

BH-SD Series AC Servo Driver Manual



BH-130SM-INC-1.3KW

Thank you for choosing SDD series servo driver. Please read this manual before using. The main contents of this manual include:

- * Servo driver inspection, installation and wiring steps.
- * Digital panel operation steps, status display, trouble alarm and disposal.
- * Servo system control mode, trial running and adjustment steps.
- * List of all the parameters of the servo drives.
- * Servo drives specifications.

For daily inspection, maintenance, finding the exception reasons and countermeasures, please keep this manual for easy reference.

Note: Please give this manual to the end user so as to maximize the utility of the servo drives.

- The manual contents may be changed due to the product improvements, there will be no prior notice.

- Any changes made to the product by users, the company will not undertake any responsibility and the product warranty will be invalid.

When reading this manual, please pay special attention to the following warning signs



Indicates the wrong operation may cause disastrous consequences—death or serious injury!



Indicates the wrong operation may hurt the operator and also make damage to the equipment!



Indicates improper use may damage the product and equipment!

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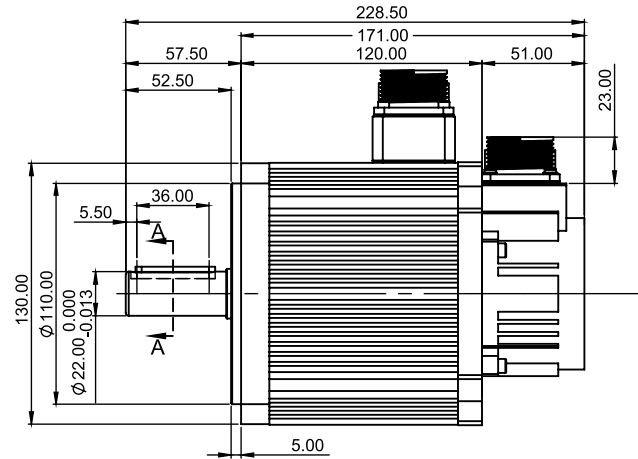
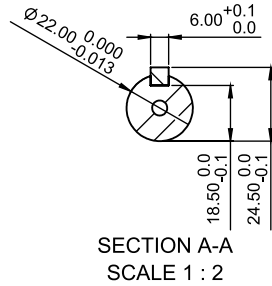
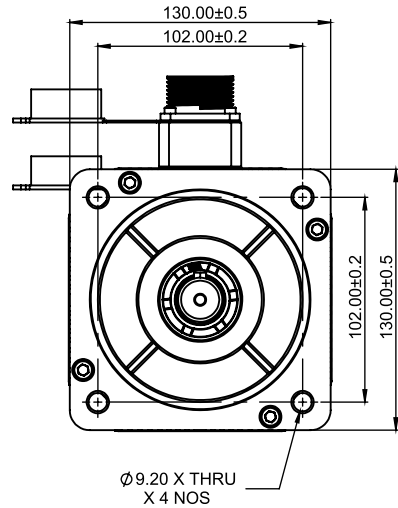
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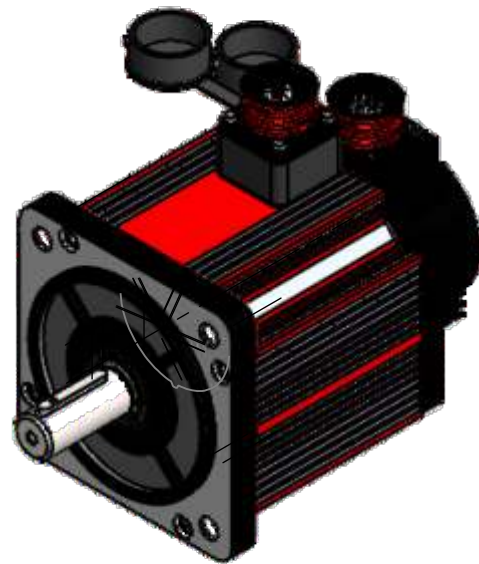
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DIMENSIONS AND TECHNICAL DETAILS.



| MOTOR MODEL | BH-130SM-1.3KW |
|------------------------------|-----------------------------|
| Rated Power (KW) | 1.3 |
| Rated Voltage (V) | 230 |
| Rated Current (A) | 5 |
| Peak Current (A) | 15 |
| Rated Speed (RPM) | 2500 |
| Rated Torque (Nm) | 5 |
| Peak Torque (N.M) | 15 |
| Back emf(v/1000r/min) | 68 |
| Torque Coefficient (Nm/A) | 1.0 |
| Rotor Inertia (Kg.MP) | 1.06X10 ⁻³ |
| Winding Resistance (Ω) | 1.54 |
| Winding Inductance (mH) | 4.9 |
| Electrical Time Constant(ms) | 2.66 |
| Weight (KG) | 8.2 |
| No of Encoder Lines (PPR) | 2500 |
| Insulation Class | Class F(130 ^o c) |
| Safety Class | IP 65 |



Motor Options Available -
 Standard Model - BH-130SM-INC-1.3KW
 With Low Backlash Planetary Gearbox - PL
 With Electro Magnetic Brake - BRK
 With Helical Gearbox - HL
 CE Certificate - N - STANDARD/CE - CERTIFIED
ORDERING CODE - BH-130SM-INC-1.3KW

Temperature; -20^oc to +40^oc, humidity; relative humidity < 90%

Chapter 1 Product inspection and installation

Summarize

SDD series servo is our third generation servo. All the input and output port can define itself, which is convenient to the user; standard RS485 communication function, realize uploads and downloads network control; internal simple PLC function, the PLC can be completely eliminated in some easy control occasions so as to lower the cost. Compare with the second generation SDB series servo, it has obvious improvement on the function and performance.

1.1 Product inspection

Our servo products have been done a completely functional test before leaving factory, in order to prevent the product exception in the process of shipment, please check the following items carefully when open the package:

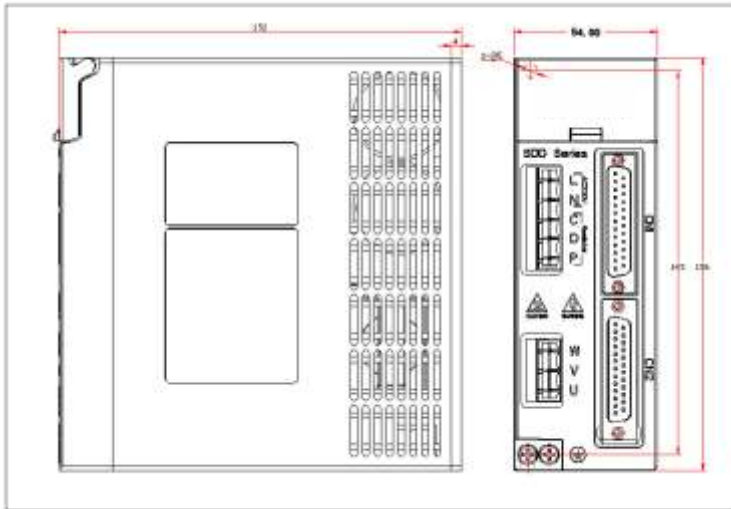
- 1) Check the servo drive and motor model whether same as ordered.
- 2) Check the servo drive and motor appearance whether with damage or scratch. If there is any above mentioned defective or abnormal signs, please contact with local distributors immediately.

Chapter 1 Product inspection and installation

1.1.2 SDD servo drive attached standard accessories

- ① CN1 plug(DB25 hole) 1 set
- ② CN2 plug(DB25 pin) 1 set
- ③ 5 pin power plug 1 piece
- ④ 3 pin power plug 1piece
- ⑤ RS485 communication line(model CABLE01) 2 piece **optional**
- ⑥ Debugging communication line(model CABLE02) 1 piece **optional**

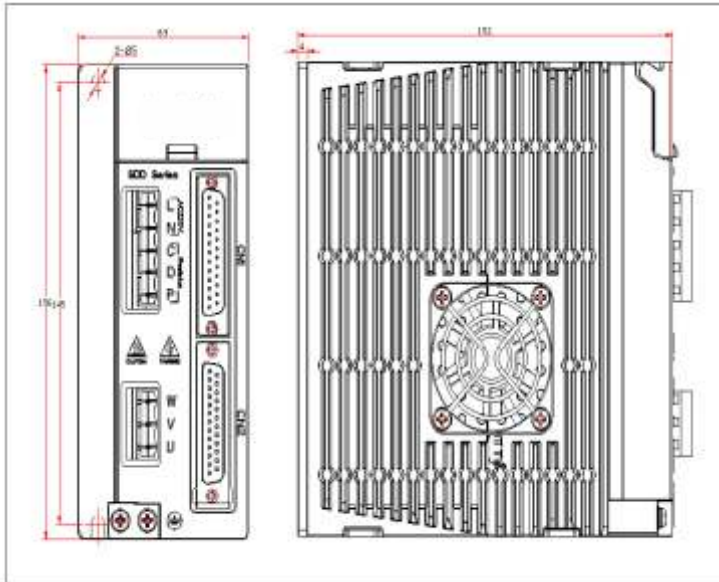
1.1.3 Servo drive installation size



Chapter 1 Product inspection and installation

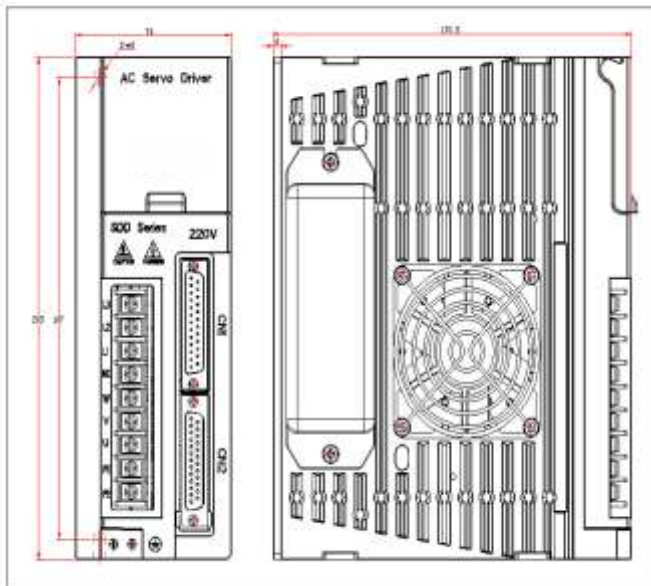
BH-SD servo drive installation dimensional

!!!!Notice: L N is 220V power supply , PD,C is external braking resistor terminals. It can not be connected wrong



servo drive installation dimensional

!!!!Notice: L N is 220V power supply, PD,C is external braking resistor terminals. It can not be connected wrong



1.2 Servo drive specifications

| | | BH-SD-INC | |
|------------------------|------------------------------|--|--|
| Basic specifications | mode | | |
| | Maximum current(A) | | 18.0 |
| | Power supply | | single phase AC170~253V 50/60Hz |
| | Cooling method | | Natural cooling/ fan Cooling |
| | Control method | | SVPWM control |
| | Encoder | | Provincial line or incremental encoder |
| | Internal functions | display and operation | |
| Control model | | position control / speed trial run / jog run / internal positioning PLC function/RS485 communication/ speed/ torque | |
| Braking function | | Internally installed | |
| Protection function | | Under voltage, over voltage, over load, over current, encoder exception, braking, position error etc. | |
| Position control model | Command control model | | External pulse |
| | External command pulse input | Form | pulse+ direction cw/ccw A/B orthogonality |
| | | Maximum frequency | Differential motion:1MHZ open collector: 200KHZ |
| | Electronic gear ratio | | 1/32767~1/32767 |
| | Speed control range | | speed ratio: 1:5000 |
| | Speed rate of change | | Speed fluctuation ratio: $\leq \pm 0.03$ (load 0~100%) . $\leq \pm 0.05$ (power-15%~+10%) |
| | Command smooth way | | Linear time constant 1ms 10000ms (0r/min \longleftrightarrow 1000r/min) |
| | frequency characteristic | | 300HZ |
| input / output signal | location signal output | output type | ABZ phase line drive output/ Z open collector output |
| | | Frequency division ratio | 1/225~1Frequency division |
| | input signal | 7 points photoelectric isolation input | Input point can be defined as any 21kinds, see parameter settings |
| | output signal | 4 collector open | 1) location/speed reach 2) servo alarm output 3) Z signal output 4) brake output. Freely defined |
| Usage temperature | | Operation:0°C~55°C storage:-20°C~80°C | |

Chapter 1 Product inspection and installation

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1.3 Servo drive installation

1.3.1 Installation environment conditions

Servo drive installation environment has a direct effect on the servo function and service life, therefore, the drive installation environment conditions must comply with following conditions:

| Items | SDD servo drive |
|------------------------------|---|
| usage temperature/ humidity | 0°C ~55°C (no frozen frost) 90%RH below (no condensation) |
| storage temperature/humidity | -20°C ~80°C 90%RH (no condensation) |
| atmospheric environment | In control cabinet, no corrosive gas, inflammable gas, oil mist or dust etc |
| vibration | less than 0.5G (4.9m/s ²) 10 Hz -60Hz (not run continuously) |
| Protection level | Ip54 |

When several drives installed in the control cabinet, please keep enough space for sufficient heat dissipation; please add an additional cooling fan to keep the drive ambient temperature below 55 °C .

Please install the drive by vertical way, face forward, top up for heat dissipation.

Avoid any drilling cuttings or other things falling in the drive during assembly.

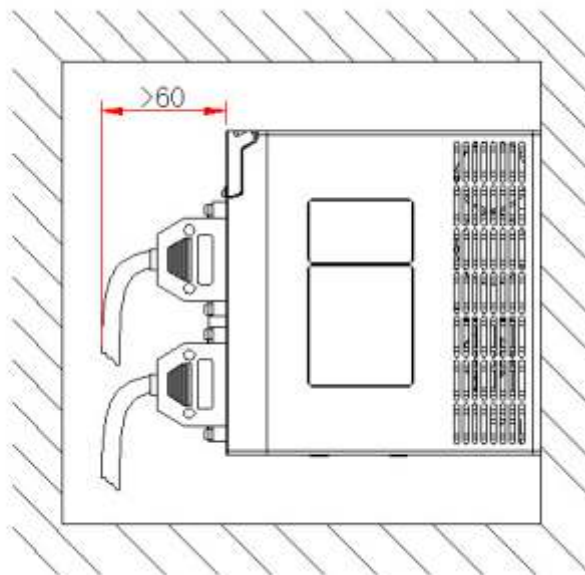
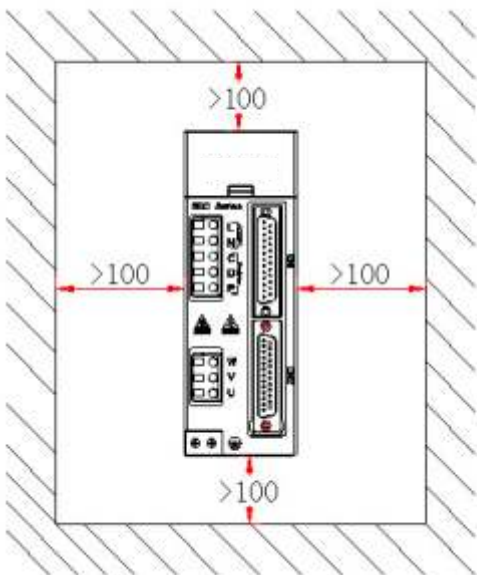
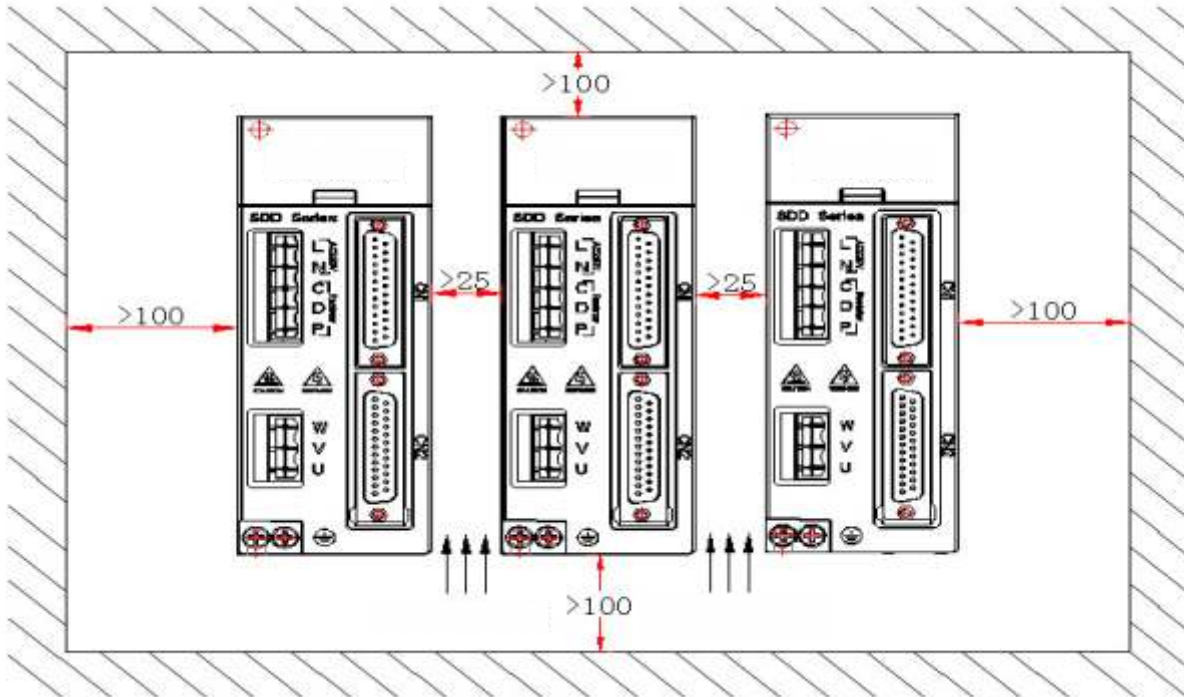
Please use M4 screws when installing.

If there is vibration source (punch) nearby and can not avoid it, please use vibration absorber or add anti-vibration rubber gasket.

If there is a large magnetic switch, welding machine etc noise interference sources nearby, the drive is easily interfered by outside and make wrong action, therefore, a noise filter must be added; but the noise filter will increase leak current, so, an insulating transformer must be installed at the input end of the drive.

