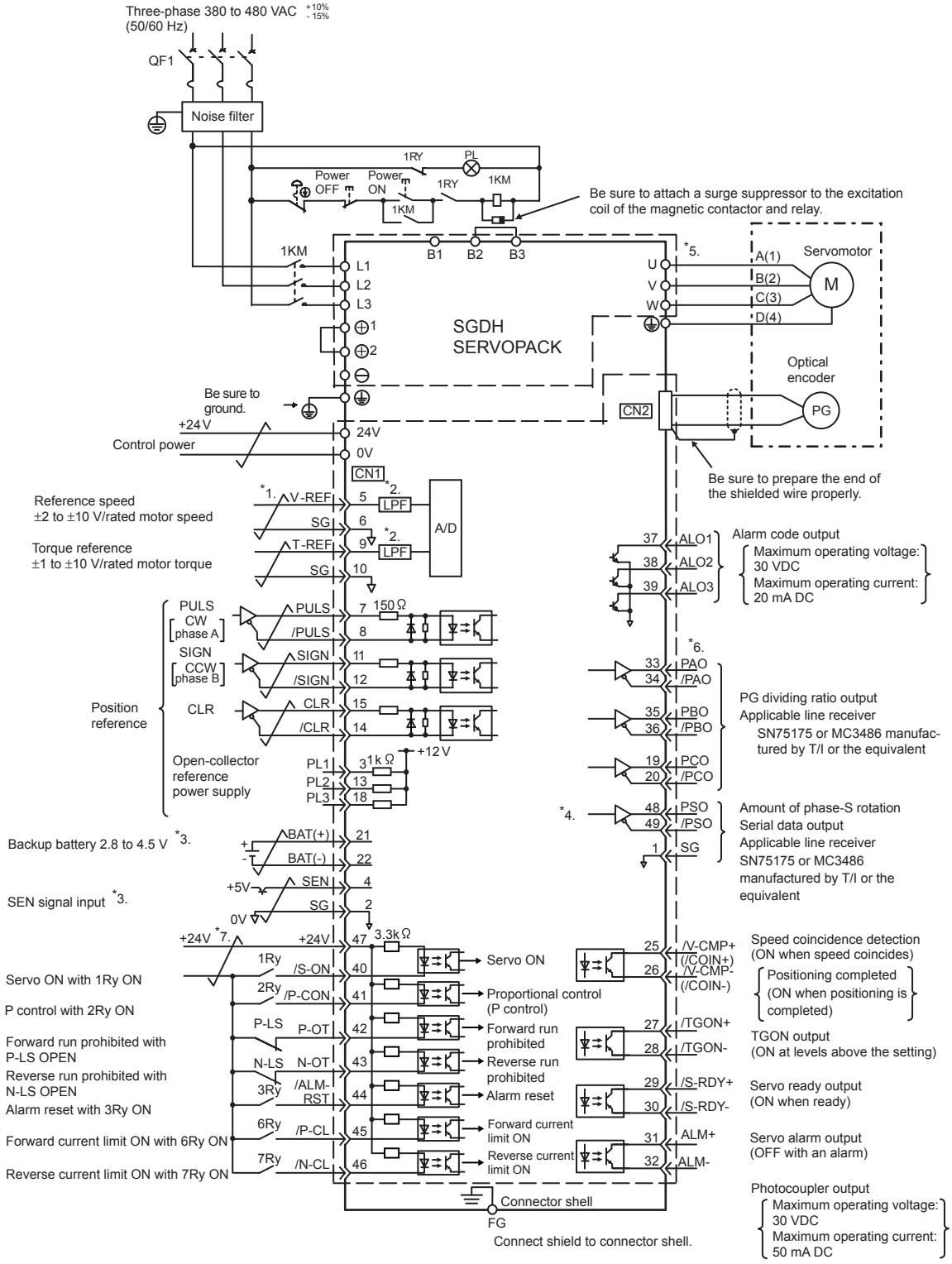


Fig. 8.3 SERVOPACK Internal Connection Diagram of 45 kW or 55 kW for 400 V

■ Instrument Connection Examples

The following diagram shows a connection example of reference and control I/O.