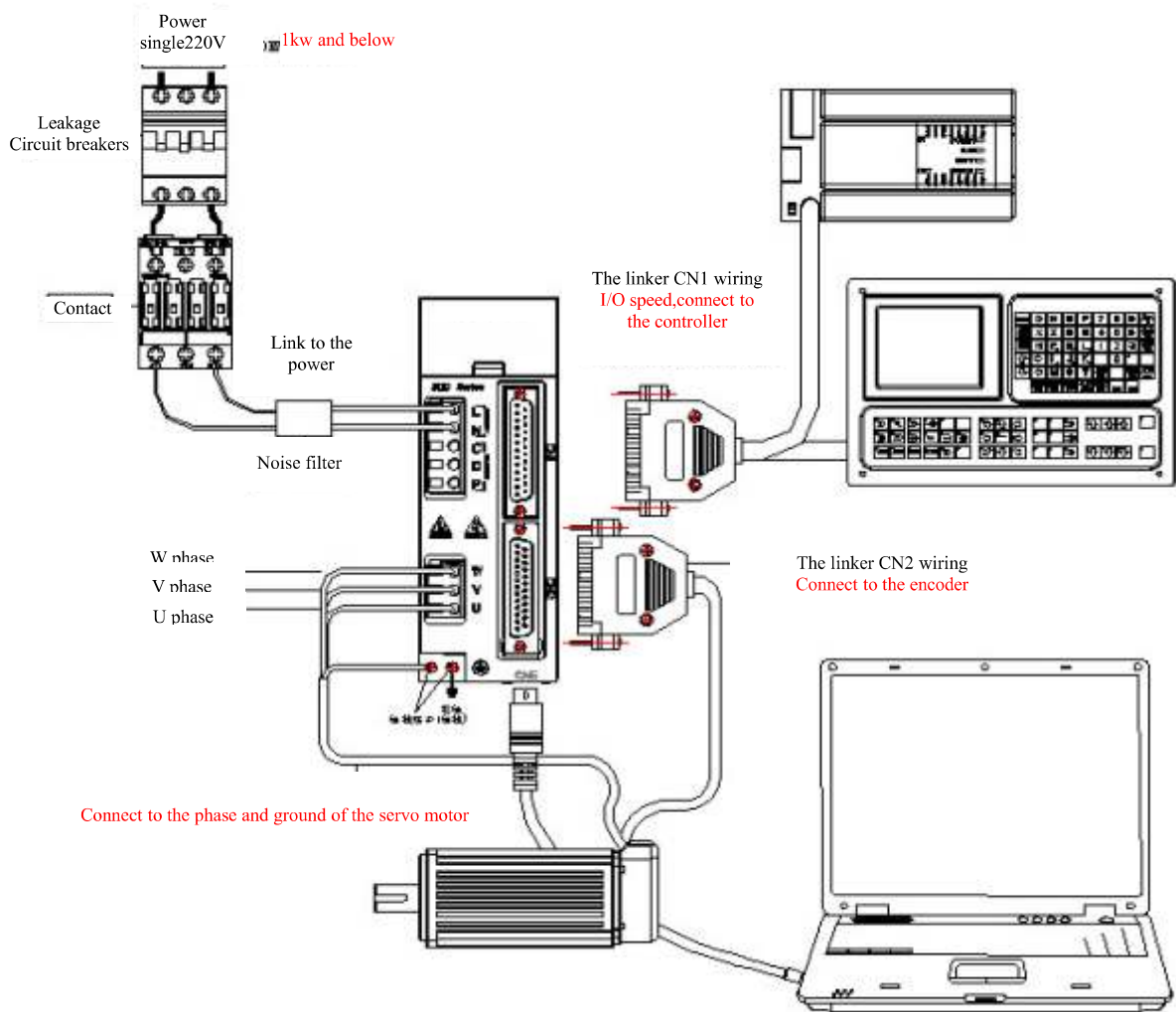
1.3.2 Servo installation direction and interval

Below chart shows a drive and multiple drives installation interval, the interval should be larger enough for a good heat dissipation conditions.

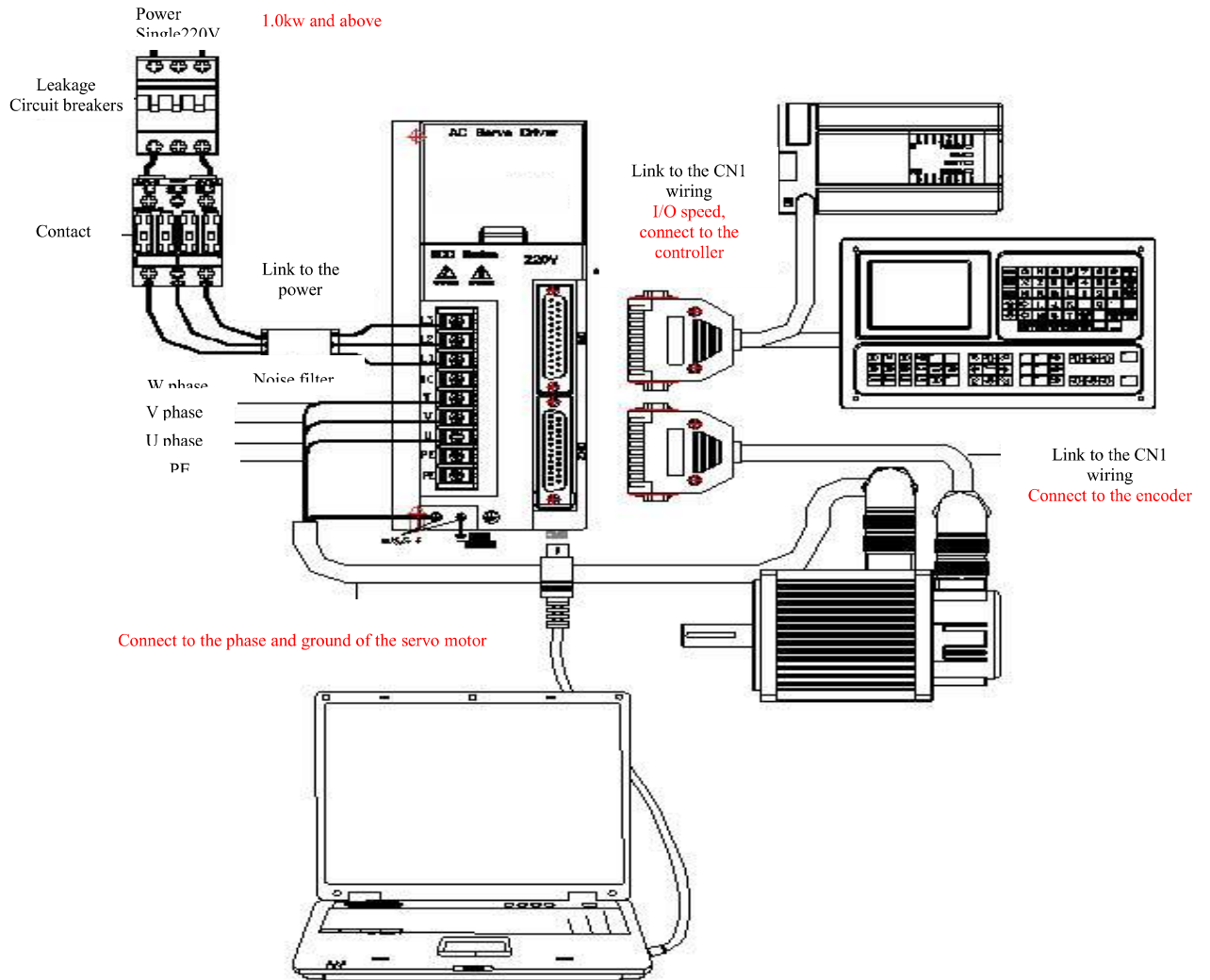


Chapter 2 Servo drive and motor wiring

2.1 Servo drive power supply and peripheral devices wiring

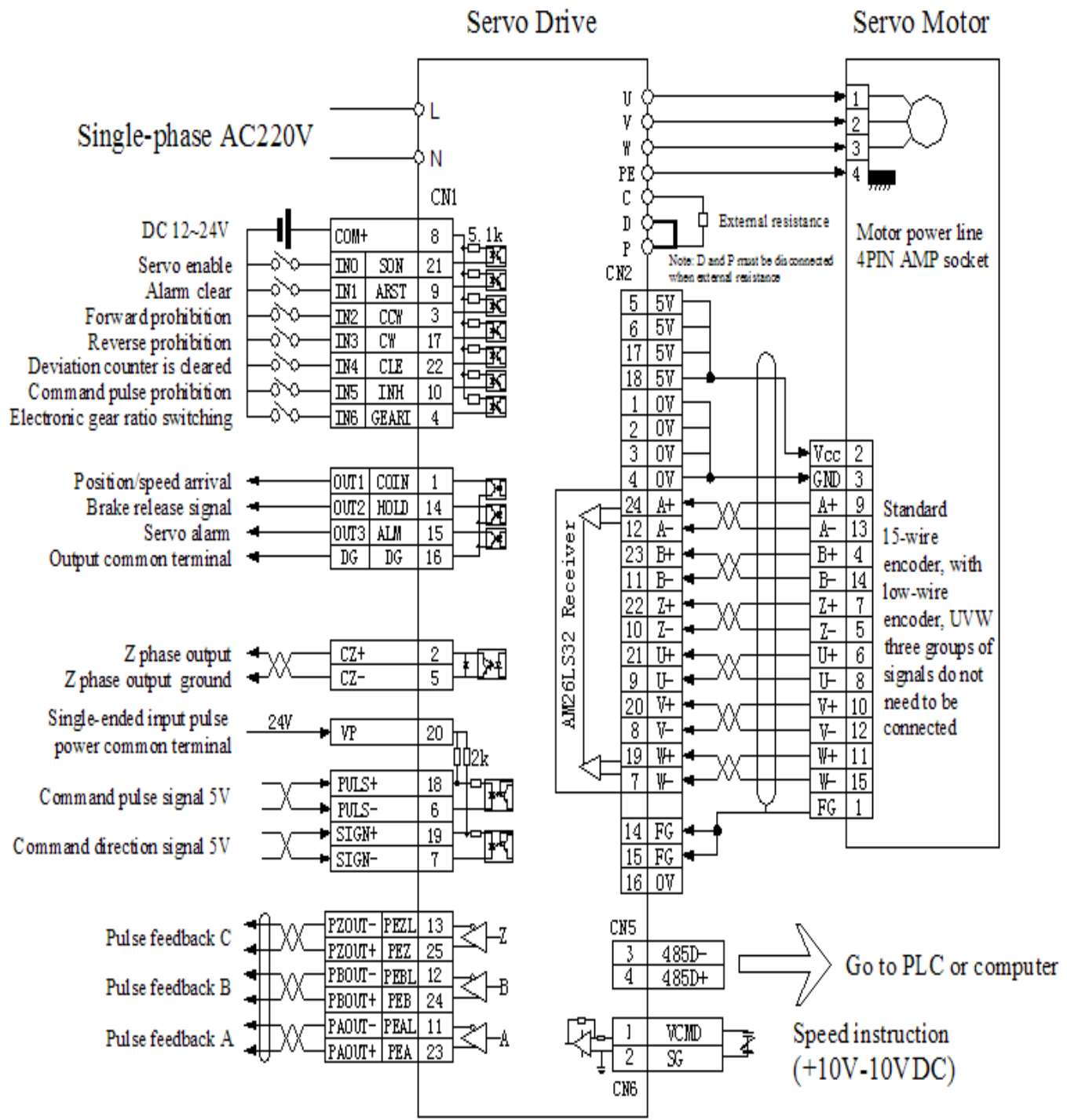


Chapter 2 Servo drive and motor wiring



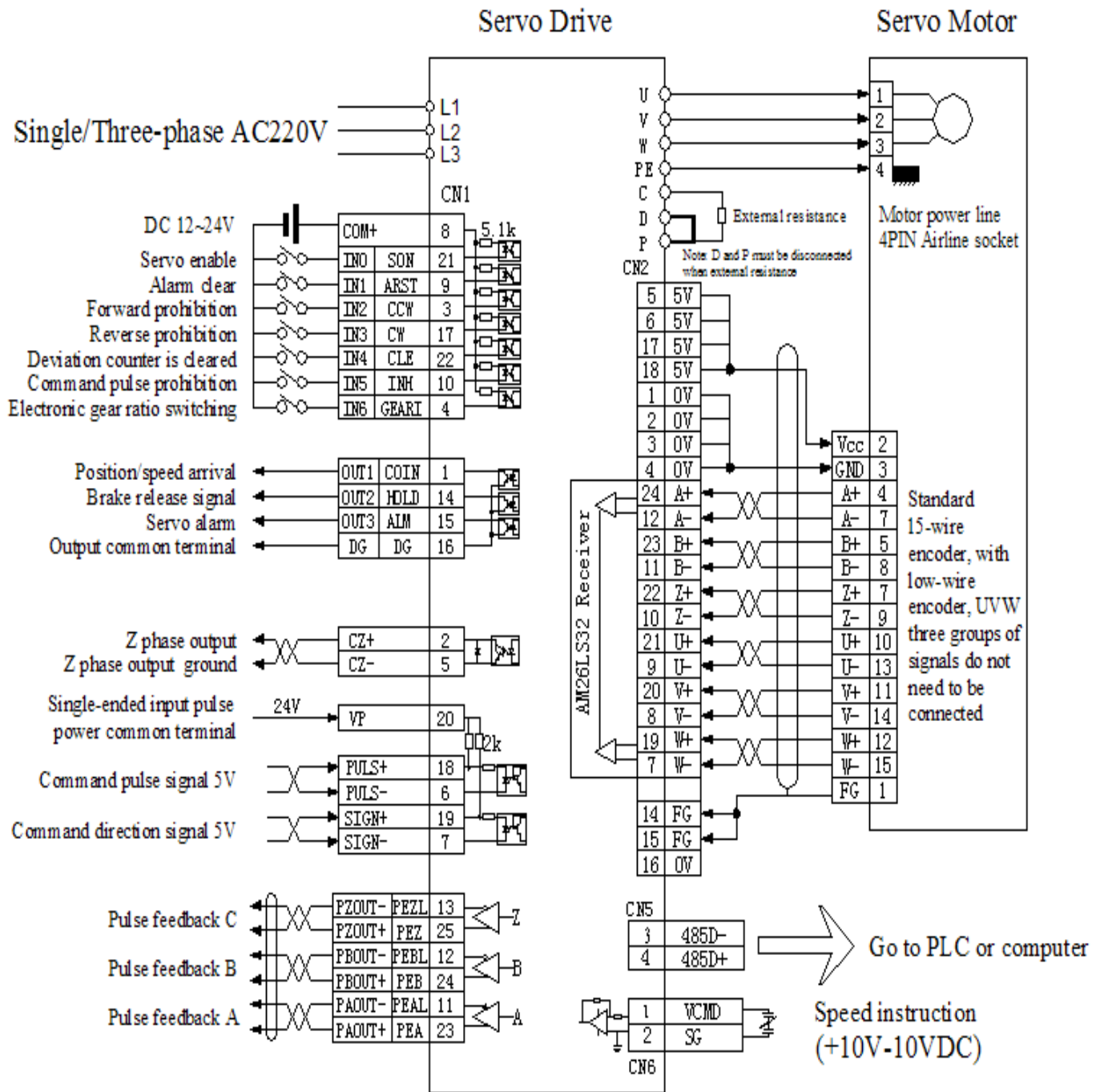
Chapter 2 Servo drive and motor wiring

2.2 Position control mode wiring diagram 1



position control mode wiring diagram

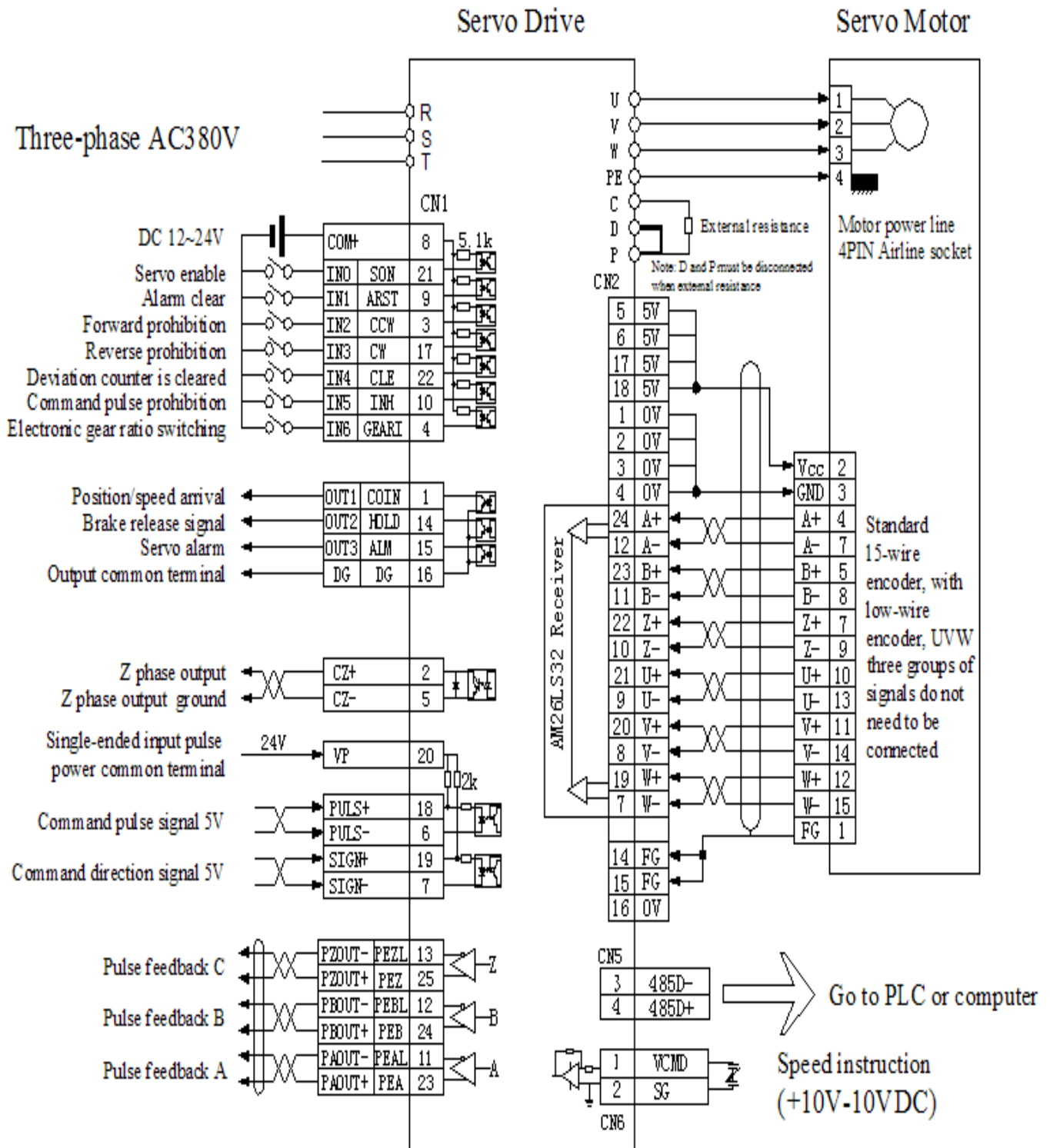
2.3 position control mode wiring diagram 2