* 1. ⫫ represents twisted-pair wires.
* 2. The time constant for the primary filter is 47 μs.
* 3. Connect when using an absolute encoder.
* 4. Used only with an absolute encoder.
* 5. These circuits are hazardous and therefore, are separated by protecting separator.
* 6. These circuits are SELV circuits and are separated from all other circuits by double and reinforced insulation.
* 7. A double-insulated 24-VDC power supply must be supplied by the user.

Appendix A

List of Parameters

This appendix lists the parameters, switches, input signal selections, output signal selections, auxiliary functions, and monitor modes for SGDH SERVOPACKs.

A.1 Parameters - - -

A.1 Parameters

The following list shows parameters and their settings.

Table A.1 List of Parameters

Category	Parameter No.	Name	Unit	Setting Range	Factory Setting	Reference
Function Selection Constants	Pn000	Function Selection Basic Switches*3	-	-	0000	4.1.1, 4.3.5
	Pn001	Function Selection Application Switches 1*3	-	-	0000	4.1.2, 4.4.2, 4.5.7
	Pn002	Function Selection Application Switches 2*3	-	-	0000	4.2.8, 4.2.10, 4.7.2
	Pn003	Function Selection Application Switches 3	-	-	0002	5.5
	Pn004	Fixed Parameters (Do not change.)	-	-	0000	-
	Pn005		-	-	0000	-
Gain Related Constants	Pn100	Speed Loop Gain	Hz	1 to 2000	40	5.2.1
	Pn101	Speed Loop Integral Time Constant	0.01 ms	15 to 51200	2000	5.2.1
	Pn102	Position Loop Gain	1/s	1 to 2000	40	5.2.1
	Pn103	Inertia Ratio	%	0 to 10000	0	5.2.1, 5.3.3
	Pn104	2nd Speed Loop Gain	Hz	1 to 2000	40	-
	Pn105	2nd Speed Loop Integral Time Constant	0.01 ms	15 to 51200	2000	-
	Pn106	2nd Position Loop Gain	1/s	1 to 2000	40	-
	Pn107	Bias	min^{-1}	0 to 450	0	5.2.4
	Pn108	Bias Addition Width	reference units	0 to 250	7	5.2.4
	Pn109	Feed-forward	%	0 to 100	0	5.2.2
	Pn10A	Feed-forward Filter Time Constant	0.01 ms	0 to 6400	0	4.2.5
	Pn10B	Gain-related Application Switches*3	-	-	0000	5.2.5
	Pn10C	Mode Switch Torque Reference	%	0 to 800	200	5.2.5
	Pn10D	Mode Switch Speed Reference	min^{-1}	0 to 10000	0	5.2.5
	Pn10E	Mode Switch Acceleration	10 min^{-1}/s	0 to 3000	0	5.2.5
	Pn10F	Mode Switch Error Pulse	reference units	0 to 10000	0	5.2.5
	Pn110	Online Autotuning Switches*3	-	-	0010	5.3.4
	Pn111	Speed Feedback Compensation*2	%	1 to 500	100	5.2.6
	Pn112	Fixed Parameters (Do not change.)	%	0 to 1000	100	-
	Pn113		-	0 to 1000	1000	-
	Pn114		-	0 to 1000	200	-
	Pn115		-	0 to 65535	32	-
	Pn116		-	0 to 65535	16	-
	Pn117		%	20 to 100	100	-
	Pn118		%	50 to 100	100	-

Table A.1 List of Parameters (cont'd)