position control mode wiring diagram

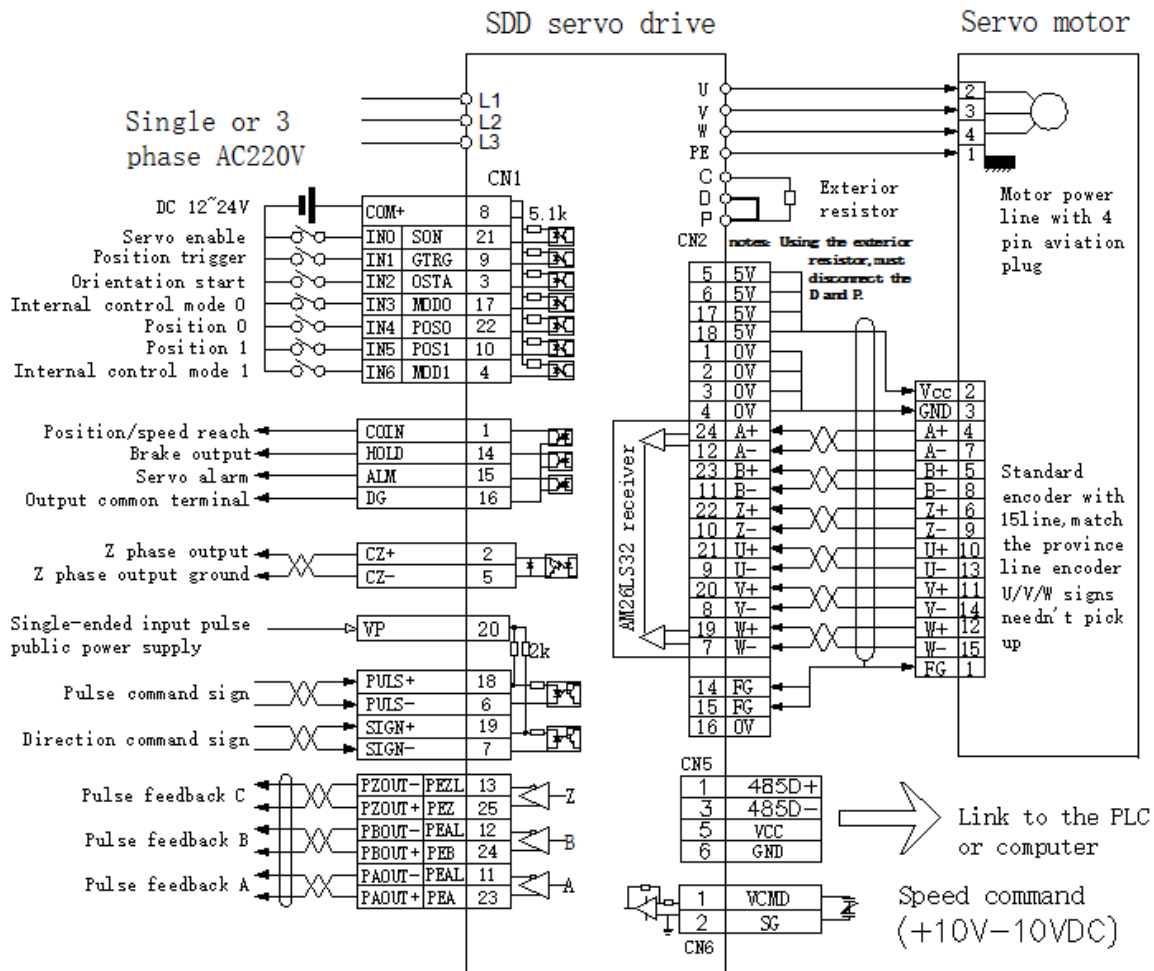
Chapter 2 Servo drive and motor wiring

2.4 position control mode wiring diagram 3



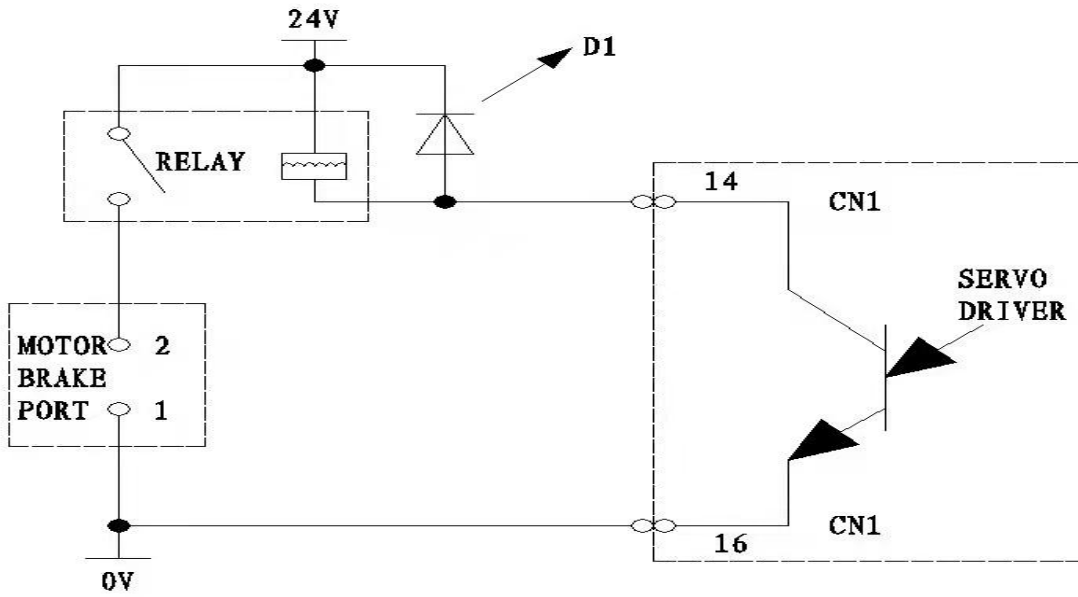
position control mode wiring diagram

internal position control mode wiring diagram(simple PLC function)



Internal position control model wiring diagram

Chapter 2 Servo drive and motor wiring



locking type brake motor wiring diagram

2.5 Terminal electrical connection

2.5.1 1、 Definition of the power terminal (SDD04NK7 series)

| | Terminal marking | signal definition | function |
|--|------------------|--------------------------------|--|
| | L | power supply | power input terminal ~220V 50Hz note: do not connect with motor output terminal U, V, W. |
| | N | | |
| | P | external connect | Built-in braking resistor: P and D short circuit connection. |
| | D | brake resistor select terminal | With external braking resistor: P and D open. The external resistance connection between P and C. |
| | C | | |
| | PE | System grounding | 1、 grounding terminal resistance <math>< 100\Omega</math>; 2、 Servo motor output and power input with one public point grounding. |
| | W | Servo motor output | Servo motor output terminals must connect with motor terminals W,V,U |
| | V | | |
| | U | | |

2、 Power terminal definition

| | Terminal marking | signal definition | function |
|--|------------------|---|---|
| | L1 | Power supply single-phase or three phase | power input terminal $\sim 220V$ 50Hz, single phase connect L1 L2 note: do not connect with motor output terminal U, V, W. |
| | L2 | | |
| | L3 | | |
| | PE | System grounding | grounding terminal resistance $< 100\Omega$; Servo motor output and power input with one public point grounding |
| | U | Servo motor output | Servo motor output terminals must connect with motor terminals W,V,U |
| | V | | |
| | W | | |
| | P | external connect brake resistor select terminal | Built-in braking resistor::P and D short circuit connection. |
| | D | | With external braking resistor:P and D open.The external resistance connection between P and C. |
| | C | | |

2.5.2 Power line terminals wiring

- L1, L2, L3, PE, U, V, W terminal, transversal area $\geq 1.5\text{mm}^2$ (AWG14-16). L, N terminal, transversal area $\geq 1.0\text{mm}^2$ (AWG16-18)。
- Grounding: the grounding wire should be as thick as possible, drive and servo motor grounding at PE terminal, grounding resistance $< 100\Omega$ 。
- Suggest providing power supply by three-phase isolating transformer to reduce the possibility of electric shock hurts.
- Suggest providing power supply by the noise filter to improve the anti-interference ability.
- Please install non fuse type(NFB) circuit breakers, so that the external power supply can be cut off promptly when the drive with failure.

2.5.3 Signal terminal definition

SDD servo drive unit interface terminal configuration as follows.CN1 signal

control terminal is DB25 connector, the socket is pin type, plug is hole type; CN2 terminal feeder is DB25 connector, socket is 25 core hole type, plug is 25 core pin type.

Control terminal CN1

| Terminal No | signal name | mark | I/O | System default function |
|-------------|-------------------------------|-------------|--------------|--|
| CN1-8 | Control Power supply positive | COM+ | power supply | Power supply positive pole of input terminal Photoelectric coupler used for drive the input terminals DC12~24V, electric current \geq 100mA |
| CN1-21 | Input port0 | IN0 (SON) | input | System default: input terminals of Servo-enabled: SON ON: allow the drive to work. SON OFF: drive off, stop working, the motor in free state. |
| CN1-9 | Input port 1 | IN1 (ARST) | input | System default: servo alarm clear ON: servo alarm output normally OFF: remove the system alarm |
| CN1-3 | Input port 2 | IN2 (CCW) | input | System default: Forward drive prohibition |
| CN1-17 | Input port 3 | IN3 (CW) | input | System default: Reverse drive prohibition |
| CN1-22 | Input port 4 | IN4 (CLE) | input | System default: position deviation counter reset CLE ON: position control, position deviation counter reset |
| CN1-10 | Input port 5 | IN5 (INH) | input | System default : position command pulse prohibit input terminals INH ON: command pulse input prohibited INH OFF: Command pulse input effective |
| CN1-4 | Input port 6 | IN6 (GEAR1) | input | System default: electronic gear ratio choose terminal (default as OFF) ON: choose PN31 parameter as present position control gear ratio OFF: choose PN9 parameter as present position control gear ratio |
| CN1-1 | Output port 1 | OUT1 (COIN) | output | System default: position reach. position reach signal output , when the servo position reach to the target position (Pn12 parameter value) , output ON |
| CN1-14 | Output port 2 | OUT2 (HOLD) | output | System default: brake output Open-drain output, normal working, optocoupler breakover. Output ON No enable, drive prohibited. When alarm, optocoupler cut-off; output OFF |

Chapter 2 Servo drive and motor wiring

| terminal No | signal name | mark | I/O | function |
|-------------|-------------------------------|---------------|-----------------|---|
| CN1-15 | Output port 3 | OUT3 (ALM) | output | System default: servo alarm output ALM ON: servo drive without alarm, servo alarm output ON. ALM OFF: servo drive alarm, servo alarm output OFF. |
| CN1-16 | common terminal of the output | DG | common terminal | Grounding common terminal of the control signal output terminal(except CZ) |
| CN1-2 | encoder Z phase output | CZ+ | output | the encoder Z phase output terminals: photoelectric code of the servo motor Z phase pulse output CZ ON: Z phase signal appear, optocoupler collector open circuit output |
| CN1-5 | encoder Z phase output | CZ- | output | |
| CN1-18 | Command pulse | PULS+ | input | external Command pulse input terminals Note 1: the parameter Pn8 set pulse input model; 0. Command pulse+symbol mode; 1. CCW/CW Command pulse mode; 2. A/B orthogonal Command pulse mode |
| CN1-6 | | PULS- | | |
| CN1-19 | command direction | SIGN+ | input | |
| CN1-7 | | SIGN- | | |
| CN1-23 | Output encoder signal A | PEA | output | Each round of the motor with pulse output The output pulse is mainly used to return to the upper machine. To achieve closed loop control, the frequency of the output signal can be set by PN41,PN42.. |
| CN1-11 | | PEAL | output | |
| CN1-24 | Output encoder signal B | PEB | output | |
| CN1-12 | | PEBL | output | |
| CN1-25 | Output encoder signal Z | PEZ | output | Each motor round output a signal, the width of the signal related to the speed of the motor |
| CN1-13 | | PEZL | output | |
| CN1-20 | External public power supply | VP | input | If the pulse signal is 24 v, connect the power supply can be without resistance |
| CN1-PE | Shield ground | PE | | |

Chapter 2 Servo drive and motor wiring

2) The feedback signal terminal CN2

| terminal No | signal name | terminal mark | I/O | function |
|-------------------|-------------------|---------------|-----|---|
| CN2-24 | encoder signal A+ | A+ | | Encoder ABZ signal |
| CN2-12 | encoder signal A- | A- | | |
| CN2-23 | encoder signal B+ | B+ | | |
| CN2-11 | encoder signal B- | B- | | |
| CN2-22 | encoder signal Z+ | Z+ | | |
| CN2-10 | encoder signal Z- | Z- | | |
| CN2-21 | encoder signal U+ | U+ | | Match province line type motor, UVW encoder signal does not need to connect. And PN74=1 |
| CN2-09 | encoder signal U- | U- | | |
| CN2-20 | encoder signal V+ | V+ | | |
| CN2-08 | encoder signal V- | V- | | |
| CN2-19 | encoder signal W+ | W+ | | |
| CN2-07 | encoder signal W- | W- | | |
| CN2-1.2 .3.4 | digital ground | GND | | Digital |
| CN2-5.6 .17.18 | +5V power | VCC | | Power |
| CN2-14 | shielding ground | FG | | |

3) Serial communication terminal

CN5

| terminal No. | signal name | mark | Model | function |
|--------------|----------------------------|-------|---------------|----------------------------|
| 3 | RS485 communication signal | 485D- | SDD** NK** | RS485 communication signal |
| 1 | RS485 communication signal | 485D+ | | RS485 communication signal |

4) Serial communication terminal

CN5

| terminal No. | signal name | mark | Model | function |
|--------------|----------------------------|-------|----------------|----------------------------|
| 3 | RS485 communication signal | 485D- | SDD** NK**D | RS485 communication signal |
| 4 | RS485 communication signal | 485D+ | | RS485 communication signal |

Terminal interface as shown below



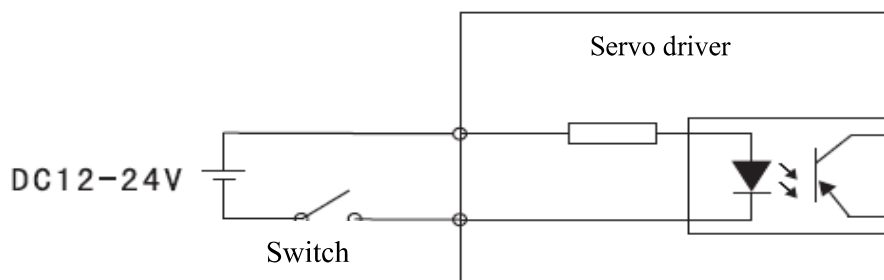
2.5.4 signal terminals wiring

- Cable selection: use shield cable (It is better to choose twisted shielded cable), wire core cross-sectional area $\geq 0.12\text{mm}^2$ (AWG24-26), shield must connect with FG terminals.
- cable length: cable length as short as possible, CN1 control cable should be less than 3meters, signal feedback CN2 cable should be less than 20meters.
- Wiring: away from power cabling to prevent interference entering. Please install surge absorber component in the relevant circuit inductor components (coil); direct current coil anti-parallel free-wheeling diode, AC coil in parallel and RC absorb return circuit.

2.6 The principle diagram of the signal interface

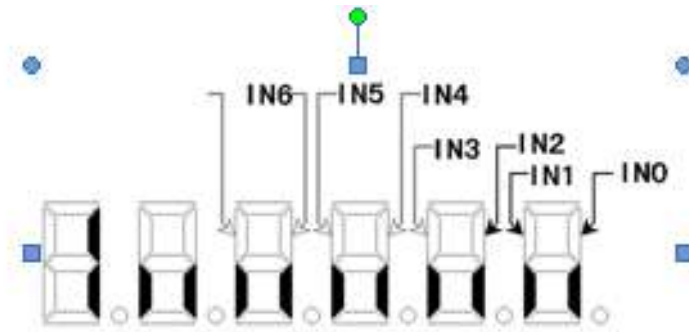
2.6.1 digital input interface circuit

Digital input interface circuit could be controlled by relay or open collector transistor circuit. User provide power, DC12 ~ 24V, current $\geq 100\text{mA}$; note: if the current polarity reversed, the drive does not work. Input signal IN0-IN6 all can refer to this connection mode.



Chapter 2 Servo drive and motor wiring

When input signal connect with OV, signal is ON input and effective. It can be judged by display menu UN-17, when input ON, the corresponding nixie tube will be light. Input OFF, the corresponding nixie tube will die out. Use this display content properly, convenient for servo input signal debugging and maintenance.

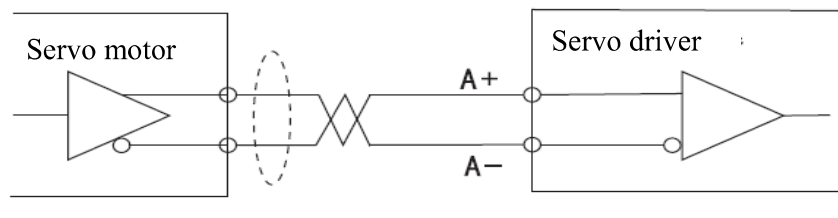


Input terminal display

(The stroke is lit to indicate ON, and to be off to indicate OFF)

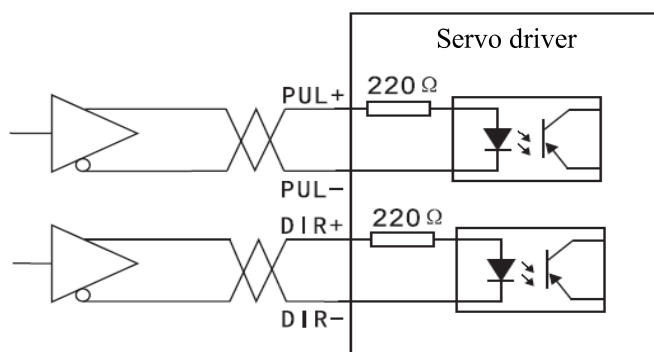
2.6.2 Servo motor photoelectric encoder input interface

In the differential output mode, use AM26LS32、MC3487 or similar line drive RS422 as a receiver.



2.6.3 The pulse signal input interface circuit

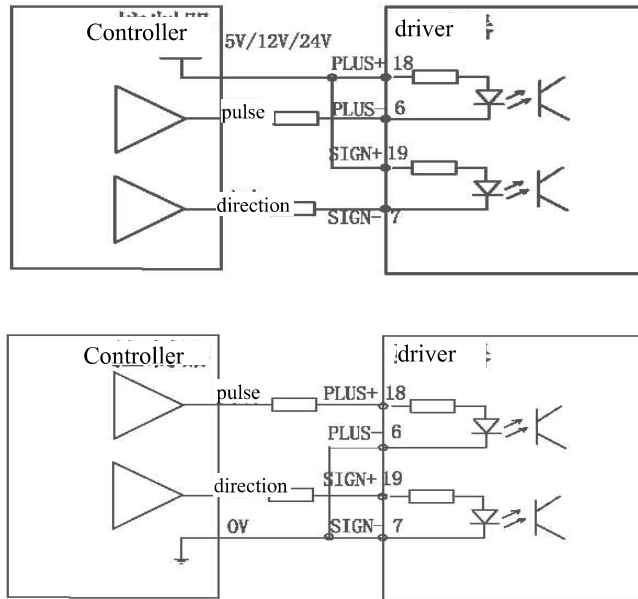
In order to transmit pulse data correctly, suggest to use differential drive way; in differential drive mode, use AM26LS31、MC3487 or similar line driver RS422 as follow diagram



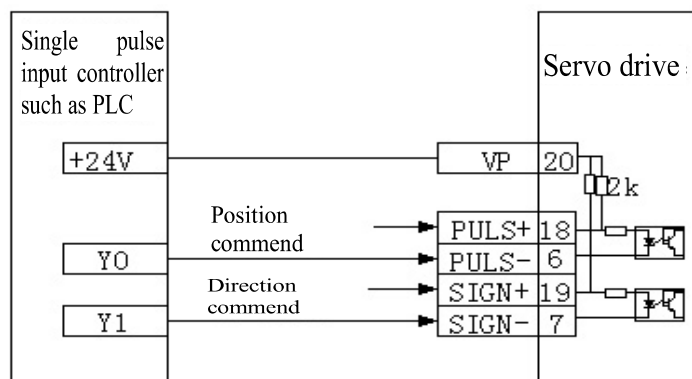
Using single-ended drive mode will lower the operating frequency.

Chapter 2 Servo drive and motor wiring

A: Input circuit according to the pulse quantity. drive current 10~25mA Limit external power maximum voltage as 24V, determine the value of resistance R. experience data:VCC=24V, R=1.3~2k; VCC=12V, R=510~820Ω。External power supply provided by user, please note that if the power polarity reversed, the servo drive unit will be damaged. Details as follow diagram.

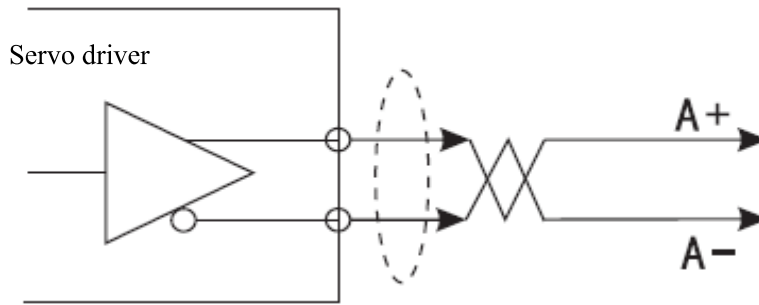


B: Don't concatenated resistance, with the internal resistance of the drive function implementation. The wiring method as diagram below.



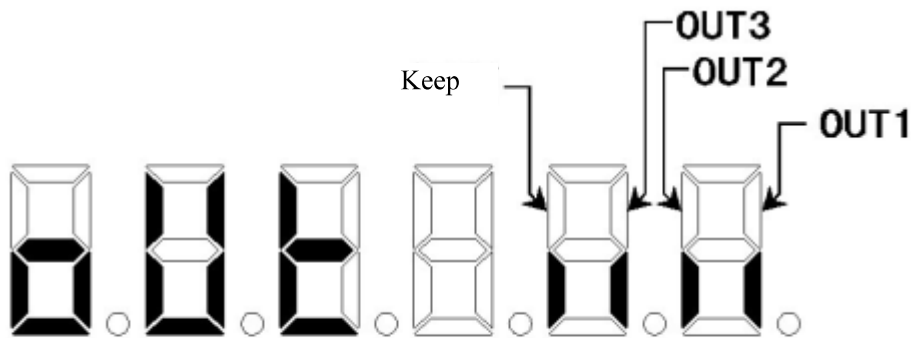
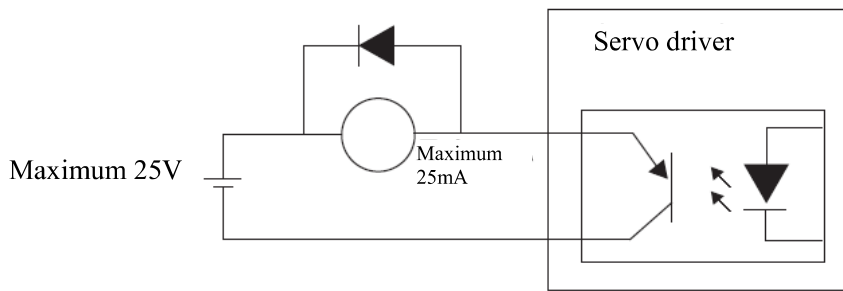
Chapter 2 Servo drive and motor wiring

2.6.4 driver speed output interface



2.6.5 The digital output interface circuit

Please pay attention to the power polarity when using external power, reversed polarity will damage the drive. Digital output is open collector mode, limit external voltage maximum as 24V, maximum current is 10mA. In terms of load, when using relay etc inductive load, a diode need be added to parallel with inductive load, if the polarity of the diode is reversed, the drive will be damaged. The status of the output signal can be observed by IIN-18



Output terminal display

Light display ON, go out display OFF

Chapter 3 operation and display

3.1 Keyboard operation







- Servo panel with 6 LED nixie tube display and 4 buttons to display various status, parameter setting . Key functions as follows:

- ▲: number, value increase, or forward.
- ▼: number, value decrease, or back.
- ◀: return to upper menu or cancel the operation.
- ↵: enter the next layer operation menu or input confirmation.


Note: ▲、▼ keep press down, repeat operation, the longer the holding time, the faster the repetition rate.

*** 6 section LED digital tube display all kinds of status and data of the system, all digital tube or the decimal point of the rightmost digital tube blink, it means alarm.




*** According to multiple-layer menu to operate, the first layer is main menu, including 8 kinds operation mode, the second layer is the function menu of all operation modes. The below diagram shows the main menu operation:












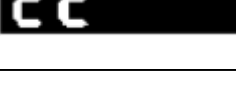






| Display status | meaning |
|---|---------------------|
|  | Status surveillance |
|  | parameter |
|  | Parameter operation |
|  | Internal speed run |
|  | Jog operation |
|  | Encoder adjustment |

Chapter 3 operation and display

















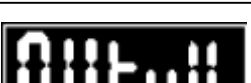

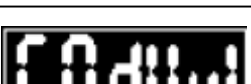








| | |
|---|---------------|
|  | Open loop run |
|---|---------------|

3.2 Monitoring method

Choose “Un-” in the first layer, press  entering monitoring mode; there are 22 display status, the user use ,  to choose the display mode.

















| Display status | Display code | Display meaning | Example |
|---|---|------------------------------|---------------------------------|
|  |  | Motor speed | Current motor speed is 500 turn |
|  |  | present position low 5 | |
|  |  | present position high 5 | |
|  |  | Command pulse low 5 | |
|  |  | Command pulse high5 | |
|  |  | Position deviation low 5 | |
|  |  | Position deviation high 5 | |
|  |  | Motor torque | |
|  |  | Motor current | |

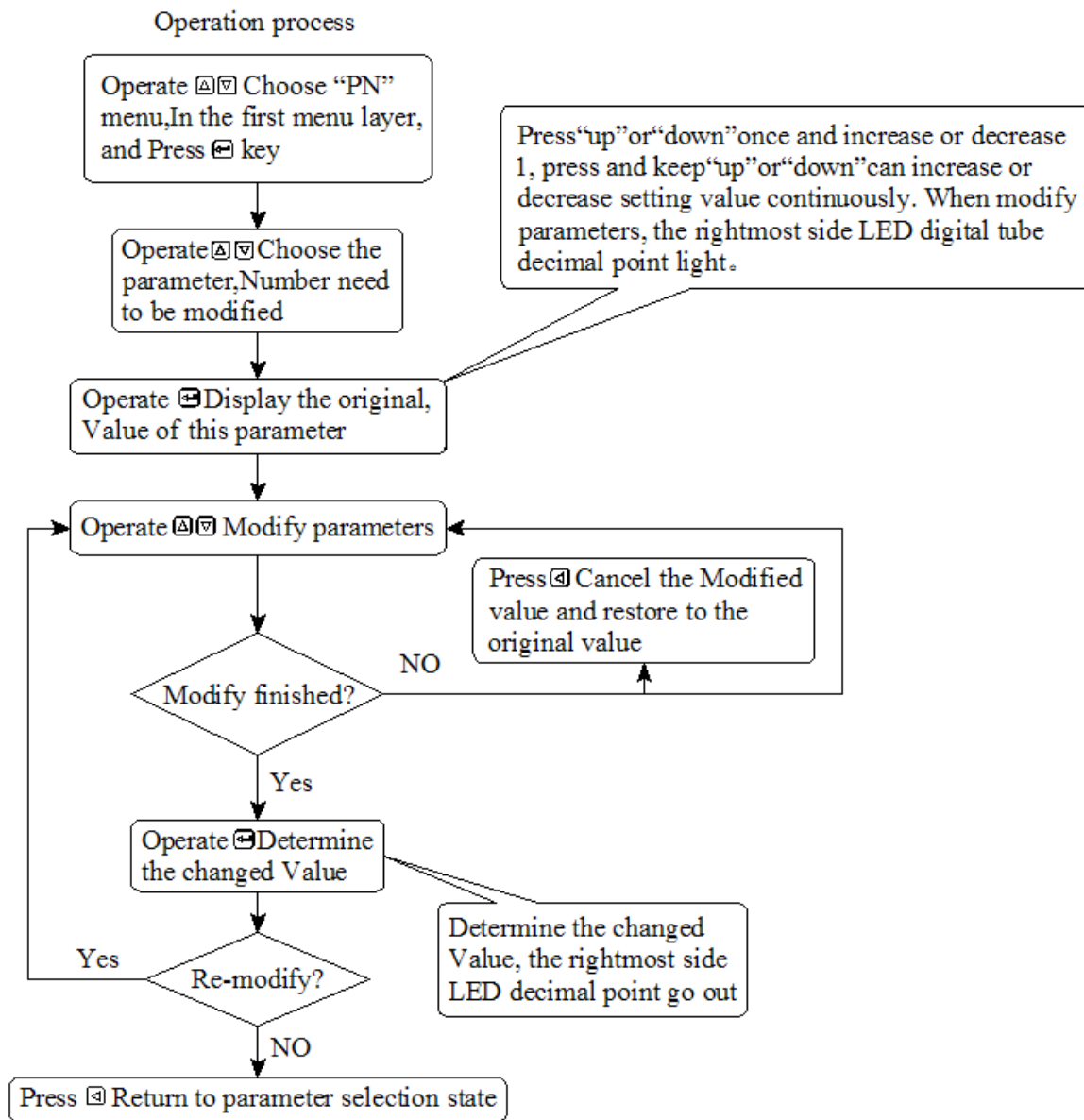
Chapter 3 operation and display

| | | | |
|---|---|-------------------------|--|
|  |  | present linear speed | |
|  |  | Control mode | |
|  |  | pulse frequency | |
|  |  | Speed command | |
|  |  | Torque command | |
|  |  | Rotor absolute position | |
|  | | Empty | |
|  |  | Input signal status | |
|  |  | Output signal status | |
|  |  | Encoder signal status | |
|  |  | Running status | |
|  |  | Alarm code | |
|  |  | Reserve | |
|  |  | Display analog AD value | |

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3.3 Parameter setting

Choose “PN-” in the first layer, and press key  to enter parameter setting mode. Use 、 to choose parameter, press key , display the value of the parameter, use 、 to modify parameter values. press  or  once, parameter increase or decrease one, press and keep  or , the parameter can be increase or decrease continuously. When the parameter value is modified, the rightmost LED digital tube lit up, press  to make sure the modified value effective, the LED digital tube decimal point of the right side go out, the modified value will be reflected in the control immediately, then press  or  keep on modify parameter, after modified press  back to the parameter selection status. If you are not satisfied with the value you are modifying, do not press , can press  to cancel, restore original parameter value, and back to the parameter selection status.



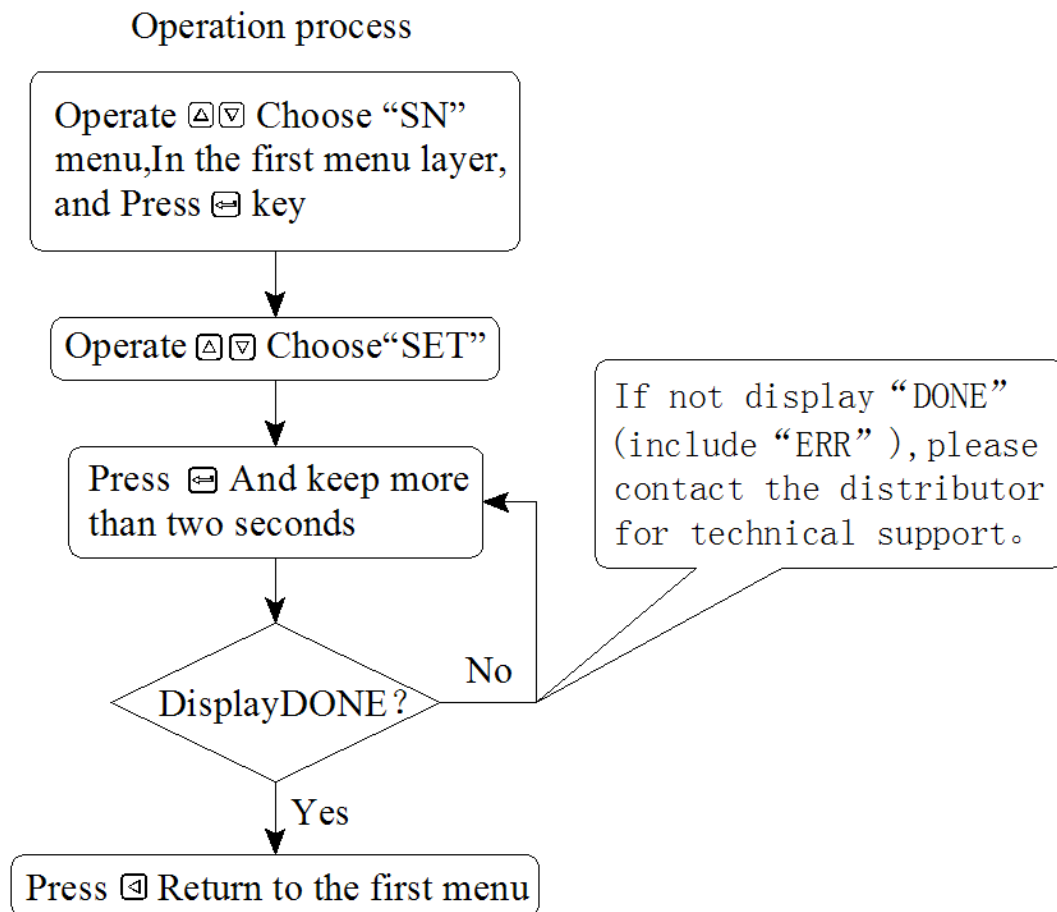
3.4 Parameter management

Parameter management mainly deals with the operation between memory and EEPROM, choose "Sn-" in the first layer, and press entering parameter management mode. First, choose the operation mode, there are 5 modes, use , to choose. Take "parameter write in" for example, choose "Sn-Set", press

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← and keep more than 2 seconds, if the write success, display “DONE”, if fail, display “ERR”. Press ← again back to the operation mode selection status.

Sn – SEt parameter write in, it means to write the memory parameter to the parameter area of EEPROM. When the users changed the parameters, only the memory parameter values changed, next power supply will be restored to the original value. If you want to change the parameter values permanently, need to perform write in operation, write the memory parameter into parameter area of EEPROM, next power supply will use the modified parameters.

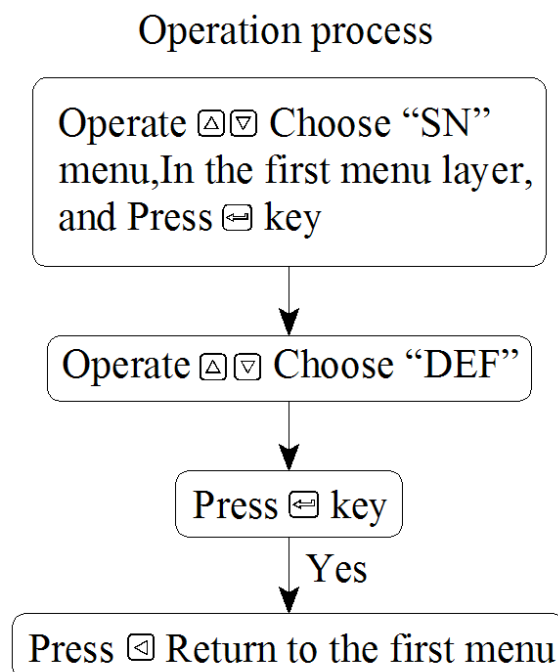


- **Sn – rd** parameter read, it means read EEPROM data in parameter area into the memory. The process will perform automatically when power on, at the beginning, the memory parameter and the EEPROM parameter is the

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same. But when the user modified the parameter, the memory parameter value changed too. When the user is not satisfied with the modified parameter or the parameter is messy, perform the parameter read operation, the data in the ENPROM parameter area will read into the memory again and restore to the original parameters when power on at the first time.

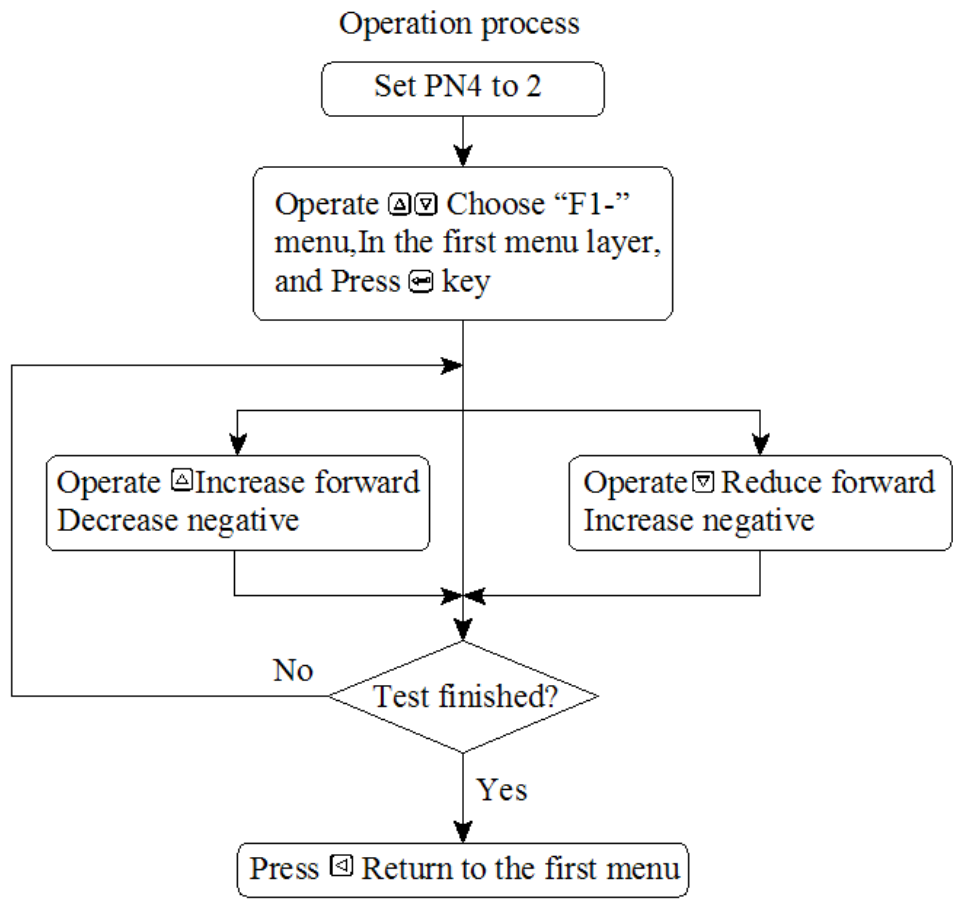
- **Sn—SS backup parameters**
- **Sn—rS Restore backup area parameters to current memory**
- **Sn—dEF** restore default value, it means to read all the parameter default value(factory defaults) into the memory, and write in the EEPROM parameter area, next power on will use the default parameter. When the user messed the parameter and can not work properly, use this operation can restore all parameters to factory default. As different drive mode with different parameter default values, when using restore default parameters, firstly have to ensure the motor ID (parameter PN1) is correct.