Category	Parameter No.	Name	Unit	Setting Range	Factory Setting	Reference
Gain Related Constants (cont'd)	Pn119	Fixed Parameters (Do not change.)	1/s	1 to 2000	50	-
	Pn11A		0.1%	1 to 2000	1000	-
	Pn11B		Hz	1 to 150	50	-
	Pn11C		Hz	1 to 150	70	-
	Pn11D		%	0 to 150	100	-
	Pn11E		%	0 to 150	100	-
	Pn11F		ms	0 to 2000	0	-
	Pn120		0.01 ms	0 to 51200	0	-
	Pn121		Hz	10 to 250	50	-
	Pn122		Hz	0 to 250	0	-
	Pn123		%	0 to 100	0	-
Position Related Constants	Pn200	Position Control Reference Selection Switches*3	-	-	0000	4.2.2
	Pn201	PG Divider*3	P/r	16 to 16384	16384	4.2.3
	Pn202	Electronic Gear Ratio (Numerator) *3	-	1 to 65535	4	4.2.5
	Pn203	Electronic Gear Ratio (Denominator) *3	-	1 to 65535	1	4.2.5
	Pn204	Position Reference Accel/ Decel Time Constant	0.01 ms	0 to 6400	0	5.1.2
	Pn205	Multiturn Limit Setting*1, *3	rev	0 to 65535	65535	4.7.6
	Pn206	Fixed Parameter (Do not change.)	P/rev	513 to 65535	16384	-
	Pn207	Position Control Function Switches*3	-	-	0000	4.2.9, 5.1.2
	Pn208	Position Reference Movement Averaging Time*3	0.01 ms	0 to 6400	0	5.1.2
Speed Related Constants	Pn300	Speed Reference Input Gain	0.01V/rated speed	150 to 3000	600	4.2.1
	Pn301	Speed 1	min^{-1}	0 to 10000	100	4.2.6
	Pn302	Speed 2	min^{-1}	0 to 10000	200	4.2.6
	Pn303	Speed 3	min^{-1}	0 to 10000	300	4.2.6
	Pn304	Jog Speed	min^{-1}	0 to 10000	500	4.3.2
	Pn305	Soft Start Acceleration Time	ms	0 to 10000	0	5.1.1
	Pn306	Soft Start Deceleration Time	ms	0 to 10000	0	5.1.1
	Pn307	Speed Reference Filter Time Constant	0.01 ms	0 to 65535	40	-
	Pn308	Speed Feed-forward Filter Time Constant	0.01 ms	0 to 65535	0	-

Table A.1 List of Parameters (cont'd)

Category	Parameter No.	Name	Unit	Setting Range	Factory Setting	Reference
Torque Related Constants	Pn400	Torque Reference Input Gain	0.1 V/rated torque	10 to 100	30	4.2.7
	Pn401	Torque Reference Filter Time Constant	0.01 ms	0 to 65535	100	5.1.5
	Pn402	Forward Torque Limit	%	0 to 800	800	4.1.3
	Pn403	Reverse Torque Limit	%	0 to 800	800	4.1.3
	Pn404	Forward External Torque Limit	%	0 to 800	100	4.1.3
	Pn405	Reverse External Torque Limit	%	0 to 800	100	4.1.3
	Pn406	Emergency Stop Torque	%	0 to 800	800	4.1.2
	Pn407	Speed Limit during Torque Control	min^{-1}	0 to 10000	10000	4.2.7
	Pn408	Torque Function Switches	-	-	0000	5.1.6
	Pn409	Notch Filter Frequency	Hz	50 to 2000	2000	5.1.6
Sequence Related Constants	Pn500	Positioning Completed Width	reference units	0 to 250	7	4.5.3
	Pn501	Zero Clamp Level	min^{-1}	0 to 10000	10	4.4.3
	Pn502	Rotation Detection Level	min^{-1}	1 to 10000	20	4.5.5
	Pn503	Speed Coincidence Signal Output Width	min^{-1}	0 to 100	10	4.5.4
	Pn504	NEAR Signal Width	reference units	1 to 250	7	4.5.8
	Pn505	Overflow Level	256 reference units	1 to 32767	1024	5.2.1
	Pn506	Brake Reference Servo OFF Delay Time	10 ms	0 to 50	0	4.4.4
	Pn507	Brake Reference Output Speed Level	min^{-1}	0 to 10000	100	4.4.4
	Pn508	Timing for Brake Reference Output during Motor Operation	10 ms	10 to 100	50	4.4.4
	Pn509	Momentary Hold Time	ms	20 to 1000	20	4.5.9
	Pn50A	Input Signal Selections 1*3	-	-	2100	4.3.3
	Pn50B	Input Signal Selections 2*3	-	-	6543	4.3.3
	Pn50C	Input Signal Selections 3*3	-	-	8888	4.3.3
	Pn50D	Input Signal Selections 4*3	-	-	8888	4.3.3
	Pn50E	Output Signal Selections 1*3	-	-	3211	4.3.4
	Pn50F	Output Signal Selections 2*3	-	-	0000	4.3.4
	Pn510	Output Signal Selections 3*3	-	-	0000	4.3.4
	Pn511	Fixed Parameter (Do not change.)	-	-	8888	-
	Pn512	Output Signal Reversal Settings*3	-	-	0000	4.3.4
Other Constants	Pn600	Regenerative Resistor Capacity*4	10 W	0 to capacity*5	0	4.6
	Pn601	Fixed Parameter (Do not change.)	-	0 to capacity*5	0	-