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3.5 F1 operation mode (panel test-run function)



Choose “F1-” in the first layer, press  entering speed trial operation mode. Speed trial prompt is “S”, value unit is r/min. Speed command provided by keys, use  ,  can change speed command. The motor operated at the given speed.  Control the speed positive increasing,  control the speed reducing (reverse increasing). When the speed value is positive, the motor rotated in the forward direction; when the speed value is negative, the motor rotated in the reverse direction. **Note: the speed mode is a continuous motion, please ensure the motion axes with enough run distance to avoid impact and limit.**

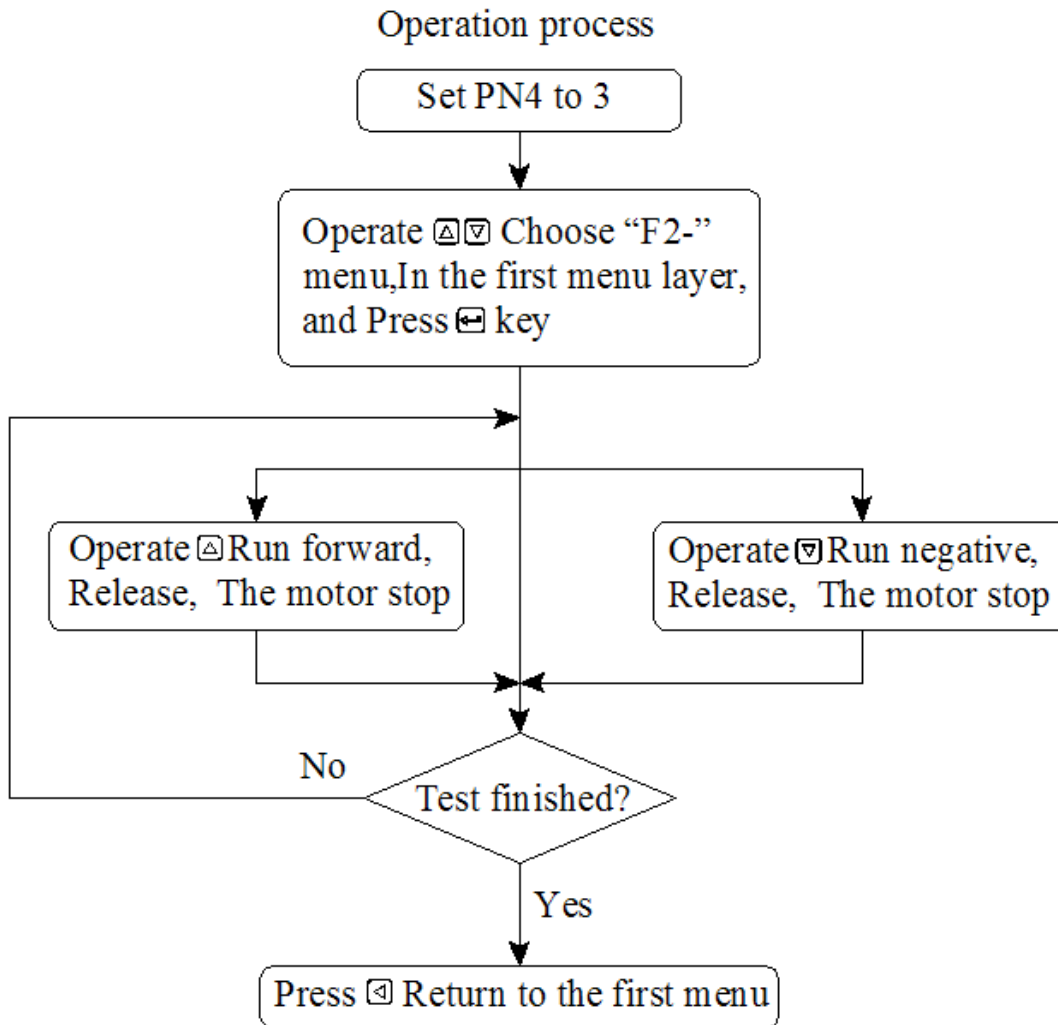


Note: if without outside enable signal, please set PN95 parameter as 1. Or the motor won't work.

3.6 F2 run mode(JOG run test function)

Choose “F2-” in the first layer, press  entering jog operation mode. JOG run prompt is “J”, value unit is r/min , speed command provided by keys. Enter F2

operation, press  key and keep, motor run at jog speed, release the button, motor stop running, retain zero speed; press  and keep, the motor inverted running at jog speed, release the key, the motor stop running, retain zero speed, jog speed set by parameter PN22.



Note: if without outside enable signal, please set PN95 parameter as 1. Or the motor won't work.

3.7 Other

F4 is the photoelectric encoder zero set function, for motor manufactures use. The user can not use it.

F5 function reserve.

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SDD series servo with total 127 parameters can be adjusted, adjust the user parameters can meet most requirements of the user. The motor mating parameters can not be modified randomly, or there will be unpredictable results appear. Pn5-Pn16 are position control parameters, Pn17-42 are speed control parameters, Pn43-Pn50 are current control parameters, Pn51-Pn59 are I/O control parameters. Pn60-Pn96 are motor mating parameters Pn97- Pn127 are internal control parameters and communication control

| p | | | p | | |
|-----|---|-------|-----|---|-------|
| No. | Name | Value | No. | Name | Value |
| 0 | Parameter password | 168 | 7 | position feed forward low pass filter cut-off frequency | 300 |
| 1 | Motor ID | 15 | 8 | Position command pulse input form | 0 |
| 2 | Software version | 1014 | 9 | Position command pulse fractional frequency numerator | 1 |
| 3 | initial display status | 0 | 10 | Position command pulse fractional frequency denominator | 1 |
| 4 | control mode | 0 | 11 | Position control motor rotation direction | 0 |
| 5 | position proportion gain | 800 | 12 | Positioning completion range | 20 |
| 6 | position feed forward/Pulse speed control mode filter | 0 | 13 | Position out of tolerance detection range | 800 |
| 14 | Position out of tolerance error invalid | 0 | 27 | Back to zero accredited range | 30 |
| 15 | Position command smoothing filter | 0 | 28 | Feedback output pulse A/B/Z phase sequence | 0 |
| 16 | drive ban input invalid | 1 | 29 | Acceleration/ deceleration time constant in speed mode | 200 |

| | | | | | |
|----|--|------|----|---|------|
| 17 | speed proportion gain | 400 | 30 | Acceleration/ deceleration time constant in position mode | 0 |
| 18 | speed integral time constant | 50 | 31 | Position command pulse fractional frequency numerator 1 | 2 |
| 19 | speed detection low pass filter | 500 | 32 | Internal control method selection | 1 |
| 20 | Rated speed | 2500 | 33 | Speed 1 | -300 |
| 21 | Arrive speed | 500 | 34 | Speed 2 | -200 |
| 22 | Jog speed | 120 | 35 | Speed 3 | -100 |
| 23 | Enable delayed | 0 | 36 | Speed 4 | 0 |
| 24 | Back to zero absolute positioning pulse number | 100 | 37 | Speed 5 | 100 |
| 25 | reserve | 10 | 38 | Speed 6 | 200 |
| 26 | Back to zero speed | -100 | 39 | Speed 7 | 300 |
| 40 | Speed 8 | 400 | 54 | input port high 3 reverse | 0 |
| 41 | numerator of the encoder output pulse | 1 | 55 | output port reverse | 7 |
| 42 | Denominator of the encoder output pulse | 1 | 56 | Analog instruction, direction reversal | 1 |
| 43 | Electric current loop proportion gain | 230 | 57 | The second position proportion gain | 225 |
| 44 | Electric current loop integral time constant | 100 | 58 | Reserved | 0 |
| 45 | Internal torque1 | 50 | 59 | Z signal stretch ratio | 0 |
| 46 | Internal torque 2 | -50 | 60 | Reserved | |
| 47 | Internal torque 3 | 100 | 61 | current rated torque | 40 |
| 48 | Internal torque 4 | -100 | 62 | motor rated speed | 2500 |
| 49 | Torque setting | 300 | 63 | Motor maximum speed | 3000 |

Chapter 4 parameter

| | | | | | |
|----|---|------|----|--|------|
| 50 | Torque command filter | 100 | 64 | motor rated current | 40 |
| 51 | Input port low 4 force effective | 0 | 65 | system allowed maximum overload capacity | 300 |
| 52 | Input port high 3 force effective | 0 | 66 | Current integral separation point | 800 |
| 53 | input port low 4 reverse | 0 | 67 | Analog voltage dead zone | 30 |
| 68 | Current command low pass filter | 100 | 83 | Key response time | 20 |
| 69 | Speed integral separation point | 200 | 84 | Reserved | |
| 70 | output port 1 function selection | 2 | 85 | Position error clear method | 234 |
| 71 | output port 2 function selection | 0 | 86 | Encoder line number | 2500 |
| 72 | output port 3 function selection | 1 | 87 | Encoder zero offset | 2650 |
| 73 | Input analog selection | 0 | 88 | Current when encoding disk is zero | 60 |
| 74 | Encoder type selection | 0 | 89 | Motor thermal overload | 105 |
| 75 | Overload torque detection point | 117 | 90 | Motor thermal overload torque | 130 |
| 76 | Overload point torque | 200 | 91 | Motor thermal overload time | 900 |
| 77 | Maximum overload time of the overload point | 1000 | 92 | Motor pole pairs | 4 |
| 78 | Analog voltage filter factor | 100 | 93 | Reserved | |

Chapter 4 parameter

| | | | | | |
|-----|---|------|-----|--|-----|
| 79 | Speed amplifier saturation detection time | 1500 | 94 | Torque to reach output signal ratio | 150 |
| 80 | Blocking speed | 20 | 95 | Forced enable | 0 |
| 81 | Blocking confirmation time | 1000 | | | |
| 82 | Input pulse filter frequency | 800 | 96 | Reserved | |
| 97 | Internal position 0 turns | 0 | 109 | Acceleration and deceleration of the internal position | 1 |
| 98 | Internal position 0 pulse number | 0 | 110 | Input port 0 definition | 1 |
| 99 | Speed at internal position 0 positioning | 1000 | 111 | Input port 1 definition | 2 |
| 100 | Internal position 1 turns | 0 | 112 | Input port 2 definition | 14 |
| 101 | Internal position 1 pulse number | 0 | 113 | Input port 3 definition | 15 |
| 102 | Speed at internal position 1 positioning | 1000 | 114 | Input port 4 definition | 4 |
| 103 | Internal position 2 turns | 0 | 115 | Input port 5 definition | 3 |
| 104 | Internal position 2 pulse number | 0 | 116 | Input port 6 definition | 0 |
| 105 | Speed at internal position 2 positioning | 1000 | 117 | RS485 communication address | 1 |
| 106 | Internal position 3 turns | 0 | 118 | RS485 communication rate | 5 |

Chapter 4 parameter

| | | | | | |
|-----|--|------|-----|--|------|
| 107 | Internal position 3 pulse number | 0 | 119 | RS485 communication agreement | 0 |
| 108 | Speed at internal position 3 positioning | 100 | 120 | Position/speed integral saturation fault detection | 0 |
| 121 | Input port is controlled selection | 0 | 122 | Analog speed proportional gain | 2048 |
| 123 | Analog torque proportional gain | 2048 | 126 | High speed torque coefficient | 190 |
| 124 | Analog zero point | 2048 | 127 | Analog control AD mode | 0 |
| 125 | Torque mode speed limit | 20 | | | |

4.1 All parameters function and significance detail list

| No. | name | function | parameter range |
|-----|------------------------|--|-----------------|
| 0 | parameter password | ① password with different level, corresponding to user parameters, system parameters ② To modify the motor ID(Pn1) , must set this item to 0, user parameter password is 168. Please consult the manufacture for system parameters. | 0~300 |
| 1 | Motor ID | For supporting motor model. Each motor with a unique ID number, Set password Pn0 to be 0 firstly, then modify this parameter. After the setting is completed, the SN-DEF needs to be executed to be valid. Please operate this parameter with caution. | 0~100 |
| 2 | software ID | Reserved by the manufacturer | |
| 3 | initial display status | Choose the display status when the drive power on 0: display motor rotation speed; 1: display current position low 5; | 0~20 |

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| | | | |
|---|--------------------------|--|--------|
| | | <p>2: display current position high 5 8: display motor current; 11:display position command pulse frequency; 12:display speed command; 13:display torque command; 14:Display the rotor absolute position</p> | |
| 4 | control mode | <p>The drive control mode can be set by this parameter: 0: position control mode; 1: internal position/speed/torque control mode 2: internal speed control mode; 3: jog control mode. 4:zero mode. 5:Open loop operation mode. 6:Automatic gain adjustment mode. 7:Analog speed mode 8:Analog torque mode 9:Position and Analog speed mode. 10:Position and Analog torque model. 11: pulse speed control mode 12: Analog zero automatic adjustment (after connecting the upper computer system, Setting this parameter can automatically write the zero point of the current analog and simplify the debugging of the analog. 11 and 12 functions are available in V519 or later, and the product model suffix with D also has these two functions. The internal position/speed/torque is determined by the I/O port.</p> | 0~12 |
| 5 | position proportion gain | <p>Set the proportion gain of the location loop regulator. The greater the setting value, the higher the gain, and the greater the stiffness, under the same frequency command pulse condition, the location hysteresis will be less. But if the value is too big may cause oscillation or overshoot.</p> | 1~1000 |

Chapter 4 parameter

| | | | |
|---|--|---|---------|
| 6 | position feed forward/ Pulse speed control mode filter | <p>This parameter is a multiplexing parameter (V1020). In position control mode, it is position feedforward, and the feedforward gain of the position loop is increased, and the high-speed response characteristic of the control system is improved, but it will make the position loop of the system unstable and prone to oscillation. unless high response characteristics are required, and the feedforward gain of the position loop is usually 0.</p> <p>In the pulse speed control mode, the function is the pulse speed control mode filter. Set pulse count filter level: PN6=0, corresponding sampling 8 times to average; PN6=1, corresponding to sampling 7 times to average, and so on; PN6=7 and above without filtering;</p> | 0~100 |
| 7 | position feed forward low-pass filter cutoff frequency | set position loop feedforward low-pass filter cutoff frequency, the high the cutoff frequency, the better the position tracking, but easy to vibrate. | 1~1200 |
| 8 | position command pulse input form | <p>Set the position command pulse input form 0: pulse + sign; 1: CCW pulse/CW pulse; CCW is observed from the axial of servo motor, counter clockwise rotate, it defined as forward direction. CW is observed from the servo motor axial, clockwise rotate, it defined as reverse direction. 2: A/B orthogonal signal</p> | 0~2 |
| 9 | position command pulse frequency division numerator | electronic gear ratio numerator | 1~32767 |

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| | | | |
|----|---|--|---------------------|
| 10 | position command pulse frequency denominator | electronic gear ratio denominator | 1~32767 |
| 11 | position control motor rotate direction | 0: normal; 1: direction reversed. | 0~1 |
| 12 | Positioning finished range | set the positioning finish pulse range under the position control; This parameter provide basis whether drive unit judgment finished positioning under the position control mode. | 0~30000 |
| 13 | Position tolerance detection range | set position tolerance alarm detection range; Under the position control mode, when the count value in the position deviation counters over this parameter, the servo drive unit will give position error alarm. | 0~30000 |
| 14 | position error invalid | 0: position error alarm detection valid; 1: position error alarm detection invalid, stop detecting location error. | 0~1 |
| 15 | position command smoothing filter | smooth filtering command pulse, with exponential form acceleration and deceleration, numerical value means time constant; The filter will not lose input pulse, but there will be command delay phenomenon; When set to 0, the filter doesn't work. | 0ms~2000 0×0.1ms |
| 16 | drive ban input invalid | 0: CCW、CW input ban valid; 1: cancel CCW、CW input ban. | 0~1 |
| 17 | speed proportion gain | Set the speed loop regulator proportion gain. 1.The greater the setting value, the higher the gain, and the greater stiffness. 2.The greater the load inertia, the greater the setting value. | 5Hz ~2000Hz |

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| | | | |
|----|--|---|-------------------|
| 18 | speed integral time constant | Set speed loop regulator integral time constant; 1.The smaller the set value, the faster integral speed and the greater stiffness. 2.The greater load inertia, the greater of set value. At the frequent start-stop small power occasion, the set value is small to prevent overshoot. | 1ms ~1000ms |
| 19 | speed detection low pass filter | set speed test low pass filter characteristic; 1. The smaller value, the low cutoff frequency, the smaller of the motor noise. If the load inertia is large, could reduce the setting value. If the value is too small may cause to low response and vibration. 2. The larger the value, the higher the cutoff frequency, the speed response faster. If high speed response needed, could increase the setting value. | 1%~500% |
| 20 | rated speed | rated speed of the motor | 0~ 6000 |
| 21 | reach speed | Set the speed value when input signal reach effective | 0~3000 |
| 22 | jog speed | Set jog speed. | -3000 ~3000 r/min |
| 23 | Enable delay | | 0-1000ms |
| 24 | Orientation absolute positioning pulse count | Precise position when external triggering orientation control Actual operation position is set value *2 | 0-65535 |
| 25 | reserve | reserve | |
| 26 | Orientation speed | The speed when external triggering orientation control, by setting plus or minus speed to decide rotation direction when positioning. | 0~3000 r/min |
| 27 | Orientation complete range | Identified range when external triggering orientation control | 0-10000 |
| 28 | Feedback output pulse A/B/Z phase sequence | Drive motor output pulse A/B/Z phase sequence during initial power-up 0: Normal; 1: Phase A is inverted; 2: Phase B is inverted; 3: A/B is reversed when it is the same; 4: | 0-7 |

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| | | | |
|----|---|--|-------------|
| | | Phase Z is inverted; 5: A/Z is reversed simultaneously; 6: B/Z is also Inverse; 7: A/B/Z is also reversed | |
| 29 | Acceleration/ deceleration time constant in speed mode | Set value means the motor acceleration/ deceleration time from 0r/min~1000r/min. Acceleration and deceleration are linear. Only used for speed control mode, it is invalid for position control mode; | 0ms~32767ms |
| 30 | Acceleration/ deceleration time constant in position mode | It means that when the motor is accelerating and decelerating from 0~1000r/min, the acceleration and deceleration characteristics are linear. When set to 0, position acceleration and deceleration have no effect. When set to other values, it can effectively reduce the impact of position loop commutation and acceleration and deceleration, and the operation is more stable. It is only used in position mode. | 0ms~32767ms |
| 31 | Position command pulse frequency second numerator | Position control the second gear ratio numerator | 1~65536 |
| 32 | Internal control method selection | <ol style="list-style-type: none"> 1. Internal speed and external pulse position switching 2. Internal torque and external pulse position switching 3. Internal position and external pulse position switching <p>It is only necessary to define the corresponding input port as function 19 when switching. If only internal speed or internal torque or internal position is used, the corresponding input port is defined as function 19 when there is no need to switch functions. At the same time, the input port is permanently set</p> | 0~3 |

Chapter 4 parameter

| | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
|-------|---|---|---------|-----|-----|-----|-------|-----|-----|-----|-------|----|-----|-----|-------|-----|----|-----|-------|----|----|-----|-------|-----|-----|----|-------|----|-----|----|-------|-----|----|----|-------|----|----|----|----------------------|
| | | <p>high or low according to the actual situation.</p> <p>When working in multiple modes, you need to observe what control mode is currently in progress. You can check un-11 to determine the working status and facilitate debugging.</p> | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 33 | Speed 1 | <p>Internal speed control mode: by external I/O point status to control the speed. For example:</p> <table style="margin-left: 40px;"> <tr> <td></td> <td>SC1</td> <td>SC2</td> <td>SC3</td> </tr> <tr> <td>Pn33:</td> <td>OFF</td> <td>OFF</td> <td>OFF</td> </tr> <tr> <td>Pn34:</td> <td>ON</td> <td>OFF</td> <td>OFF</td> </tr> <tr> <td>Pn35:</td> <td>OFF</td> <td>ON</td> <td>OFF</td> </tr> <tr> <td>Pn36:</td> <td>ON</td> <td>ON</td> <td>OFF</td> </tr> <tr> <td>Pn37:</td> <td>OFF</td> <td>OFF</td> <td>ON</td> </tr> <tr> <td>Pn38:</td> <td>ON</td> <td>OFF</td> <td>ON</td> </tr> <tr> <td>Pn39:</td> <td>OFF</td> <td>ON</td> <td>ON</td> </tr> <tr> <td>Pn40:</td> <td>ON</td> <td>ON</td> <td>ON</td> </tr> </table> | | SC1 | SC2 | SC3 | Pn33: | OFF | OFF | OFF | Pn34: | ON | OFF | OFF | Pn35: | OFF | ON | OFF | Pn36: | ON | ON | OFF | Pn37: | OFF | OFF | ON | Pn38: | ON | OFF | ON | Pn39: | OFF | ON | ON | Pn40: | ON | ON | ON | -6000 ~6000 r/min |
| | SC1 | | SC2 | SC3 | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn33: | OFF | | OFF | OFF | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn34: | ON | | OFF | OFF | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn35: | OFF | | ON | OFF | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn36: | ON | | ON | OFF | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn37: | OFF | | OFF | ON | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn38: | ON | | OFF | ON | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn39: | OFF | ON | ON | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| Pn40: | ON | ON | ON | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 34 | Speed 2 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 35 | Speed 3 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 36 | Speed 4 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 37 | Speed 5 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 38 | Speed 6 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 39 | Speed 7 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 40 | Speed 8 | -6000 ~6000 r/min | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 41 | numerator of the encoder output pulse | Every loop feedback pulse encoder output after through the gears within the drive unit. | 1~65536 | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 42 | Denominator of the encoder output pulse | Every loop feedback pulse encoder output after through the gears within the drive unit. | 1~65536 | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 43 | current loop proportion gain | 1.The higher the set value, the greater the gain, the current tracking error is smaller. But too much gain will produce vibration or noise, 2.it related with the servo motor, 3. Independent of load | 1 ~ 500 | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |
| 44 | current loop integral time constant | 1.The smaller the set value, the faster the integral speed, and the current tracking error is smaller. But too small integral will produce vibration or noise.2. It related with servo motor, 3. Independent of load. | 1~10000 | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | | |

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| | | | |
|----|--------------------------------|--|----------|
| | | 4. Try to set larger value under the condition of the system without vibration. | |
| 45 | Internal torque 1 | Internal torque control mode: the size of the torque is controlled by the status of the external I/O point. For example: T0 T1 Pn45: OFF OFF Pn46: ON OFF Pn47: OFF ON Pn48: ON ON | 0%~300% |
| 46 | Internal torque 2 | | -300%~0% |
| 47 | Internal torque 3 | | 0%~300% |
| 48 | Internal torque 4 | | -300%~0% |
| 49 | torque set | internal speed, jog speed torque | 0~300% |
| 50 | torque command filter | 1. Setting the torque command filter characteristics can restrain the vibration which produced by torque (the motor give out sharp vibration noise). 2. The smaller of the value, the lower of the cutoff frequency, the smaller noise produced by motor. If the load inertia is very big, can reduce the set value properly. If the value is too small, may result in slow response and may cause instability. | 1%~500% |
| 51 | Input low 4 enforce effective | The lower four bits of the input signal are forced ON. Invert the binary, set the value to decimal, for example: 1 (0001) the lowest bit is forced to be valid, 2 (0010) the second bit is forced to be valid, 4 (0100) the third bit is forced to be valid, 8 (1000) the fourth bit is forced to be valid. | 0~15 |
| 52 | Input high 3 enforce effective | Input signal high 3 enforce ON | 0~7 |
| 53 | input low 4 reverse | input signal low 4 reverse, used to match the electrical level of the input signal contact spot | 0~15 |
| 54 | input high 3 reverse | input signal high 3 reverse, used to match the electrical level of the input signal contact spot | 0~7 |
| 55 | output port reverse | Output signal reverse, used to match the electrical level of the output signal | 0~15 |

Chapter 4 parameter

| | | | |
|----|--|---|-----------------|
| 56 | Analog instruction, direction reversal | Analog instruction, direction reversal. Switch direction. | 0~1 |
| 57 | The second position proportion gain | The function is same with PN5, which parameter used as position proportion gain in system, is determined by external I/O, in default situation, with PN5 as system internal position proportion gain. | 1-65536 |
| 58 | Reserved | Reserved | |
| 59 | Z signal stretch ratio | When using a host computer such as a PLC, if the Z signal reception is difficult, this parameter can be used to widen the output Z signal to facilitate the use of the upper computer. When set to 0, no stretch function | 0-31 |
| 60 | Reserved | Reserved | |
| 61 | motor rated torque | set motor rated torque | 1~1000 |
| 62 | motor rated speed | Set motor rated speed. | 0~6000 r/min |
| 63 | Motor maximum speed | Set motor maximum speed | 0~6000 r/min |
| 64 | motor rated current | Set motor rated current. Set value is valid. | 1~500× 0.1A |
| 65 | system allowed maximum overload capacity | Set system allowed maximum overload multiple | 0~300% |
| 66 | Current integral separation point | Current error over the set value, the current loop from PI change to P, value is the percentage of rated current | 0~800% |
| 67 | Analog voltage dead zone | Analog voltage dead zone AD value, set this value reasonable, with the absence of the input voltage, and solve the motor rotation produced by the zero | 0~4096 |

Chapter 4 parameter

| | | | |
|----|----------------------------------|---|----------|
| | | voltage wave. | |
| 68 | current command low pass filter | Set current command low pass filter cutoff frequency. Used to limit the current command frequency band, avoid the current shock and vibration, and make the current response stably. | 1~1500HZ |
| 69 | Speed integral separation point | When speed error over the set value, the speed change from PI to P | 0~300 |
| 70 | Output port 1 function selection | Set output port 1 function: 0: break output function 1: servo alarm output 2: position reach 3: speed reach 4: servo ready 5: back to zero complete 6: out of torque reach 7: Motor stall signal output | 0-7 |
| 71 | Output port2 function selection | Set Output 2 function: refer to Pn70 | 0-7 |
| 72 | Output port3 function selection | Set output 3 function: refer to Pn70 | 0-7 |
| 73 | Input analog selection | 0: -10V~10V voltage analog input, the positive and negative voltage determines the direction 1: 0V~10V voltage analog input, IO input port function is set to 22, 23, two channels of signal on and off determine different directions 2: -10V~0V voltage analog input, IO input port | 0-3 |

Chapter 4 parameter

| | | | |
|----|---|---|-------------|
| | | <p>function is set to 22, 23, two channels of signal on and off determine different directions</p> <p>3: 0V~10V voltage analog input, the IO input port function is set to 22, and the direction is determined by the on-off of a signal</p> <p>The above functions are in the analog speed and analog torque mode</p> <p>Can be used</p> | |
| 74 | Encoder type selection | <p>0; 15core 2500p normal encoder</p> <p>1; 9core line 2500p encoder</p> | 0~1 |
| 75 | Overload torque detect point | <p>Set the start torque value of the overload protection, rated percentage.</p> <p>When the present torque over this value, the system internal overload counter work, counter exceeds, system output overload alarm.</p> | 0-300% |
| 76 | Overload feature point torque | <p>Set overload point torque, This parameter and Pn77 make up the overload characteristic of the motor together. Set by the motor overload characteristic parameters. Note Pn76» Pn75</p> | 0-300% |
| 77 | Maximum overload time of the overload point | refer to Pn76 | 0-3000×10ms |
| 78 | Analog voltage filter coefficients | <p>Analog voltage filter coefficient, the larger the setting, the more stable the speed;</p> <p>Set PN78 < 10, and the filtering result is 1/Pn78;</p> <p>Set PN78 > 10, the filtering result is 1/Pn78² ;</p> <p>Set PN78=10, and the filtering result is the same as the original one. (V1020)</p> <p>The occasions <10 are occasions that require quick response. Applications greater than 10 are used as the input module voltage fluctuation is unstable, but the</p> | 0-1000 |

Chapter 4 parameter

| | | | |
|----|---|---|-----------------|
| | | motor speed is required to be stable, but there is no potential for fast response. In the case of speed regulation. | |
| 79 | Speed amplifier saturation time | When the continuous saturation time of the system's internal speed regulator exceeds this value, a speed saturation alarm is generated. Used to prevent mechanical jamming or other reasons caused the continuous current larger. | 0-3000×10 ms |
| 80 | Blocking speed | When the torque control, the motor is blocked after the value is lower than the set value. | 0~100 |
| 81 | Blocking confirmation time | Output blocking signal from the time when the lock is confirmed to the set value When the stall signal is enabled, the output port function is set to 7 to be effective. | 0.1ms |
| 82 | Input pulse filtering frequency | Set input pulse pass frequency, unit 1 means 1KHZ, set at 500, means the system maximum pass frequency is 500KHZ. | 1-10000 |
| 83 | Key period | The key response time | 2~200 |
| 84 | Reserved | Reserved | |
| 85 | Position difference removal method/pulse speed instruction filter | 0: no enable status, position deviation command pulse accumulation reset 1: no enable status, position deviation command pulse accumulation is not reset, count continuously. V519 version and product model with D version, this parameter function is pulse speed command filter; | 0-500 |
| 86 | Encoder line number | Encoder line number | 1-65536 |
| 87 | The encoder zero offset | The encoder zero division angle with U. | 1-65536 |
| 88 | Encoder current when reset | Set current value when the encoder reset, the percentage cannot too big to avoid motor | 0-300% |

Chapter 4 parameter

| | | overheating | |
|----|--|--|-----------------|
| 89 | Motor thermal overload torque detect point | Thermal overload use I*I*T calculate method | 10-300% |
| 90 | Motor thermal overload torque | Set this parameter bigger than Pn89 | 10-300% |
| 91 | Motor thermal overload time | Set thermal overload maximum time | 0-1000S |
| 92 | motor pole pairs | Set servo motor pole pairs, different manufacture and different model motor may with different pole pairs, cannot change this parameter randomly | 1~36 |
| 93 | Position gain attenuation coefficient | Set the position gain attenuation factor. | 1~100× 0.1A |
| 94 | Torque reached output signal ratio | Simulation control torque reaches the set value, torque reach output signals effectively. The value is the percentage of rated torque. | 0~300% |
| 95 | Force enable | 0: servo enable is controlled by external I/O 1: automatic servo enable when forced power on, do not need to connect external signal | 0~1 |
| 96 | Reserved | reserve | |
| 97 | Internal position 0 turn | Set internal position 0 precise position When the internal position control: target position | -65535~65535 |
| 98 | Internal position 0 pulse | determine by these 2 parameters, position 0= Pn97*10000+ Pn98 For example: Pn97=2 Pn98=1000 Indicates internal position movement =2*10000+1000=21000unit | 1~65535 |
| 99 | Speed at internal position 0 positioning | The speed of positioning to internal position 0 | 0~3000 r/min |

Chapter 4 parameter

| | | | |
|-----|--|---|-----------------|
| 100 | Internal position 1 turn | Set internal position 1 precise position | -65535~65535 |
| 101 | Internal position 1 pulse | Refer to Pn97 Pn98 | 1~65536 |
| 102 | Speed at internal position 1 positioning | The speed of positioning to internal position 1 | 0~3000 r/min |
| 103 | Internal position 2 turn | Set internal position 2 precise position | -65535~65535 |
| 104 | Internal position 2 pulse | Refer to Pn97 Pn98 | 1~65535 |
| 105 | Speed at internal position 2 positioning | The speed of positioning to internal position 2 | 0~3000 r/min |
| 106 | Internal position 3 turn | Set internal position 3 precise position | -65535~65535 |
| 107 | Internal position 3 pulse | Refer to Pn97 Pn98 | 1~65535 |
| 108 | Speed at internal position 3 positioning | The speed of positioning to internal position 3 | 0~3000 r/min |
| 109 | Acceleration of the internal position | Acceleration and deceleration time when internal positioning, the greater the value, the faster the acceleration. | 0~2000 |
| 110 | Input port 0 definition | Servo enable function, this input port cannot define other functions | 1 |
| 111 | Input port 1 definition | Used to define the function of the input port, for the convenience of customers The set value and functions as follows: 0: no definition, no function 1: servo enable 2: alarm clear 3: input pulse prohibited 4: position deviation counter reset | 0~23 |

Chapter 4 parameter

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|-----|-------------------------|---|------|
| | | <p>5: speed command input 0 6: speed command input 1 7: speed command input 2 8: Input point controls motor direction reversal 9: position gain switch 10: position gear ratio numerator switch 11: Zero speed clamp 12: torque command input 0 13: torque command input 1 14: positive drive prohibited 15: reverse drive prohibited 16: internal position command 0 17: internal position command 1 18: internal position running start 19: internal control method option 0 20: internal control method option 1 21: directional control functions 22: Voltage analog input inversion 23: Voltage analog input forward</p> <p>Note: V1014 version or above, internal/analog speed and pulse position switching; internal/analog torque and pulse position switching; after setting PN4 PN32, only need to set the switching input point function to 19</p> | |
| 112 | Input port 2 definition | Refer to Pn111 | 0-23 |
| 113 | Input port 3 definition | Refer to Pn111 | 0-23 |
| 114 | Input port 4 definition | Refer to Pn111 | 0-23 |
| 115 | Input port 5 definition | Refer to Pn111 | 0-23 |

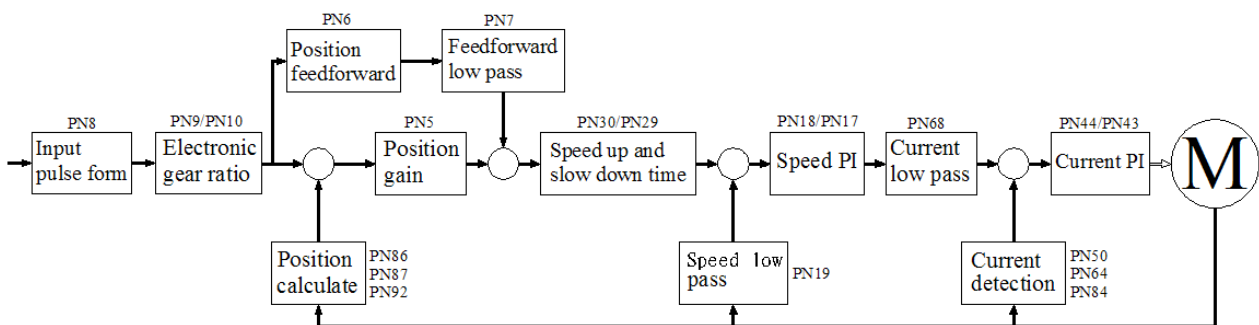
Chapter 4 parameter

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|-----|---|--|--------|
| 116 | Input port 6 definition | Refer to Pn111 | 0-23 |
| 117 | Communicate address | More than one drive communicate, set the station number | 0-127 |
| 118 | Communication rate | Communication rate 0: 4800 1: 9600 2: 19200 3: 38400 4: 57600 5: 115200 | 0-5 |
| 119 | Transport protocol | Transport protocol, use RTU mode 0: 8 O 1 (MODBUS, RTU) 1: 8 E 1 (MODBUS, RTU) 2: 8 N 2 Note: 8 means 8 bits data, E means 1 even O means 1 odd 1 means 1 end bit | 0-2 |
| 120 | position/speed integral saturation fault detect | 0: detect integral saturation fault 1: do not detect integral saturation fault | 0-1 |
| 121 | Input port is controlled section | Set I/O port as controlled object 0: controlled by external input terminal CN1 1: controlled by RS485 communication control | 0-1 |
| 122 | Simulation speed proportional gain | Certain input voltage, the bigger of the set values, the higher speed got. | 0-4096 |
| 123 | Simulation torque proportional gain | Certain input voltage, the bigger of the set values, the bigger of the torque got. | 0-4096 |

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| | | | |
|-----|--------------------------------|--|--------|
| 124 | Simulation zero | Set up to simulate zero voltage, adjust the symmetry of positive and negative direction of speed or torque. | 0-4096 |
| 125 | The speed limit of torque mode | Torque control mode to limit the speed | 0-4000 |
| 126 | High speed torque coefficient | Ascension of coefficient of high speed torque | 0-500 |
| 127 | Analog AD conversion method | <p>Analog control AD conversion mode:</p> <p>0: When the voltage is higher than the dead zone, start to accelerate and deceleration from 0.</p> <p>1: When the voltage is higher than the dead zone, the speed starts to jump to the speed corresponding to the dead zone voltage start acceleration and deceleration.</p> <p>2: When the voltage is lower than the dead zone, add position control and lock the current position.</p> | 0-2 |

4.2 parameter adjust diagram model



4.3 Description of Servo key parameters

As the default motor mating parameters has been optimized, therefore, the parameters (except electronic gear) do not need to adjust in most applications and can be used directly. But the actual mechanic is complex. If abnormality appear or needs high response when adjusting, then need to adjust the parameters to meet requirement. The adjustment principle is first current loop, second speed loop, last position loop.

The current loops do not need to adjust except for individual situation. The too fast speed response results in current shock and AL11 alarm. It can adjust PN64 to solve.

Speed loop: If high speed response needed, can increase PN17 or decrease PN18. However, the PN17 setting too large will cause vibrate. In the occasion of too big load inertia, if the load motor park unstably when decelerating and wag from side to side, need to increase PN18 to solve.

Position loop: If high location response needed, can increase PN5. Some occasions can increase PN6 to meet requirement. But PN5 PN6 is too large will cause vibrate. The setting precondition is to adjust PN5 prior, only in the short distance and high response occasion can use PN6.

electronic gear ratio: 1) if calculate from rotate speed angle, the below formula can be used

$$f \times (PN9/PN10) = 131072$$

in which f denotes the upper computer pulse, unit is KHZ/circle

If knows the pulse number from the upper computer and make the motor or load turn a circle, the gear ratio set value can be calculated with the above formula.

Chapter 4 parameter

2) calculate according to the position accuracy directly

$$(\text{lead/pulse equivalent}) \times (\text{PN9/PN10}) = 10000$$

For example: screw lead is 5mm, motor and screw lead connected directly, the motor rotates a circle, the load move 5mm. If the accuracy need 0.001mm, there are 5000 pulse needed for motor rotating a circle; that is: PN9=10, PN10=5

Pulse input form: support pulse with direction and double pulse (positive and negative pulse), set PN8

4.4 parameter adjusting steps in actual application

In the process of adjusting or application, if there is vibration, noise or cannot reach the control accuracy, can adjust system parameters and meet the control requirement as the following methods.