* 1. The multiturn limit value must be changed only for special applications. Changing it inappropriately or unintentionally can be dangerous.

* 2. The setting of parameter Pn111 is valid only when parameter Pn110.1 is set to 0.
* 3. After changing these parameters, turn OFF the main circuit and control power supplies and then turn them ON again to enable the new settings. (except Pn110.1 and Pn110.2)
* 4. Normally set to “0.” When installing an external regenerative resistor, set the regenerative resistors capacity (W).
* 5. The upper limit is the maximum output capacity (W) of the SERVOPACK.

A.2 Switches

The following list shows the switches and their factory settings.

Table A.2 List of Switches

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn000 Function Selection Basic Switches	0	Rotation Direction Selection	0	Sets CCW as forward direction.	0
			1	Sets CW as forward direction (reverse rotation mode).	
	1	Control Method Selection	0	Speed control (analog reference)	0
			1	Position control (pulse train reference)	
			2	Torque control (analog reference)	
			3	Internal set speed control (contact reference)	
			4	Internal set speed control (contact reference)/Speed control (analog reference)	
			5	Internal set speed control (contact reference)/Position control (pulse train reference)	
			6	Internal set speed control (contact reference)/Torque control (analog reference)	
			7	Position control (pulse train reference)/Speed control (analog reference)	
			8	Position control (pulse train reference)/Torque control (analog reference)	
			9	Torque control (analog reference)/Speed control (analog reference)	
			A	Speed control (analog reference)/Zero clamp	
			B	Position control (pulse train reference)/Position control (Inhibit)	
	2	Axis Address	0 to F	Sets SERVOPACK axis address.	0
	3	Reserved		-	0

Table A.2 List of Switches (cont'd)

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn001 Function Selection Application Switches	0	Servo OFF or Alarm Stop Mode	0	Stops the motor by applying dynamic brake (DB).	0
			1	Stops the motor by applying dynamic brake (DB) and then releases DB.	
			2	Makes the motor coast to a stop state without using the dynamic brake (DB).	
	1	Overtravel Stop Mode	0	Same setting as Pn001.0 (Stops the motor by applying DB or by coasting.)	0
			1	Sets the torque of Pn406 to the maximum value, decelerates the motor to a stop, and then sets it to servolock state.	
			2	Sets the torque of Pn406 to the maximum value, decelerates the motor to a stop, and then sets it to coasting state.	
	2	AC/DC Power Input Selection	0	Not applicable to DC power input: Input AC power supply through L1, L2, and (L3) terminals.	0
			1	Applicable to DC power input: Input DC power supply through (+)1 and (-) terminals.	
	3	Warning Code Output Selection	0	ALO1, ALO2 and ALO3 output only alarm codes.	0
			1	ALO1, ALO2 and ALO3 output both alarm codes and warning codes. While warning codes are output, ALM signal output remains ON (normal state).	
Pn002 Function Selection Application Switches	0	Speed, Position Control Option (T-REF Terminal Allocation)	0	None	0
			1	Uses T-REF as an external torque limit input.	
			2	Uses T-REF as a torque feed-forward input.	
			3	Uses T-REF as an external torque limit input when P-CL and N-CL are ON.	
	1	Torque Control Option (V-REF Terminal Allocation)	0	None	0
			1	Uses V-REF as an external speed limit input.	
	2	Absolute Encoder Usage	0	Uses absolute encoder as an absolute encoder.	0
			1	Uses absolute encoder as an incremental encoder.	
	3	Fixed Parameter (Do not change.)	0 to 4	-	0