When the motor is in static locking state, if there is vibration or sharp noise, please decrease parameter Pn43; set this parameter as large as possible under the condition without vibration. The larger the parameter, the better the current tracking effect and the faster the motor response; but too large parameter results in vibration or noise.

(1) : speed control mode parameters adjustment

1) [speed proportion gain] (parameter Pn17) set value, as large as possible under the condition without vibration. Generally, the larger of the load inertia, the larger of the set value.

2) [speed integral time constant] (parameter Pn18) set value, try to set as small as possible according to the given condition. If the set value is too small, the response speed will be increased, but easy to vibration. Try to set the value as small as possible under the condition of no vibration. If the value is too large, when the load changed, the speed will change bigger.

(2) : position control mode parameter adjustment

1) according to the above method to set proper [speed proportion gain] and [speed integral time constant].

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2) [position feed forward gain] (parameter Pn6) set to 0%.

3) [position proportion gain] (parameter Pn5) set value, set as large as possible in the stable range. When the parameter is large, the position tracking will be good and hysteresis error is small, but easy to produce vibration when stop positioning. When the parameter is small, the system in stable state, but the position tracking become worse and hysteresis error become larger.

4) If position tracking requirement quite high, can increase Pn6 set value; but if it is too big, can lead to overshoot.

Chapter 5 operation and adjustment

5.1 special attention during debugging:

- 1) (large/medium-power model suffix are K8) servo drive Connect the three phase AC 220V power to input terminal. three phase connect L1、L2、L3, single phase connect L2、L1.
- 2) (small power model suffix is K7) servo drive single phase connect L、N.
- 3) motor power line U, V, W, PE, the sequence cannot reverse.
- 4) Drive connection as above. The wrong connection may cause burning, motor does not run, alarm etc. please check the line connection correct or not.

5.1.1 Power on sequence

- 1) When the power supply switch on, servo alarm signal output in 1S, after 1.5S signal output ready, after 10MS response to enable signal, less than 10MS motor excitation lock; waiting for running.

5. 2 Position control mode

- 1) Connect control circuit power and main circuit power, the display of the drive lighten. If there is alarm, please check the line connection.

- 2) Set below parameters:

| parameter No. | parameter name | definition | Set value |
|---------------|-----------------------------------|---|-----------|
| Pn4 | Control mode | 0: position mode 1:internal position mode | 0 |
| Pn8 | Position command pulse input mode | 0: Single pulse 1: double pulse 2: A/B orthogonal pulse | 0 |
| Pn9 | Gear ratio numerator | | 1 |
| Pn10 | Gear ratio denominator | | 1 |
| Pn95 | Servo enable | 0: external enable 1: force enable | 1 |

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3) Confirm there are no alarm and any abnormal situation, make enable servo (SON) ON, at this time, the motor motivated, in a state of zero velocity. If enable signal cannot connect wire, set Pn95 as 1 can make enable motor automatically.

4) Adjust the pulse frequency of the input signal; make the motor running according to command.



5.3 speed trial run mode

1) Connect control circuit power and main circuit power, the display of the drive lighten. If there is alarm, please check the line connection.

2) Set parameter as below:

| parameter No. | parameter name | definition | Set value |
|---------------|----------------|---|-----------|
| Pn4 | Control mode | 0: position mode 1: internal position mode 2: trial run | 2 |
| Pn95 | Servo enable | 0: external enable 1: force enable | 1 |

3) Confirm there are no alarm and any abnormal situation, make enable servo (SON) ON, at this time, the motor motivated, in a state of zero velocity. If enable signal cannot connect wire, set Pn95 as 1 can make enable motor automatically.

4) Through key operation enter F1 speed trial operation mode, speed trial operation prompt “S“, value unit is r/min, system in the speed trial mode, speed command provided by key, use   change speed command, the motor run based on the setting speed.

5.4 Jog operation



1) Connect control circuit power and main circuit power, the display of the drive lighten. If there is alarm, please check the line connection.

2) Set parameter as below:

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| parameter No. | parameter name | definition | Set value |
|---------------|----------------|---|-----------|
| Pn4 | Control mode | 0: position mode 1: internal position mode 2: trial run 3: jog run | 3 |
| Pn95 | Servo enable | 0: external enable 1: force enable | 1 |

3) Confirm there are no alarm and any abnormal situation, make enable servo (SON) ON, at this time, the motor motivated, in a state of zero velocity. If enable signal cannot connect wire, set Pn95 as 1 can make enable motor automatically.

4) Through key operation enter F2 speed trial operation mode, JOG run prompt “J”, value unit is r/min, system in the speed control mode, speed and direction determined by parameter Pn22, press  motor running according to the speed and direction which determined by Pn22, press  motor running opposite direction according to the given speed.

5.5 Internal position/speed/torque control mode

1) Connect control circuit power and main circuit power supply, the drive display light. If there is alarm, please check the line connection.

2) Set parameter as below:

| parameter No. | parameter name | definition | Set value |
|---------------|----------------|---|-----------|
| Pn4 | Control mode | 0: position mode 1: internal position mode | 1 |
| Pn95 | Servo enable | 0: external enable 1: force enable | 1 |
| Pn111 | IN1 definition | Define as position trigger | 18 |
| Pn112 | IN2 definition | Define as orientation start | 21 |
| Pn113 | IN3 definition | Define internal mode selection 0 | 19 |

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| | | | |
|-------|----------------|----------------------------------|----|
| Pn114 | IN4 definition | Define internal position 0 | 16 |
| Pn115 | IN5 definition | Define internal position 1 | 17 |
| Pn116 | IN6 definition | Define internal mode selection 1 | 20 |

3) Power off, re-up electricity, Confirm there are no alarm and any abnormal situation, make enable servo (SON) ON, at this time, the motor motivated, in a state of zero velocity. If enable signal cannot connect wire, set Pn95 as 1 can make enable motor automatically.

4) By switching the status of IN3 IN6 can switch under the mode position, speed and torque

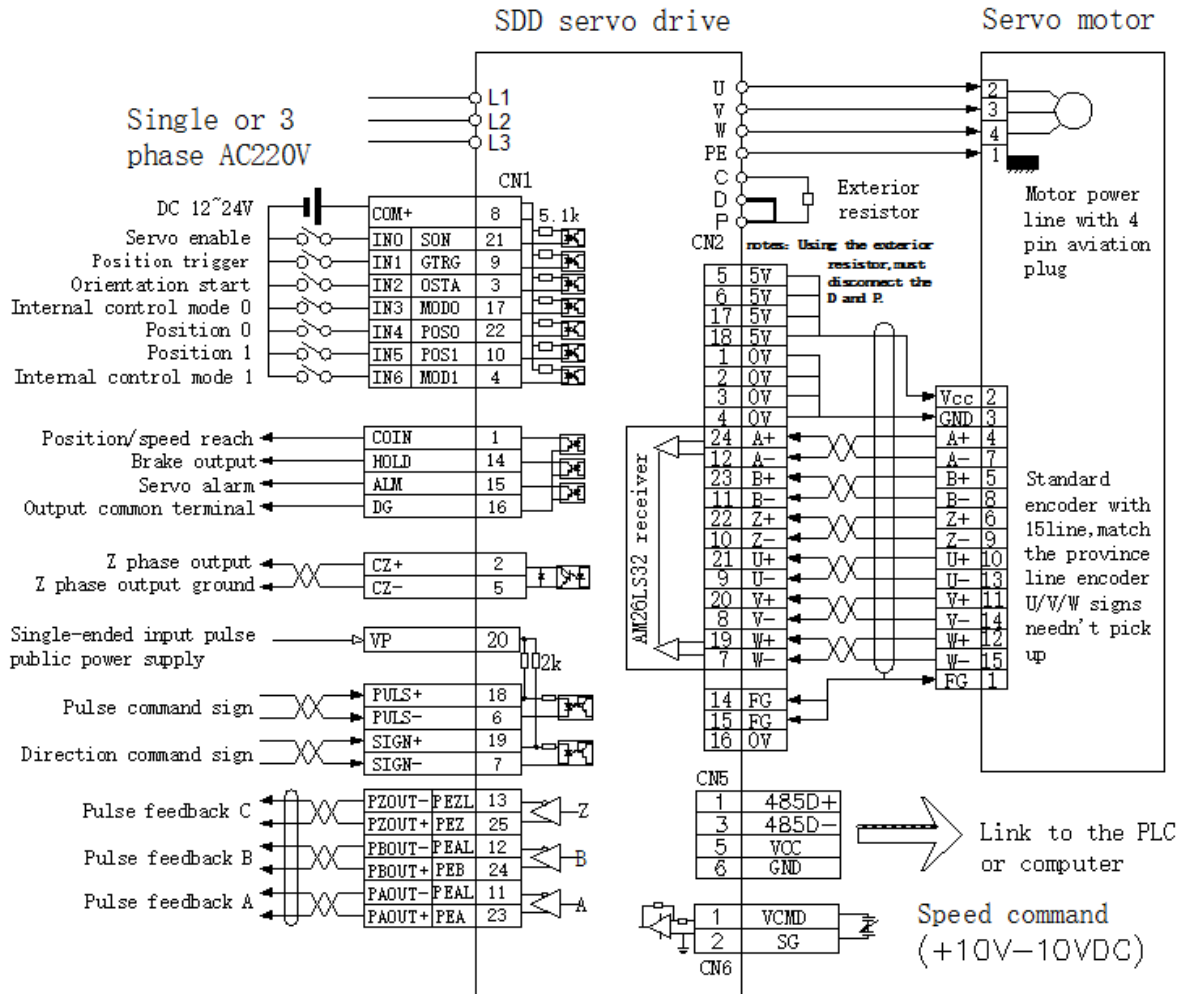
Corresponding method as follows:

| IN3. IN6 input signal status | Internal control mode |
|------------------------------|-----------------------|
| OFF OFF | position |
| ON OFF | speed |
| OFF ON | torque |

5) By switching the status of IN4 IN5 can realize 4 point positioning movement, the speed of 4 point positioning movement and accurate position set by Pn97-Pn109.

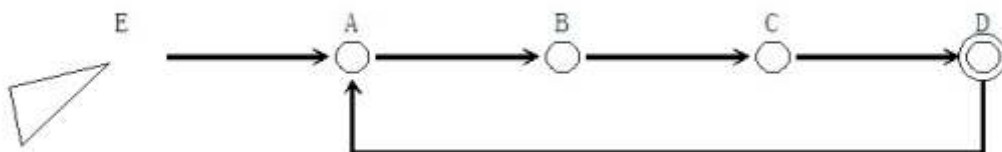
| IN4 IN5 input signal status | Internal control mode |
|-----------------------------|-----------------------|
| OFF OFF | Position A |
| ON OFF | Position B |
| OFF ON | Position C |
| ON ON | Position D |

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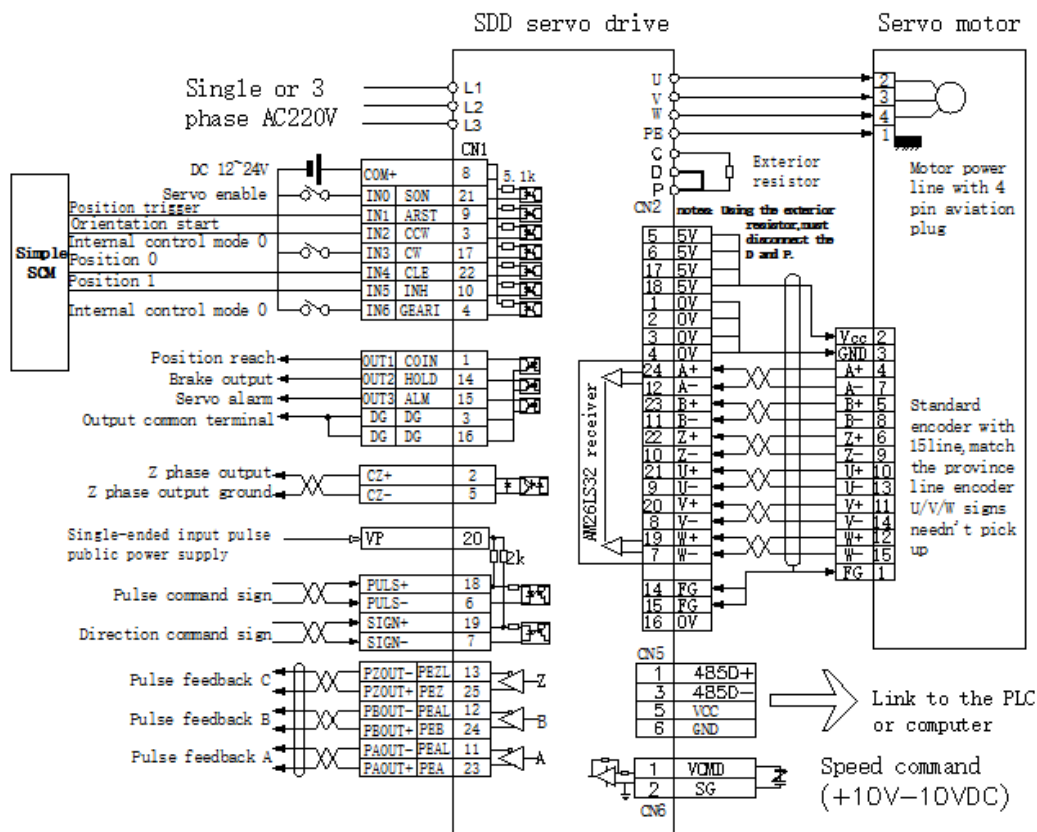


5.5.1 Internal position application example

Use internal position control to realize the belowing 4 point movement mode.



Chapter 5 operation and adjustment



Internal position control applications Electrical wiring diagram

The framework consists of one of the simplest microcontrollers and this servo system. The one-chip computer is used to send three control signals to the servo to trigger the servo's internal position control mode and the precise positioning of the operation. This example can be omitted high-end computer such as: PLC motion controller. At the same time, interference during pulse transmission is eliminated. More accurate servo positioning. In the case of repeated positioning within four points, it has a very economical cost and excellent control performance.

Control detailed description: IN3 IN6 signal connect with OV signal, it means choose internal position control mode. IN0 signal connect with OV signal, it means choose servo automatic enable after power on. Singlechip control process: system power on, the singlechip send a low level signal to servo IN2 signal, start servo and orientation back to the origin point A. carry out every time when starting up, it means wherever the origin position is, will be back to

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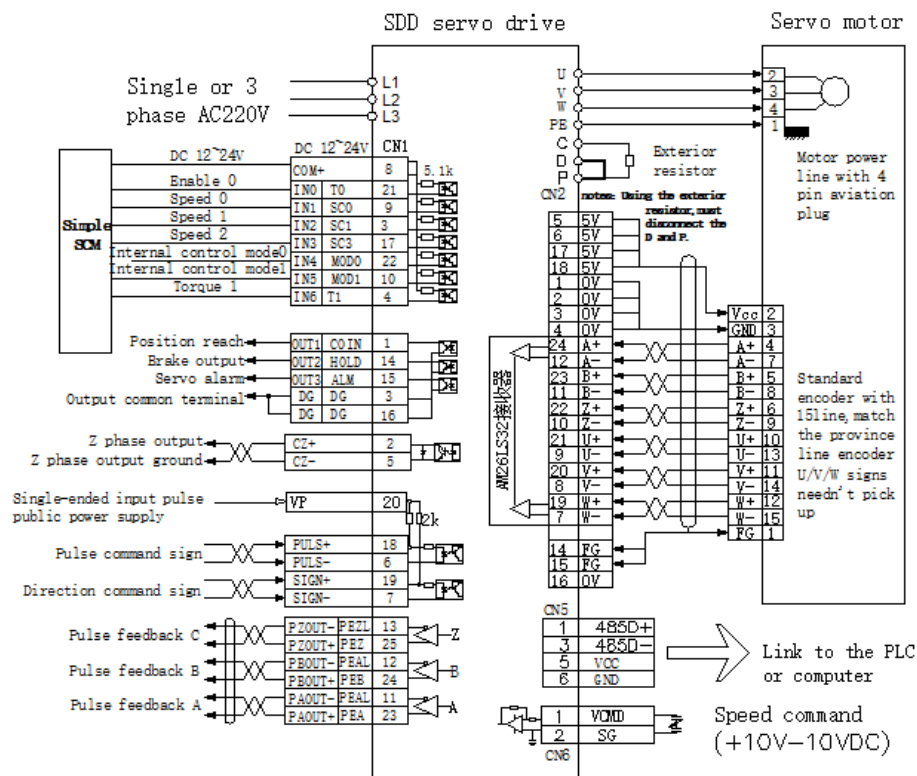
the fixed position before work. When servo position back to point A, the singlechip send two level signal to servo IN4 IN5 so as to control servo move from point A to point B, C, D and back to point A, complete a circulation. Every time start and trigger are done by IN2 signal. Rising edge effective.

This system has the characteristics of simple control, accurate positioning, and strong anti-interference ability. The run speed and precise position set by Pn97- Pn109. The parameters needed to be set as below:

| parameter No. | parameter name | definition | Set value |
|---------------|--|--|---|
| Pn4 | Control mode | 0: position mode 1:internal position mode | 1 |
| Pn111 | IN1 definition | Define as position trigger | 18 |
| Pn112 | IN2 definition | Define as orientation start | 21 |
| Pn113 | IN3 definition | Define internal mode selection 0 | 19 |
| Pn114 | IN4 definition | Define internal position 0 | 16 |
| Pn115 | IN5 definition | Define internal position 1 | 17 |
| Pn116 | IN6 definition | Define internal mode selection 1 | 20 |
| Pn 97 | Internal position 0 turns | | Set relevant parameters according to the actual ABCD four coordinates |
| Pn 98 | Internal position 0 pulse | | |
| Pn 99 | Internal position speed of 0 positioning | | |
| Pn 100 | Internal position 1 turns | | |
| Pn 101 | Internal position 1 pulse | | |
| Pn 102 | Internal position speed of 1 positioning | | |
| Pn 103 | Internal position 2 turns | | |
| Pn 104 | Internal position 2 pulse | | |
| Pn 105 | Internal position speed of 2 positioning | | |

| | | |
|--------|---|--|
| Pn 106 | Internal position 3 turns | |
| Pn 107 | Internal position 3 pulse | |
| Pn 108 | Internal position speed of 3 positioning | |
| Pn 109 | Acceleration and deceleration time constant of internal control | |

5.5.2 internal speed application example



Internal speed and torque mix control application electric wiring diagram

As shown in the figure, according to this example, 8 kinds of internal speed control and 2 types of internal torque control can be realized. And can be switched to each other. IN1 IN2 and IN3 are internal speed switch signals. Internal speed value set by parameters Pn33- Pn40. IN4 IN5 are internal speed and torque mode switch signals. Internal torque value set by parameters Pn45- Pn46.