Table A.2 List of Switches (cont'd)

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn003 Function Selection Application Switches	0	Analog Monitor 1 Torque Reference Monitor	0	Motor speed: 1 V/1000 min^{-1}	2
			1	Speed reference: 1 V/1000 min^{-1}	
			2	Torque reference: 1 V/100%	
	1	Analog Monitor 2 Speed Reference Monitor	3	Position error: 0.05 V/1 reference unit	0
			4	Position error: 0.05 V/100 reference unit	
			5	Reference pulse frequency (converted to min^{-1}): 1 V/1000 min^{-1}	
			6	Motor speed × 4: 1 V/250 min^{-1}	
			7	Motor speed × 8: 1 V/125 min^{-1}	
			8	Fixed Parameters (Do not change.)	
			9		
			A		
			B		
			C		
			D		
			E		
			F		
	2	Not used.		-	0
	3	Not used.		-	0
Pn10B	0	Mode Switch Selection	0	Uses internal torque reference as the condition (Level setting: Pn10C)	0
			1	Uses speed reference as the condition (Level setting: Pn10D)	
			2	Uses acceleration as the condition (Level setting: Pn10E)	
			3	Uses error pulse as the condition (Level setting: Pn10F)	
			4	No mode switch function available	
	1	Speed Loop Control Method	0	PI control	0
			1	IP control	
	2	Not used.	0	-	0
	3	Fixed Parameter (Do not change.)	0 to 2	-	0

Table A.2 List of Switches (cont'd)

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn110 Online Autotuning Switches	0	Online Autotuning Method	0	Tunes only at the beginning of operation.	0
			1	Always tunes.	
			2	Does not perform autotuning.	
	1	Speed Feedback Compensation Selection	0	Enabled	1
			1	Disabled	
	2	Friction Compensation Selection	0	Friction compensation: Disabled	0
			1	Friction compensation: Small	
			2	Friction compensation: Large	
	3	Fixed Parameter (Do not change.)	0 to 3	-	0
Pn200 Position Control References Selection Switches	0	Reference Pulse Form	0	Sign + pulse, positive logic	0
			1	CW + CCW, positive logic	
			2	Phase A + phase B (×1), positive logic	
			3	Phase A + phase B (×2), positive logic	
			4	Phase A + phase B (×4), positive logic	
			5	Sign + pulse, negative logic	
			6	CW + CCW, negative logic	
			7	Phase A + phase B (×1), negative logic	
			8	Phase A + phase B (×2), negative logic	
			9	Phase A + phase B (×4), negative logic	
	1	Error Counter Clear Signal Form	0	Clears error counter when the signal goes high.	0
			1	Clears error counter at the rising edge of the signal.	
			2	Clears error counter when the signal goes low.	
			3	Clears error counter at the falling edge of the signal.	
	2	Clear Operation	0	Clears error counter at the baseblock.	0
			1	Does not clear error counter. (Possible to clear error counter only with CLR signal.)	
			2	Clears error counter when an alarm occurs.	
	3	Filter Selection	0	Reference input filter for line driver signals	0
			1	Reference input filter for open collector signals	
Pn207 Position Control Function Switches	0	Position Reference Filter Selection	0	Acceleration/deceleration filter	0
			1	Average movement filter	
	1	Position Control Option	0	Disabled	0
			1	Uses V-REF as a speed feed-forward input.	
	2	Not used.		-	0
	3	Not used.		-	0

Table A.2 List of Switches (cont'd)

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn408 Torque Function Switches	0	Notch Filter Selection	0	Disabled	0
			1	Uses a notch filter for torque reference.	
	1	Not used.		-	0
	2	Not used.		-	0
	3	Not used.		-	0

A.3 Input Signal Selections

The following list shows input signal selections and their factory settings.

Table A.3 Input Signal Selections

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn50A	0	Input Signal Allocation Mode	0	Sets the input signal allocation for the sequence to the same one as for the SGDB SERVOPACK. *	0
			1	Possible to freely allocate the input signals.	
	1	/S-ON Signal Mapping (Servo ON when low.)	0	Inputs from the SI0 (CN1-40) input terminal.	0: SI0
			1	Inputs from the SI1 (CN1-41) input terminal.	
			2	Inputs from the SI2 (CN1-42) input terminal.	
			3	Inputs from the SI3 (CN1-43) input terminal.	
			4	Inputs from the SI4 (CN1-44) input terminal.	
			5	Inputs from the SI5 (CN1-45) input terminal.	
			6	Inputs from the SI6 (CN1-46) input terminal.	
			7	Sets signal ON.	
			8	Sets signal OFF.	
			9	Inputs the reverse signal from the SI0 (CN1-40) input terminal.	
			A	Inputs the reverse signal from the SI1 (CN1-41) input terminal.	
			B	Inputs the reverse signal from the SI2 (CN1-42) input terminal.	
			C	Inputs the reverse signal from the SI3 (CN1-43) input terminal.	
			D	Inputs the reverse signal from the SI4 (CN1-44) input terminal.	
			E	Inputs the reverse signal from the SI5 (CN1-45) input terminal.	
			F	Inputs the reverse signal from the SI6 (CN1-46) input terminal.	
	2	/P-CON Signal Mapping (P control when low.)	0 to F	Same as above.	1: SI1
	3	P-OT Signal Mapping (Overtravel when high.)	0 to F	Same as above.	2: SI2
Pn50B	0	N-OT Signal Mapping (Overtravel when high.)	0 to F	Same as above.	3: SI3
	1	/ALM-RST Signal Mapping (Alarm reset when low.)	0 to F	Same as above.	4: SI4
	2	/P-CL Signal Mapping (Torque control when low.)	0 to F	Same as above.	5: SI5
	3	/N-CL Signal Mapping (Torque control when low.)	0 to F	Same as above.	6: SI6

Table A.3 Input Signal Selections (cont'd)

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn50C	0	/SPD-D Signal Mapping (Internal Set Speed Selection)	0 to F	Same as above.	8: OFF
	1	/SPD-A Signal Mapping (Internal Set Speed Selection)	0 to F	Same as above.	8: OFF
	2	/SPD-B Signal Mapping (Internal Set Speed Selection)	0 to F	Same as above.	8: OFF
	3	/C-SEL Signal Mapping (Control Mode Switching)	0 to F	Same as above.	8: OFF
Pn50D	0	/ZCLAMP Signal Mapping (Zero Clamping)	0 to F	Same as above.	8: OFF
	1	/INHIBIT Signal Mapping (Disabling Reference Pulse)	0 to F	Same as above.	8: OFF
	2	/G-SEL Signal Mapping (Gain Switching)	0 to F	Same as above.	8: OFF
	3	(Reserved)	0 to F	Same as above.	8: OFF

* When Pn50A.0 is set to 0 for the SGDB SERVOPACK, only the following modes are compatible: Pn50A.1=7, Pn50A.3=8, and Pn50B.0=8.

A.4 Output Signal Selections

The following list shows output signal selections and their factory settings.