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Servo relevant parameters set as below:

| parameter No. | parameter name | definition | Set value |
|---------------|----------------|---|---|
| Pn4 | Control mode | 0: position mode 1: internal position mode | 1 |
| Pn95 | Servo enable | 0: external enable 1: force enable | 1 |
| Pn110 | IN0 definition | Servo enable | 1 |
| Pn111 | IN1 definition | Define as speed 0 | 5 |
| Pn112 | IN2 definition | Define as speed 1 | 6 |
| Pn113 | IN3 definition | Define as speed 2 | 7 |
| Pn114 | IN4 definition | Define internal selection mode 0 | 19 |
| Pn115 | IN5 definition | Define internal selection mode 1 | 20 |
| Pn116 | IN6 definition | Define as moment of force 1 | 13 |
| Pn 33 | Speed 1 | | Set relevant parameters according to the actual run speed and moment of force |
| Pn 34 | Speed 2 | | |
| Pn 35 | Speed 3 | | |
| Pn 36 | Speed 4 | | |
| Pn 37 | Speed 5 | | |
| Pn 38 | Speed 6 | | |

| | | | |
|-------|-------------------|--|--------------|
| Pn 39 | Speed 7 | | requirements |
| Pn 40 | Speed 8 | | |
| Pn 45 | Internal torque 1 | | |
| Pn 46 | Internal torque 2 | | |

5.6 Servo features application

Servo start orientation function

when input port set as servo start orientation function, only set input signal as ON, the orientation function will start automatically(except torque control mode). Rotate direction of orientation is determined by Pn 26. precise position of orientation is determined by Pn 24 Pn 25. if set single turn orientation, the precise position is determined by Pn 24; if set multi turns orientation, the precise position is determined by $(Pn\ 25 * 131072) + Pn\ 24$. when input signal OFF, orientation function turnoff.

5.6.1 Position gear ratio switch function

When input port set as position gear ratio switch function, and input signal set as ON, the system use parameters of Pn 31 as present input pulse electronic gear. When input signal set as OFF, the system use the parameters of Pn9 as present input pulse electronic gear. This function mainly used to the occasions that dynamic electronic gear ratio needed.

5.6.2 Position gain switch function

When input port set as position gain switch function and input signal set as ON, the system use the parameters of Pn57 as present position loop control gain. When input signal set as OFF, the system use parameters of Pn5 as present position loop control gain. This function mainly used to the occasions that dynamic position gain needed.

5.6.3 Input pulse command filter

In the practice industry application sit, there is much interference, the input pulse command may caused the servo counting error because of the external

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interference. Therefore, affect the servo repositioning accuracy. Setting this filter can prevent the interference into the servo system. Improve the ability of anti-interference of the system.

The relationship of set value and the passable frequency as below:

| Pn 82 set value | The maximum passable pulse frequency |
|-----------------|--------------------------------------|
| 1000 | 1MHZ |
| 500 | 500KHZ |
| 250 | 250KHZ |
| 100 | 50KHZ |

5.7 Simulation speed control mode

Input analog voltage signal by the CN6, and set PN4 to be 7, Servo work in analog speed. We can control the speed of motor by adjust the size of voltage.

5.8 Simulation torque control mode

Input analog voltage single by the CN6, and set PN4 to be 8. Servo work in analog torque. We can control the torque of motor by adjust the size of voltage.

5.9 Position and simulation speed hybrid control mode

Input analog voltage single by CN6, and set PN4 to be 9, pulse command input from the control port. Servo work in position and analog speed hybrid control mode. Can be realized the switch between position and analog speed by I/O port control. Typical applications such as machine main axis.

5.10 Position and simulation torque hybrid control mode

Input analog voltage single by CN6, and set PN4 to be 10, pulse command input from the control port. Servo work in position and analog torque hybrid control mode. Can be realized the switch between position and analog torque by I/O port control. Typical applications such as: Injection molding machine, screw machine.

Chapter 7 Alarm and processing

If the servo with failure in use, the display will show: Al—xx, if there are various alarms, different alarm message will display by turns. For fault diagnosis, please operate according to the content of this chapter, get rid of the corresponding fault and can be put into use again.

7.1 Alarm list

| alarm code | alarm name | alarm reason |
|------------|------------------------------|---|
| AL-0 | normal | |
| AL-1 | overspeed | servo motor speed exceeds the set value |
| AL-2 | main circuit overvoltage | main circuit voltage too high |
| AL-3 | main circuit undervoltage | main circuit voltage too low |
| AL-4 | Position out of tolerance | motor with deviation over parameter Pn13 setting value |
| AL-6 | speed amplifier saturation | speed amplifier saturated a long time |
| AL-9 | encoder abnormal | encoder with break line or short circuit |
| AL-11 | excess current 1 | IPM module output current is too large |
| AL-12 | excess current 2 | DSP detection current is too large |
| AL-13 | excess load | servo output torque over the allowed value |
| AL-14 | braking abnormal | braking circuit abnormal |
| AL-15 | encoder count abnormal | encoder AB signal abnormal |
| AL-16 | motor thermal overload | Motor overload long time |
| AL-20 | EPROM error | servo inside EEPROM read-write abnormal |
| AL-24 | FPGA communication abnormal | FPGA communication abnormal |
| AL-32 | encoder UVW invalid | Encoder sign error |
| AL-45 | ADC error | ADC error |
| AL-46 | servo power sign abnormal | servo power sign abnormal |

7. 2 Alarm processing method

| alarm code | alarm name | reason | disposal method |
|------------|---------------------------|--|---|
| AL-1 | overspeed | input command pulse frequency is too high | Set input command pulse correct |
| | | input electronic gear ratio is too large | set Pn9 Pn10 parameter correct |
| | | encoder zero point error | ask the factory to reset the encoder zero |
| | | motor U、V、W lead connect wrong | confirm the wiring sequence |
| AL-2 | main circuit overvoltage | input L1 L2 L3 power voltage higher than AC260V | reduce power voltage |
| | | brake circuit capacity is not enough (Usually occur in the occasion that frequently and rapidly start and stop and the load inertia is large) | 1.prolong control system acceleration and deceleration time 2.contact manufacturer to increase braking resistance capacity |
| AL-3 | main circuit undervoltage | input L1 L2 L3 power voltage less than AC170V | find out the external reason of low voltage |
| | | servo protection action | replace a new servo drive |
| AL-4 | position error | operation, the motor does not turn any angle, immediately alarm | 1.confirm UVW wire phase sequence correct or not 2.confirm if the input pulse frequency is too high 3.pulse electronics gear setting it too large, set parameter Pn9 Pn10 correctly |
| | | alarm when rotating (input pulse abnormal) | confirm input pulse frequency and width |
| | | alarm when rotating (error detection range is too small) | set parameter Pn13 larger |

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| | | | |
|-------|----------------------------|---|--|
| | | alarm when rotating (position proportion gain is too small) | increase position gain Pn5 set value |
| | | alarm when rotating (lack of torque) | higher power servo motor |
| AL-6 | speed amplifier saturation | motor mechanically locked | check the load mechanical part |
| | | the load is too large | 1.decrease load, 2.change a higher power drive and motor |
| AL-9 | encoder failure | encoder wiring wrong or line break | check or change encoder wire |
| | | caused by interference | set Pn58 to 1 |
| | | the encoder cable is too long, lead to the encoder power voltage a little low | shorten the cable |
| AL-11 | Over-current 1 | grounding defective | grounding correctly |
| | | motor insulation damaged | replace a new motor |
| | | motor winding with short circuit | replace a new motor |
| | | servo motor parameters do not match | Correctly set motor ID number Pn1 |
| | | deceleration time is too short | increase the upper computer acceleration and deceleration time |
| | | current surge | 1.decrease parameter Pn43 Pn5 value 2.increase parameter Pn64 value |
| | | input pulse is not well-distributed | increase pulse smoothing parameter Pn15 value |
| | | servo protection action | replace a new servo drive |
| AL-12 | Over-current 2 | motor insulation damaged | replace a new motor |
| | | grounding defective | grounding correctly |
| | | servo protection action | Replace a new servo drive |

Chapter 7 Alarm and disposal

| | | | |
|-------|---------------------------|--|---|
| AL-13 | excess load | servo output torque over the allowed value | 1.mechanically locked or resistance is large, 2.motor type is not good, change to higher power drive and motor |
| AL-14 | braking abnormal | servo protection action | Increase the external braking unit |
| | | brake circuit capacity is not enough | 1.increase acceleration/deceleration time constant 2.replace a larger power servo and motor |
| | | main circuit power is too high | check the AC input power supply |
| AL-15 | encoder count abnormal | Encoder wiring error | check or replace the motor encoder wire |
| | | grounding defective | grounding correctly |
| | | servo motor defective | replace servo motor |
| AL-16 | motor thermal overload | motor over load long time | replace servo drive |
| AL-20 | EEPROM abnormal | servo inside EEPROM read-write abnormal | replace servo drive |
| AL-24 | FPGA error | FPGA communication error | replace servo drive |
| AL-32 | encoder UVW abnormal | Encoder cable or encoder damage | replace servo drive |
| AL-45 | ADC error | ADC error | replace servo drive |
| AL-46 | servo power sign abnormal | servo power sign abnormal | replace servo drive |

Special explanation: if the servo drive alarm, but after power on again, the alarm will disappear. Generally, it is considered that the servo drive outside parts with problem or the parameter adjusted improperly; please check the servo peripheral

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parts. For example: power voltage, controller, mechanical load, motor etc. if the peripheral parts without problem, please consult the manufacture about parameter adjustment.

If the alarm cannot clear after power on, please replace the servo drive and observe.

7.3 FAQ or exception handling in use

1、 No-load operation motor vibrate strongly or scream, load with noise or position error.

Handling method: confirm the servo drive PN 1 parameter whether match with the connected motor, set correct parameter based on table 7.2, then restore to factory value.

For example:

1) check table appendix A, and get the motor ID=1

2) operate drive, set PN0 to 0

3) set PN1 to motor ID number, that is PN1=1

4) operate drive and enter SN-DEF interface, press the ENTER key on the display panel for 2 seconds, when display DONE, indicates success.

5) turn off and power on again, done.

2、 The motor run positional accuracy and the required accuracy deviation is very large but regular

Handling method: Set position pulse electronic gear ratio correctly.

This servo system default 10000 pulses rotate a circle. If the upper computer requires 3000 pulses for motor to rotate a circle, need to set gear ratio to meet requirement.

It can be calculated by below format:

$$3000 * (PN9 / PN10) = 10000$$

$$\text{Get } PN9=10 \quad PN10=3$$

3、 drive input, output signal level reversed

1) Set parameter PN53 PN54 PN55 to set input/output suitable high level or low level so as to adapt to different input/output level requirement of the controller.

4、 upper computer pulse but motor not running

Make sure PN4=0, check UN-12 monitoring value, if there is digital shows that means the drive received pulse, it indicates the control signal connection without problem. Please refer to method 1 to clear fault. If display F 0.0 it indicates the drive do not received pulse. Please refer to method 2 to clear fault .UN-12 display unit is KHZ , like display F150, it indicates the present drive received pulse frequency is 150KHZ.

Method1:

Set below two parameters: PN95=1 PN4=3 in F2 model performs JOG function. If the motor can rotate, it indicates the motor, the motor power line, encoder wire connected correct, there is no problem.

Check CN1 signal if with INH signal or CLE signal with ON or not. It can be found by check UN-16.

If the motor can not run, please do following inspection

1) Check the drive with enable motor or not, and turn the motor shaft by hand. If it can not be rotated, indicates the motor enable locked. If it can be rotated, indicates there is no enable, please check if CN1 input enable signal correct connected or not. If the enable signal do not need to control by the upper

Chapter 7 Alarm and disposal

computer. CN1 input enable signal not connected, can set PN95=1, drive motor automatically enable locked.

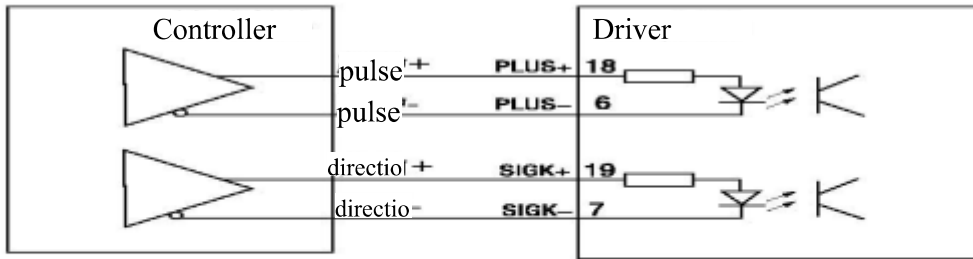
- 2) Check if the power cable which between drive and motor connected correctly or not, and the socket loose or not. Drive output terminal U V W PE and motor U V W PE whether corresponding. Power cable U V W PE must be connected correctly, can not change the sequence randomly.
- 3) Please contact the factory technical personnel.

Method 2:

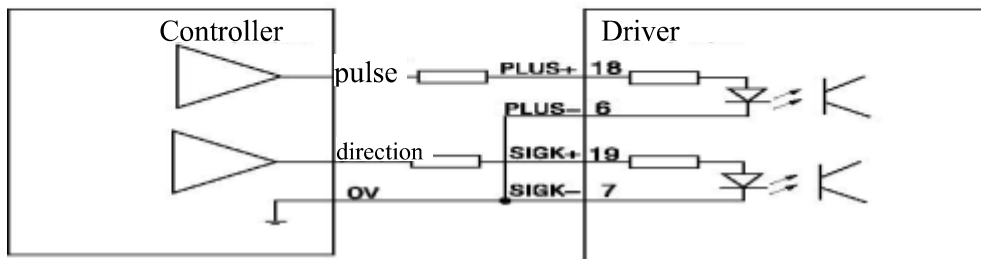
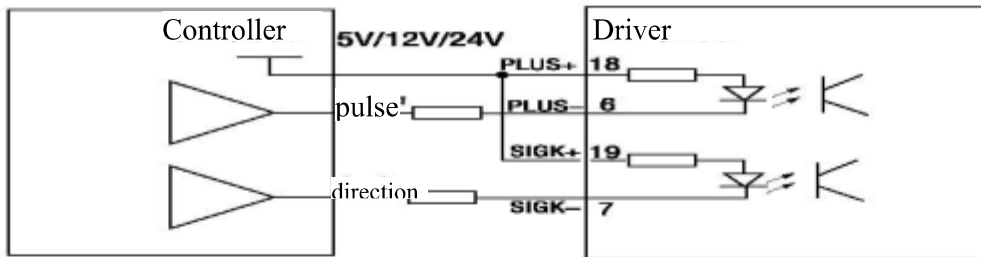
- 1) Check the pulse amplitude input to drive, the standard is 5V. If the pulse amplitude is 12V, must series 1K resistance; if the pulse amplitude is 24K, must series 2K resistance. The drive input circuit will be burned if not series resistance according to the requirements. Lead to the servo can not receive pulse.
- 2) Confirm the pulse connection mode is correct, the connection mode: differential connection mode and single end connection mode. Specific see below chart

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Typic application: numerical control system, motion



Typic application: PLC, SCM controller



5、 The motor can only turn to one direction

- 1) Confirm the input pulse type to drive, pulse and direction setting PN8=0; Double pulse setting PN8=1; A/B orthogonal pulse setting PN8=1, and confirm the drive model is SDxxx-D。
- 2) Observe UN-12 display state, upper computer send forward signal should display F xx. Reversal signal should display F - xx. If the upper computer send forward signal or reversal signal both display F xx or F - xx. Please check the direction signal SIGN from upper computer to drive.
- 3) Please contact the factory technical personnel.

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6、 high speed stop or from top to down does negative work, the drive display

AL—3

- 1) modify the upper computer deceleration time
- 2) reduce motor speed
- 3) small power drive access external braking resistance
- 4) medium high power drive please contact the factory technical personnel.

7、 there is no display when power on

- 1) Confirm power connecting wire and input power
- 2) Please contact the factory technical personnel.

8、 Power on drive display “。 。 。 。 。 。 。 ” or “888888”

- 1) the input power lack phase, check each phase power line
- 2) servo drive damaged by short circuit, and lead to servo drive damaged. The motor damage can be judged by rotate motor shaft under the no-load situation, rotate a circle, if the shaft is not smooth, can be concluded that the motor is damaged.

9、 Motor position is not accurate

- 1) Irregular, check motor connection mechanical part
- 2) Regular, monitor and analyse UN-02 UN-03 UN-04 UN-05 can get results
- 3) Screening interference, the signal wire use shield wire and grounding, add magnetic coiling. Motor cable change to shield wire. Electronic control system wiring again, make the strong and weak electricity line separately. Install filter etc.

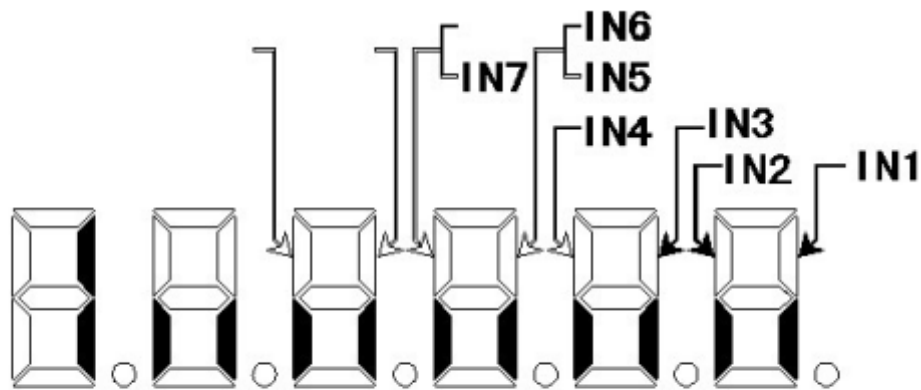
The effect of the servo monitoring menu in analysis and adjustment processes.

- 1) UN-01 motor speed observe the motor actual speed
- 2) UN-02 UN-03 The current position of the motor: used to observe the current position of the motor. It is represented by the number of pulses. For example, if the control takes a fixed trajectory, the displayed value should be the same when each

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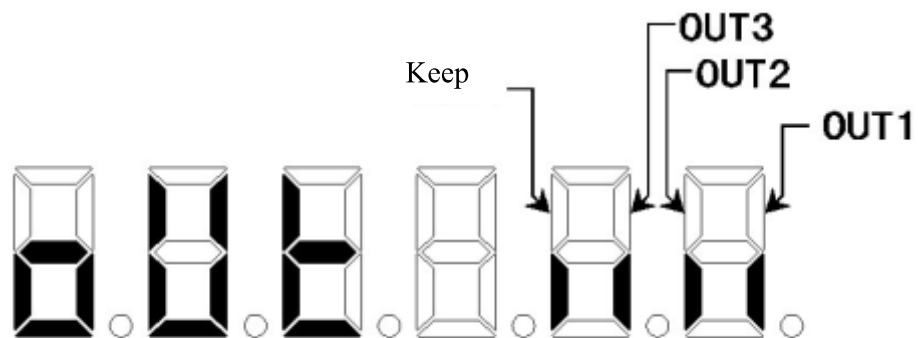
repeat operation is performed. Indicates accurate positioning each time.

- 3) UN-04 UN-05 Pulse command count, used to monitor whether the pulse from the host computer is accurate. For example, if the control traverses a fixed trajectory, the displayed value should be the same when it comes to the same position each time it repeats its operation, indicating that the pulse sent by the host computer is accurate.
- 4) UN-08 motor present torque, used to observe motor actual operate situation. If this value over 90 for a long time, means the current motor type is small.
- 5) UN-12 input pulse frequency, used to observe pulse frequency from upper computer and stability state
- 6) UN-17 input signal state, used to judge whether the input signal is normal
- 7) UN-18 output signal state, used to judge whether the output signal is normal
- 8) UN-23 input model voltage AD value, used to indicate the level of the input voltage, it's 2048 with no input.



Input terminal display

Light display ON, go out display OFF



Output terminal display

Light display ON, go out display OFF