Parameter	Digit Place	Name	Setting	Contents	Factory Setting
Pn50E	0	/COIN Signal Mapping	0	Disabled.	1: SO1
			1	Outputs from the SO1 (CN1-25, 26) output terminal.	
			2	Outputs from the SO2 (CN1-27, 28) output terminal.	
			3	Outputs from the SO3 (CN1-29, 30) output terminal.	
	1	/V-CMP Signal Mapping	0 to 3	Same as above.	1: SO1
	2	/TGON Signal Mapping	0 to 3	Same as above.	2: SO2
	3	/S-RDY Signal Mapping	0 to 3	Same as above.	3: SO3
Pn50F	0	/CLT Signal Mapping	0 to 3	Same as above.	0: Not used
	1	/VLT Signal Mapping	0 to 3	Same as above.	0: Not used
	2	/BK Signal Mapping	0 to 3	Same as above.	0: Not used
	3	/WARN Signal Mapping	0 to 3	Same as above.	0: Not used
Pn510	0	/NEAR Signal Mapping	0 to 3	Same as above.	0: Not used
	1	Reserved	0 to 3	Same as above.	0: Not used
	2	Not used.	0	-	0
	3	Not used.	0	-	0
Pn512	0	Output Signal Reversal for SO1 (CN1-25 and 26)	0	Output signal not reversed.	0: Not reversed
			1	Output signal reversed.	
	1	Output Signal Reversal for SO2 (CN1-27 and 28)	0	Output signal not reversed.	0: Not reversed
			1	Output signal reversed.	
	2	Output Signal Reversal for SO3 (CN1-29 and 30)	0	Output signal not reversed.	0: Not reversed
			1	Output signal reversed.	
	3	Not used.	-	-	0

Note: 1. When more than one signal is allocated to the same output circuit, data is output using OR logic.
2. Depending on the control mode, undetected signals are treated as OFF. For example, in the speed control mode, the /COIN signal is treated as OFF.
3. Types of /WARN signals: Overload and regenerative overload.

A.5 Auxiliary Functions

The following list shows the available auxiliary functions.

Parameter	Function
Fn000	Alarm traceback data display
Fn001	Rigidity setting during online autotuning
Fn002	JOG mode operation
Fn003	Zero-point search mode
Fn004	(Fixed parameter)
Fn005	Parameter settings initialization
Fn006	Alarm traceback data clear
Fn007	Writing inertia ratio data obtained from online autotuning to EEPROM
Fn008	Absolute encoder multiturn reset and encoder alarm reset.
Fn009	Automatic tuning of analog (speed, torque) reference offset
Fn00A	Manual adjustment of speed reference offset
Fn00B	Manual adjustment of torque reference offset
Fn00C	Manual zero-adjustment of analog monitor output
Fn00D	Manual gain-adjustment of analog monitor output
Fn00E	Automatic offset-adjustment of motor current detection signal
Fn00F	Manual offset-adjustment of motor current detection signal
Fn010	Password setting (protects parameters from being changed)
Fn011	Motor models display
Fn012	SERVOPACK Software version display
Fn013	Multiturn limit value setting change when a Multiturn Limit Disagreement Alarm (A.CC) occurs
Fn014	Option unit detection results clear

A.6 Monitor Modes

The following list shows monitor modes available.

Parameter	Content of Display	Unit	Remarks
Un000	Actual motor speed	min^{-1}	-
Un001	Input speed reference	min^{-1}	-
Un002	Internal torque reference	%	Value for rated torque
Un003	Rotation angle 1	pulse	Number of pulses from the origin
Un004	Rotation angle 2	deg	Angle (electrical angle) from the origin
Un005	Input signal monitor	-	-
Un006	Output signal monitor	-	-
Un007	Input reference pulse speed	min^{-1}	-
Un008	Error counter value	reference units	Amount of position error
Un009	Accumulated load rate	%	Value for the rated torque as 100%. Displays effective torque in 10-s cycle.
Un00A	Regenerative load rate	%	Value for the processable regenerative power as 100%. Displays regenerative consumption power in 10-s cycle.
Un00B	Power consumed by DB resistance	%	Value for the processable power when dynamic brake is applied as 100%. Displays DB power consumption in 10-s cycle.
Un00C	Input reference pulse counter	-	Displayed in hexadecimal.
Un00D	Feedback pulse counter	-	Displayed in hexadecimal.

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